ANALYSIS AND DESIGN OF STANDARD TELEROBOTIC CONTROL SOFTWARE

THESIS

Matthew L. June, Capt, USAF

AFIT/GCS/ENG/96D-12

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ANALYSIS AND DESIGN OF STANDARD TELETROBOTIC CONTROL SOFTWARE

THESIS

Presented to the Faculty of the School of Engineering of the Air Force Institute of Technology Air University
In Partial Fulfillment of the Requirements for the Degree of Master of Science in Computer Science

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Capt, USAF

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ABSTRACT

The Robotics and Automation Center for Excellence (RACE) at Kelly Air Force Base, Texas, has defined an open telerobotics control architecture. This architecture, called the Unified Telerobotic Architecture Project (UTAP), is a proposed standard for all Air Force telerobotic systems. Implementation of UTAP will reduce the cost of robotic applications by increasing software modularity, portability, and reusability. This thesis continued the effort to prove the feasibility of UTAP.

In December, 1995, 1st Lt Anchor implemented a portion of the UTAP specification on a PUMA robot. The UTAP-compliant controller exhibited some degradation in the system performance. However, the performance degradation was not fully measured. This thesis extended the measurements of Anchor’s implementation.

Additionally, a portion of the UTAP specification was implemented on an Adept 550 manipulator and the performance effects were measured. The implementation included portions of the generic, robot/axis servo control, tool control, sensor control, programmable IO, subsystem task level control, task description and supervision, parent task program sequencer, task program sequencer, and object knowledge modules.

Performance measurements of the Adept implementation indicated that, although performance was adversely affected, the degradation was caused by the interface between the UTAP-compliant application and the non-UTAP-compliant operating system. There was little difference between the complaint and non-compliant applications.

Successful implementation of the UTAP specification on the PUMA and Adept manipulators proves that UTAP is a feasible telerobotic architecture. However, further
study of the specification is recommended. Specifically, the development of a UTAP-compliant operating system should be continued.
ANALYSIS AND DESIGN OF STANDARD TELEROBOTIC
CONTROL SOFTWARE

I. Introduction

The Robot Industries Association (RIA) defines a robot as “a reprogrammable, multfunctional manipulator designed to move material, parts, tools or specialized devices through variable programmed motions for the performance of a variety of tasks” [12]. A telerobotic system couples the robot’s abilities with a human operator’s abilities to think and react. There are three basic types of telerobotic systems based on the amount and type of interaction between the robot and the human. The first type of telerobotic system is “operator controlled.” With systems of this type, the operator has complete, real-time control of the robot’s movements. The second type is “operator supervised.” In this case, the robot obeys a control program and the operator does not have direct, real-time control. However, the operator can stop the robot or change the program as required. The final type is “shared control.” This is a combination of the other types. The operator exerts some real-time control over the robot while the control program manages the remaining aspects of the task [12].

In each of these systems, the operator provides some sort of input to the system and receives some type of output or feedback. A telerobotic control architecture defines the methodology behind providing the input and receiving the output. Currently, each telerobotic system has its own control architecture.
Because each system has its own unique control architecture, it is very difficult to port a task, or function, from one system to operate on another system. Therefore, there is very little reuse of software in the telerobotic field. This results in expensive one-of-a-kind installations. To lower costs and improve efficiency and productivity, telerobotic systems must be modular, portable, and easily reconfigurable. A standard telerobotic control architecture would provide a framework for developing systems that meet these objectives.

Because the Air Force desires the use of telerobotic systems for many critical tasks including aircraft painting and paint stripping, surface cleaning, and sealing and descaling of fuel tanks, the Robotics and Automation Center for Excellence (RACE) at Kelly Air Force Base, Texas, has defined an open telerobotics control architecture. This architecture, called the Unified Telerobotic Architecture Project (UTAP), is a proposed standard for all Air Force telerobotic systems. UTAP supports a modular development that ensures plug-and-play functionality. The standardized interface and modularity of UTAP mean that a telerobot can be switched from one task to another simply by switching modules. The modularity of UTAP also increases the potential reuse of modules on new tasks.

1.1. Problem

Before I conducted my research, UTAP had only been implemented on one Air Force system. This was accomplished under a previous AFIT thesis effort conducted by 1st Lt Kevin Anchor. He implemented a portion of UTAP on the PUMA robot in the
AFIT Robotics Laboratory [3]. However, the effects of his implementation on the performance of the robot were not completely measured.

In addition to measuring the performance of Anchor’s UTAP implementation, other systems needed to be retrofitted to the UTAP specification before UTAP could be considered feasible. Therefore, I implemented the UTAP specification on the Adept 550 robot in the robotics laboratory and measured the performance effects of the implementation.

1.2. Summary of Current Knowledge

Anchor’s thesis work involved implementing the UTAP specification on the PUMA 560 manipulator using the Chimera 3.2 real-time operating system. Anchor measured the performance effects of UTAP by commanding the robot through a series of motions at various speeds and recording the difference between the commanded and the actual positions. Measurements were taken on the system both before and after implementing UTAP. He then plotted the amount of error between commanded and actual robot position and performed statistical analysis on the data [3]. While this method gave a general idea of the performance issues associated with his implementation, several additional steps needed to be completed before a thorough understanding was obtained. These steps included controller gain tuning and modifying the trajectory generation module to allow step response testing. They are defined in later sections.

In addition to Anchor’s work, the Advanced Cybernetics Group, Inc. (ACG) developed some applications that embodied some of the concepts of the information
module portion of the UTAP specification [5]. ACG’s code provided a foundation for the
implementation of UTAP on the Adept 550.

1.3. Scope
This research effort was divided into two separate tasks; performance testing of Anchor’s
UTAP implementation and implementation of UTAP on the Adept robot. The
performance testing of Anchor’s UTAP implementation was conducted first. I only
tested the UTAP functionality implemented by Anchor and did not implement any further
UTAP functionality on the PUMA manipulator. Second, portions of the following
modules were implemented on the Adept 550 manipulator using the V+ operating
system:

- generic
- robot/axis servo control
- tool control
- sensor control
- programmable IO
- subsystem task level control
- task description and supervision
- parent task program sequencer
- task program sequencer
- object knowledge

This task also included performance testing.

1.4. Approach/Methodology
As stated earlier, my research consisted of two major tasks; performance testing
of Anchor’s UTAP implementation and implementation of UTAP on the Adept system.

1.4.1 Performance Testing of Anchor’s UTAP Implementation

Performance testing was conducted using the following general steps:

a. Using the non-UTAP-compliant controller, command the robot through a
series of motions at varying speeds while recording the commanded and actual
joint position values.

b. Tune the controller gains for optimal performance of Anchor’s UTAP
implementation.
c. Using Anchor’s UTAP-compliant controller, command the robot through a series of motions at varying speeds while recording the commanded and actual joint position values.

d. Modify the Chimera trajectory generation module to allow step response testing.

e. Using Anchor’s UTAP-compliant architecture and the modified trajectory generation module, command the robot to perform a step motion while recording the commanded and actual joint position values.

f. Analyze the data.

### I.4.2 Implementation of UTAP on the Adept Manipulator

Implementation of the UTAP specification on the Adept manipulator was conducted using the following steps:

a. Determine an appropriate application to convert to UTAP compliance.

b. Analyze the application to determine which program statements require modification.

c. Convert the program statements to UTAP messages.

d. Develop an interface that implements the UTAP messages in the V+ programming language.

e. Develop a test routine that measures the running time of the application.

f. Measure the performance of the non-UTAP and UTAP-compliant versions of the application by executing the test routine with the robot speed set to 25, 50, 75, and 100 percent of maximum.

g. Collect metrics on source lines of code and number of procedure calls for both versions of the application.

h. Analyze the data.
1.5. Materials and Equipment

All necessary equipment and software were available in the AFIT Robotics Laboratory. The software and equipment required to test Anchor’s UTAP implementation included the following:

- PUMA 560 manipulator
- VMEbus hardware associated with the PUMA
- Sun Sparc 2 workstation
- Chimera 3.2 real-time operating system
- SunOS 4.1.3 operating system
- UTAP software developed by Anchor

The software and equipment required to implement the UTAP specification on the Adept robot included the following:

- Adept 550 manipulator with MV-19 VME controller
- VMEbus hardware associated with the Adept
- V+ 11.1 operating system and programming environment
- ACG UTAP information module V+ code

1.6. Thesis Organization

This thesis report is divided into five chapters. Chapter I is an introduction to the topic and contains background information. A literature review of current robotic architecture work and associated information is presented in Chapter II. Chapter III contains the methods and procedures used to measure the performance of Anchor’s UTAP implementation, as well as an evaluation of the research results. Chapter IV describes the implementation of UTAP on the Adept system and presents an analysis of the results. Finally, Chapter V contains the conclusions drawn from this research and makes recommendations for the UTAP specification and future research.
II. Literature Review

In this literature review, I present an initial examination of the current work in the field of robotic architectures. I have limited the examinations to work which supports the Air Force’s need for an open telerobotic architectural standard. The review describes the Unified Telerobotic Architecture Project (UTAP) specification, which is being considered by the RACE to become the Air Force architecture standard for robotic systems. This review also motivates the need for my thesis research, which is to investigate the complexity of converting a telerobotic system to be compliant with the UTAP specification and to measure the performance of the converted system.

The review begins with the UTAP specification. The specification is summarized and its purpose and goals are presented. Then, it discusses research covered by a previous AFIT thesis on the UTAP specification and describes the remaining research. This is followed by an investigation of a commercial application of the UTAP specification. Finally, the review presents a comparison of the UTAP effort to other standardization efforts.

II.1. Unified Telerobotic Architecture Project Specification

The Unified Telerobotic Architecture Project is described in [9]. The UTAP specification describes a standard interface environment that promotes the development of modular, portable, and reusable robotic applications. To help avoid point solutions to specific applications, the UTAP architecture accommodates different types of robotic manipulators with different degrees of freedom. It also accommodates different part
The UTAP architecture is composed of hardware and software modules. Each module has defined inputs, outputs, and responsibilities. All data inside a module is self-contained and hidden from other modules. The Object Knowledge module stores data that is needed by multiple modules. Data and control flow are passed between modules through the use of pre-defined messages. Thus, the UTAP specification defines the modules and interfaces that make up the system.

Figure II.1. UTAP Architecture [3]
Figure II.1 shows the overall UTAP architectural block diagram. Each box represents a module and each line represents a communication channel. Arrows on the line show which direction communication can occur. Communication can only occur between connected modules.

For any particular application, not all of the modules need to exist. Likewise, some modules may have multiple instances. The local and remote controllers each have a configuration file that specifies which modules compose the system. For example, if the Object Modeling module is not needed, then the corresponding configuration file would indicate the absence of that module from the system. Furthermore, not all modules will accommodate every interface message. Therefore, each module maintains a service profile that describes the set of UTAP messages and data posting capabilities supported by the module.

The UTAP specification provides a foundation for a standard telerobotic architecture. However, there are some minor naming inconsistencies in the specification. For example, the UTAP specification gives three different names for the SGD module; “Status Graphics and Displays”, “Status and Graphical Display”, and “Status Graphics Displays.” It is even abbreviated as SDG in some places. The different names can imply different functions for the module. Inconsistencies of this nature also appear in other areas of the specification. For example, twenty different modules are named throughout the document. However, messages are only defined for seventeen modules. Additionally, some areas of the specification require more explanation or clarification. The UTAP messages are an example of this. The meaning and purpose behind each
message should be described. Without defining the meaning of each message, an individual implementing a UTAP-compliant application may not know which message to use to accomplish a particular task. Chapter VI further addresses these issues with the UTAP specification and presents my recommendations.

II.2. Previous AFIT Research

Anchor’s research [3] represents the first implementation of UTAP. His research primarily involved redesigning the AFIT Robotics and Automation Applications Group (RAAG) Lab B PUMA manipulator to be compliant with the UTAP architecture. Anchor’s thesis shows the UTAP specification to be implementable. However, if the underlying operating system does not support generic message passing, an interface layer must be implemented to access operating system functions.

Anchor’s UTAP-compliant controller implemented portions of the robot servo control, object knowledge, and operator interface modules of the specification (see Figure II.1). The controller performed adequately; although, there was degradation in the performance as evidenced by increased position error during trajectories. Additionally, Anchor pointed out the “spikiness” of the error plots of the UTAP controller when compared to the plots of the non-UTAP controller (see Figure III.3). He indicated that the “spikiness” was due to the lack of controller gain tuning. This is further addressed in the next chapters.

Anchor conducted his performance measurements without tuning the gains of his UTAP-compliant controller. Gain tuning will optimize the performance of the controller and decrease the amount of error. Furthermore, Anchor obtained his measurements by
using the Chimera trajectory generation module to move the robot in a step response and
the Chimera track module to record the commanded and actual joint angles. The
trajectory generation module computes the trajectory needed to move the robot from the
current position to the commanded position. It accomplishes this by dividing the
difference between the positions into very small increments and moving the robot
through each increment. Error compensation takes place at each increment. Thus, the
trajectory generation module does not provide a true step response motion.

The motion command of the trajectory generation module hides some of the
performance degradation of the UTAP-compliant controller. To avoid this, the trajectory
generation module must be modified to command the robot directly from the initial
position to the final position without the incremental movement. This is a true step
response and provides more accurate data on the performance of the UTAP-compliant
controller.

11.3. Commercial Work Associated with UTAP

Using the UTAP specification as a guide, Advanced Cybernetics Group, Inc.
(ACG) has implemented several robotic application building blocks that are compatible
with the UTAP philosophy [5]. ACG built their product on the commercially available
Adept V+ robotic programming language. In addition to describing the application’s
implementation, ACG gives examples of commercial and Air Force sites that are using
their product to perform tasks with telerobotic systems.

ACG begins to show that the philosophy of the UTAP document is sound and
commercially available products can be used to implement the UTAP specification.
ACG's design of their building blocks conforms to the UTAP goals of modularity and reusability. They have also adopted a module naming convention similar to the UTAP message naming convention. However, the ACG work focuses on the sensor control portion of the UTAP specification. The remaining portions of UTAP, such as task level control, programmable IO, etc., are not implemented.

ACG has shown that a commercially-available product can be used to implement modules that are generic enough to be used in several different robotic applications. This confirmed that modularity and reusability are obtainable goals. However, ACG did not closely match their naming conventions and message parameters with the UTAP specification. This, coupled with the fact that ACG focused primarily on the sensor control module while I intended to implement a broader portion of the UTAP specification, prevented me from simply building upon their V+ code as I had originally intended.

11.4. Other Standardization Efforts

To understand the amount of time and effort required to develop a standard with the amount of complexity inherent in a telerobotic architecture, we can compare the UTAP effort to the effort expended developing the Ada programming language. The benefits of a standardized architecture can be seen by looking at the benefits obtained through the Portable Operating System Interface (POSIX) standard.

11.4.1. Ada

In 1974, the Department of Defense (DoD) initiated the common high order language program to define the requirements for a common language for programming
large scale and real-time systems [6]. After extensive reviews by the Services, industrial organizations, universities, and foreign military departments, the final requirements were published in the Steelman specification. This phase in the development of Ada lasted for four years.

Implementation of the requirements began in 1978 and culminated in 1983 with the publication of ANSI/MIL-STD-1815A. This five-year development consisted of three phases. The design team received numerous evaluation reports at the end of the first and second phases. During the third phase, they received nine hundred language issue reports and test and evaluation reports from fifteen different countries. The design team also conducted several intense week-long design reviews attended by dozens of industry experts.

From the above paragraphs we see that the Ada project took nine years and thousands of man-hours to reach the first release. In contrast, UTAP began in 1992 as an engineering study of Air Logistic Center (ALC) remanufacturing processes conducted by NASA's Jet Propulsion Laboratory (JPL) [11] and the UTAP working group consisted of ten individuals. Certainly, UTAP does not have the same publicity that Ada has; and it definitely does not have the same support and funding as Ada. Therefore, we cannot expect to apply the same amount of effort to UTAP. On the other hand, the comparison shows that exceptional progress has already been made on the UTAP specification considering the level of effort expended. Likewise, the comparison shows that it is reasonable to expect that a considerable amount of work remains.
II.4.2. Portable Operating System Interface (POSIX)

The POSIX System Interface Standard is the central open system standard related to the historical UNIX timesharing system and is an application program interface standard for basic operating system functions [10]. The POSIX working group had the following four main goals when developing the standard:

1. Promote application source code portability
2. Specify an interface, rather than an implementation
3. Consider all major historical implementations
4. Keep the interface minimal

By achieving these goals, the working group has ensured that applications developed for POSIX-compliant systems can be ported to new POSIX-compliant systems with minimal effort. This saves time and money by providing users with the capability to upgrade and expand their systems. By specifying the interface but not the implementation, the working group ensured that users can take advantage of new technology. In other words, as long as the interface remains the same, an old implementation can be replaced by a better one.

When examining the goals of the UTAP specification, we find a direct correspondence to the goals of the POSIX working group. It is reasonable to expect UTAP will benefit from the same advantages as those experienced by POSIX compliant systems, provided the UTAP goals are obtained.

II.5. Summary

A standard interface environment for telerobotic applications will reduce the cost of telerobotic systems by increasing module reuse and portability and by decreasing module development time and costs. The UTAP specification defines a standard that
attempts to meet these goals. Anchor's research showed the feasibility of implementing the UTAP specification on one particular platform. However, there are still performance issues to be investigated and UTAP must be implemented and tested on additional platforms. ACG's work proves that robotic applications can be developed by re-using generic modules written in the V+ language. Finally, by comparing the UTAP effort to other standardization efforts, we see that the process of developing and implementing a large standard of this nature is difficult and time consuming but the rewards are worth the effort.
III. Performance Measurement of Anchor's UTAP Implementation

This chapter describes the methodology behind the performance measurement of Anchor’s UTAP implementation. It presents the steps followed to accomplish the measurement and justifies the choices made while conducting the measurement. It then provides an analysis of the data obtained from the measurements.

III.1. Methodology

This section is divided into three parts. The first part contains preliminary information about Chimera and Anchor’s UTAP controller that is needed to understand the methods. The second part contains the steps taken to prepare for the performance measurement. Finally, the third part explains the actual performance measurement.

III.1.1. Preliminary Information

Anchor implemented his UTAP-compliant controller under the Chimera Real-Time Operating System (OS). Chimera provides the interface between the operator and the manipulator hardware. It converts the program commands (movement commands etc.) to digital signals and sends them to the manipulator hardware. Chimera supports application development in the C and C++ programming languages. It is the Chimera OS that provides the functions to use and program the manipulator.

Throughout his research, Anchor used several predefined manipulator positions. To maintain continuity with his performance tests, I used the same positions. Table III.1 lists the relevant positions. The values are in radians and are measured from the baseframe of the respective joint.
In many of the steps described below, the term “spawned” is used. Under Chimera, spawning a module loads the module into memory, but does not begin execution of the module. The “on” command begins the execution of the module, or activates it. It is through the “on” command that operator-input parameters, if required, are passed to the module.

<table>
<thead>
<tr>
<th>Position Name</th>
<th>Joint 1</th>
<th>Joint 2</th>
<th>Joint 3</th>
<th>Joint 4</th>
<th>Joint 5</th>
<th>Joint 6</th>
</tr>
</thead>
<tbody>
<tr>
<td>Home</td>
<td>0.0</td>
<td>-1.5708</td>
<td>1.5708</td>
<td>0.0</td>
<td>0.0</td>
<td>0.0</td>
</tr>
<tr>
<td>Data Initial</td>
<td>0.0</td>
<td>-2.36</td>
<td>2.36</td>
<td>0.0</td>
<td>0.0</td>
<td>0.0</td>
</tr>
<tr>
<td>Data Final</td>
<td>1.5708</td>
<td>-1.5708</td>
<td>0.524</td>
<td>0.0</td>
<td>0.0</td>
<td>0.0</td>
</tr>
</tbody>
</table>

Table III.1. Predefined Positions (radians)

Several Chimera modules are also mentioned in this chapter. What follows is a brief description of their purpose and the results of their execution.

The Chimera **puma_pidg** module is the proportional integral derivative (PID) controller module used on the AFIT PUMA 560 manipulator under the Chimera operating system. Anchor modeled his UTAP-compliant controller after the **puma_pidg** module and the Chimera gravity compensation (**grav_comp**) module.

The Chimera **trjgen** module is the trajectory generator and accepts as input the desired joint angles (measured in radians from the baseframe of each joint) and a movement duration (measured in seconds). From these values, the module computes a trajectory (as described in section II.2.) that will move the manipulator to the desired joint angles.

The Chimera **track** module records the manipulator’s commanded and actual joint angles during movement. When the track module is activated, it records the data at a rate of fifty samples per second. The data is written to a file specified at activation.
Anchor's int_RSC module was the interface module between his UTAP-compliant controller (the UTAP_RSC module) and the Chimera operating system functions. Figure III.1 shows the relationship between Anchor's interface and UTAP modules and the Chimera OS modules. In Anchor's modules, RSC stands for Robot Servo Control.

To start the UTAP-compliant controller, the user spawns and activates the int_RSC module. The int_RSC module accesses the UTAP_RSC functions that include the PID controller and gravity compensation functionality.

III.1.2. Preparatory Steps

Before I could begin the performance measurements, I needed to tune the gains of Anchor's controller and establish a performance baseline. These steps are described and justified in the next two sections.
III.1.2.1. Gain Tuning

To accurately measure the performance limits of a system, the system must be operating at its optimal level. In section IV.3 of [3], Anchor suggested that the performance of his UTAP-compliant system could be improved by controller gain tuning. Therefore, his system required gain tuning before the performance could be measured.

In [7], Klafter describes the basic steps required to gain tune a PID controller as follows:

1. With $K_i = K_d = 0$, adjust $K_p$ until the system step response is either critically (or slightly under-) damped.
2. For the value of $K_p$ just found, increase $K_i$ until the steady-state error is either zero or has reached an "acceptable" value. (Normally, $K_i > K_p$.)
3. Increase $K_d$ until the system step response is again either critically or slightly underdamped.

Each joint of the manipulator has its own values for $K_p$, $K_i$, and $K_d$ and must be tuned separately. Under Anchor’s UTAP implementation, all three values for each of the six joints are stored in the configuration file named int_rsc.rmod.

III.1.2.1.1. Joint One Gain Tuning

Joint one was gain tuned using Klafter’s procedure without deviation. I determined when the joint was critically damped, slightly under-damped, or had an acceptable steady-state error by plotting the joint position data at each iteration of the procedure. The Chimera track module was used to record the data while the joint moved through a 90.0 degree arc.

III.1.2.1.2. Results from Gain Tuning Joint One

During the tuning of joint one, I quickly learned that it was going to be a very time consuming process. Each adjustment of one of the values meant that each module
must be unloaded, the value changed, the modules re-spawned, the movement started, the
data extracted from the trjgen output, the data plotted, and the next change determined.
Occasionally, the system would give an error message stating that it was not calibrated.
When this occurred, I had to kill all the active modules, calibrate the manipulator, and re-
load all the modules. Since this was a time consuming process, I decided to combine
steps and save time.

III.1.2.1.3. Joint Two Gain Tuning

For joint two, I began at the home position with the original gains. A -90.0 degree
movement was commanded and the position data from the track module was plotted.
Then, based on the results from joint one, the movement was commanded with an
increased $K_p$ and again with a decreased $K_p$, leaving $K_i$ and $K_d$ at the original values. By
analyzing the resulting plots of these three movements, it could be determined that joint
two was already critically damped with the original $K_p$ value.

Next, the $K_i$ value was slightly increased and the $K_d$ value was slightly decreased
from the original values. This decision was also based on the results of tuning joint one.
After commanding the -90.0 degree movement, the results were analyzed. The trajectory
was slightly improved. I continued this process until I was satisfied with the joint two
trajectory. The modified procedure saved two days.

III.1.2.1.4. Joint Three Through Six Gain Tuning

The joint two procedure was used on joints three through six with similar time
 savings. Table III.2 shows the gain values before and after tuning. Appendix D contains
the trajectory plots for all six joints.
III.1.2.2. Obtaining a Baseline

Besides tuning the controller gains, another step was required. Before the performance of Anchor’s UTAP implementation could be measured, a performance baseline of the original system had to be obtained. With this baseline, a comparison could be made between the original system and Anchor’s UTAP-compliant system. For the comparison to be valid, the baseline had to be obtained by executing the Chimera functions that matched the functions implemented in the UTAP controller. Anchor modeled his UTAP system after the Chimera `puma_pidg` and `grav_comp` modules. Therefore, the baseline was obtained using those Chimera modules.

The steps used to obtain the baseline were the same steps Anchor used to obtain his performance measurements. Additionally, data was collected from the same three movement durations used by Anchor. The fast movement lasted 1.5 seconds, the nominal movement lasted 3 seconds, and the slow movement lasted 5 seconds. The measurements were taken during the movement of the manipulator from the data initial position to the data final position. These positions were the same as those used by Anchor and are shown in Table III.1. For each of the three motion durations, I activated the `puma_pidg`,

<table>
<thead>
<tr>
<th>Joint</th>
<th>(K_p) Before</th>
<th>(K_p) After</th>
<th>(K_i) Before</th>
<th>(K_i) After</th>
<th>(K_d) Before</th>
<th>(K_d) After</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>4000</td>
<td>4000</td>
<td>5</td>
<td>20</td>
<td>80</td>
<td>20</td>
</tr>
<tr>
<td>2</td>
<td>11000</td>
<td>11000</td>
<td>5</td>
<td>20</td>
<td>114</td>
<td>10</td>
</tr>
<tr>
<td>3</td>
<td>3000</td>
<td>3000</td>
<td>5</td>
<td>20</td>
<td>25</td>
<td>25</td>
</tr>
<tr>
<td>4</td>
<td>500</td>
<td>500</td>
<td>5</td>
<td>5</td>
<td>7</td>
<td>7</td>
</tr>
<tr>
<td>5</td>
<td>310</td>
<td>310</td>
<td>5</td>
<td>5</td>
<td>7</td>
<td>7</td>
</tr>
<tr>
<td>6</td>
<td>300</td>
<td>300</td>
<td>5</td>
<td>5</td>
<td>17</td>
<td>17</td>
</tr>
</tbody>
</table>

Table III.2. Gain Values
The grav_comp, and trjgen modules, giving the trjgen module the data initial position. When the manipulator reached the data initial position, the track module was activated. Then, the trjgen module was activated with the data final position and the appropriate duration. Upon completion of the movement, the data file created by the trjgen module contained the commanded and actual joint position value samples. Since this was accomplished for each of the motion durations, three files were produced containing data. With this data, the error between commanded and actual joint positions could be calculated. This error data constituted the baseline performance.

III.1.3. Measurement of the Performance

This section of the chapter is divided into three parts. This first part discusses the pseudo-step response performance measurements. These are the same type of measurements as conducted by Anchor. The second part describes my attempt at a modified step response performance measurement. The step response issue was first addressed in section II.2 and is further addressed below. The final part discusses missed cycle testing.

III.1.3.1. Pseudo-Step Response

As discussed in section II.2, the trjgen module does not provide a true step response motion. However, the measurements taken by Anchor did give a good general idea of the performance of his UTAP controller. Also, I wanted to see how much the gain tuning affected the performance. Therefore, I conducted the performance measurement of the gain tuned system using Anchor’s method (which is also the same
method used to obtain the baseline). Section III.2.2 contains an analysis of the data received during these measurements and Appendix E contains the position error plots.

III.1.3.2. Modified Step Response

The first task under this portion of the research was to modify the Chimera trjigen module to perform a true step response motion. The modification involved removing the loop in the trjigenCycle function that divided the difference between the current position and the desired position into small increments and moved the joint through the increments. Instead, the function now moves the joint directly from the current position to the desired position. Appendix F contains the trjigenCycle function source code both before and after modification.

The next task involved using the modified trjigen module to collect the step response data. I attempted to follow the same data collecting procedure as I had used with the pseudo-step response function. However, any attempt to command movement resulted in severe oscillations of joint four, five, or six. Once the oscillations started, the emergency kill switch had to be pressed to stop them. Therefore, use of the modified step response for performance testing was not feasible. Section III.2.3 discusses these oscillations and their probable cause.

III.1.3.3. Missed Cycle Testing

I had originally planned to conduct a third performance test on Anchor’s controller. Under this test, the execution frequency of the original controller would have been slowed to the point were it almost missed cycles but did not. I would have then attempted to execute the UTAP controller at the same frequency. If execution was
possible and the controller was stable, the number of missed cycles would have been counted and evaluated. However, contrary to Anchor’s belief, the UTAP controller was already missing cycles at the current operating frequency. The missed cycles, coupled with the oscillations, prevented the conduction of this test.

III.2. Analysis

This section is divided into three parts corresponding to the gain tuning, pseudo-step response testing, and step response testing of Anchor’s controller. In each part, the data is presented and explained.

III.2.1. Gain Tuning

Figure III.2 shows the final trajectory plot obtained while tuning joint one. The graph shows the joint one trajectories for before and after gain tuning. As can be seen, there is a significant improvement in the post-gain tuned trajectory over the pre-gain tuned trajectory. The post-gain tuning trajectory reaches steady state much sooner and has less over-shoot.
Joints two and three showed similar improvements. As shown in Table III.2, the gains for joints four, five, and six did not require changing. Therefore, the position plots show only a single trajectory. Appendix D contains the trajectory plots for all six joints.

III.2.2. Pseudo-Step Response

From the data obtained by the baseline measurements, I calculated the error between the commanded and actual positions of each joint for each trajectory on the non-UTAP controller. The data obtained during the pseudo-step response measurement was then used to calculate the position error of each joint for each trajectory on the gain-tuned UTAP controller. These error values, along with the values obtain by Anchor for the non-gain tuned UTAP controller, were then plotted. Each plot shows the original, non-gain tuned UTAP, and gain tuned UTAP controller’s error for a particular joint at one of the three trajectory durations. The error plot for the nominal trajectory of joint one is shown in Figure III.3 and Appendix E contains all the error plots.

Figure III.3. Joint 1 Error for Nominal Trajectory
The error values are in radians and are plotted against the cycle of the periodic task that recorded the data. The cycle can be equated to time since the task recorded the data once each cycle and it was executed at a frequency of 50 Hz.

Tables III.3, III.4, and III.5 show the integral error exhibited by each controller. I calculated these values by summing the absolute value of the error measurement at each cycle. The percent difference between the original controller and the pre-gain tuned controller was calculated using the following equation:

\[
PercentDifference = 100 \times \left( \frac{PreGainTunedError - OriginalError}{PreGainTunedError} \right)
\]

The percent difference between the original controller and the post-gain tuned controller was calculated using the following equation:

\[
PercentDifference = 100 \times \left( \frac{PostGainTunedError - OriginalError}{PostGainTunedError} \right)
\]

Likewise, the percent difference between the pre-gain tuned controller and the post-gain tuned controller was calculated with this equation:

\[
PercentDifference = 100 \times \left( \frac{PostGainTunedError - PreGainTunedError}{PostGainTunedError} \right)
\]

<table>
<thead>
<tr>
<th>Joint</th>
<th>Joint 1</th>
<th>Joint 2</th>
<th>Joint 3</th>
<th>Joint 4</th>
<th>Joint 5</th>
<th>Joint 6</th>
<th>Total</th>
</tr>
</thead>
<tbody>
<tr>
<td>Original Error:</td>
<td>1.9273</td>
<td>0.8392</td>
<td>1.1085</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>3.8751</td>
</tr>
<tr>
<td>Pre-gain Tuning Error:</td>
<td>1.7497</td>
<td>0.9547</td>
<td>0.8569</td>
<td>0.5317</td>
<td>0.1568</td>
<td>95.228</td>
<td>99.4768</td>
</tr>
<tr>
<td>Post-gain Tuning Error:</td>
<td>0.1347</td>
<td>0.1208</td>
<td>0.1442</td>
<td>0.1124</td>
<td>0.0658</td>
<td>0.2828</td>
<td>0.8607</td>
</tr>
<tr>
<td>Original vs Pre-gain Tuning Percent Difference</td>
<td>-10.16</td>
<td>12.09</td>
<td>-29.37</td>
<td>100.00</td>
<td>100.00</td>
<td>100.00</td>
<td>96.10</td>
</tr>
<tr>
<td>Original vs Post-gain Tuning Percent Difference</td>
<td>-1,330.35</td>
<td>-594.80</td>
<td>-668.84</td>
<td>100.00</td>
<td>100.00</td>
<td>100.00</td>
<td>-350.22</td>
</tr>
<tr>
<td>Pre-gain Tuning vs Post-gain Tuning Percent Difference</td>
<td>-1,198.53</td>
<td>-690.38</td>
<td>-494.31</td>
<td>-373.16</td>
<td>-136.86</td>
<td>-33,566.96</td>
<td>-11,457.39</td>
</tr>
</tbody>
</table>

Table III.3. Integral Error for Slow Trajectory
<table>
<thead>
<tr>
<th>Joint 1</th>
<th>Joint 2</th>
<th>Joint 3</th>
<th>Joint 4</th>
<th>Joint 5</th>
<th>Joint 6</th>
<th>Total</th>
</tr>
</thead>
<tbody>
<tr>
<td>Original Error:</td>
<td>2.3087</td>
<td>0.9821</td>
<td>1.2041</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>Pre-gain Tuning Error:</td>
<td>2.2042</td>
<td>1.1034</td>
<td>1.0679</td>
<td>0.8692</td>
<td>0.2423</td>
<td>104.7391</td>
</tr>
<tr>
<td>Post-gain Tuning Error:</td>
<td>0.2007</td>
<td>0.1221</td>
<td>0.2247</td>
<td>0.1673</td>
<td>0.1010</td>
<td>0.4785</td>
</tr>
<tr>
<td>Original vs Pre-gain Tuning Percent Difference</td>
<td>-4.74</td>
<td>11.00</td>
<td>-12.75</td>
<td>100.00</td>
<td>100.00</td>
<td>100.00</td>
</tr>
<tr>
<td>Original vs Post-gain Tuning Percent Difference</td>
<td>-1050.42</td>
<td>-704.57</td>
<td>-435.78</td>
<td>100.00</td>
<td>100.00</td>
<td>100.00</td>
</tr>
<tr>
<td>Pre-gain Tuning vs Post-gain Tuning Percent Difference</td>
<td>-998.35</td>
<td>-803.99</td>
<td>-375.19</td>
<td>-419.45</td>
<td>-139.91</td>
<td>-21,786.81</td>
</tr>
</tbody>
</table>

Table III.4. Integral Error for Nominal Trajectory

<table>
<thead>
<tr>
<th>Joint 1</th>
<th>Joint 2</th>
<th>Joint 3</th>
<th>Joint 4</th>
<th>Joint 5</th>
<th>Joint 6</th>
<th>Total</th>
</tr>
</thead>
<tbody>
<tr>
<td>Original Error:</td>
<td>2.9561</td>
<td>1.1813</td>
<td>1.5658</td>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>Pre-gain Tuning Error:</td>
<td>2.8866</td>
<td>1.3002</td>
<td>1.5148</td>
<td>1.659</td>
<td>0.4419</td>
<td>1.3951</td>
</tr>
<tr>
<td>Post-gain Tuning Error:</td>
<td>0.2666</td>
<td>0.1379</td>
<td>0.3385</td>
<td>0.3019</td>
<td>0.1756</td>
<td>0.9034</td>
</tr>
<tr>
<td>Original vs Pre-gain Tuning Percent Difference</td>
<td>-2.34</td>
<td>9.15</td>
<td>-3.37</td>
<td>100.00</td>
<td>100.00</td>
<td>100.00</td>
</tr>
<tr>
<td>Original vs Post-gain Tuning Percent Difference</td>
<td>-1008.98</td>
<td>-756.42</td>
<td>-362.54</td>
<td>100.00</td>
<td>100.00</td>
<td>100.00</td>
</tr>
<tr>
<td>Pre-gain Tuning vs Post-gain Tuning Percent Difference</td>
<td>-983.66</td>
<td>-842.65</td>
<td>-347.47</td>
<td>-451.81</td>
<td>-151.68</td>
<td>-54.43</td>
</tr>
</tbody>
</table>

Table III.5. Integral Error for Fast Trajectory

The plots and the tables show that, in all cases, by gain tuning the UTAP controller, the error was reduced from that exhibited by the non-gain tuned UTAP controller. In fact, the error values for all trajectories of joints one, two, and three of the post-gain tuned controller are less than the values for the original controller. Additionally, the total error values for all trajectories of the post-gain tuned controller are less than the values for the original controller. If only the total error and percent difference numbers are considered, it would appear that implementing a gain-tuned UTAP controller enhanced the system performance. However, there is no evidence to suggest that the original controller was gain-tuned for optimal performance. Normal
wear of the system would require that the gains be periodically tuned. I believe that the original controller requires gain tuning. If gain-tuning of the original controller was accomplished, I would expect it to perform better than the gain-tuned UTAP controller. The gain-tuned original controller versus the post-gain tuned UTAP controller error values would be similar to the original versus pre-gain tuned values.

III.2.3. Step-Response

As stated in Section III.1.3.2, the step response evoked severe oscillations in joints four, five, or six. Movement of joints one, two, or three usually caused joint four to oscillate. Movement of joints four, five, or six would cause that particular joint to oscillate. The oscillations occurred when the magnitude of a commanded joint movement exceeded a certain threshold. The threshold varied for each joint. The larger joints, joints one, two, and three, could sometimes be moved up to five degrees without oscillations. Joints four, five, and six could rarely be moved more than one degree.

While investigating the oscillations, I found that they could be induced with both the original and the modified trajectory generation modules under the UTAP-compliant controller. However, they could not be induced with either module under the original controller. Eventually, the problem was isolated to the controller gains.

When the \( K_p \) and \( K_d \) values were reduced and the \( K_i \) value was set to zero for joints four, five, and six, the oscillations ceased to occur. This indicated a problem in the gain tuning procedures. When conducting both Klafter’s and the modified gain tuning procedures, the \texttt{trijgen} module was used to move the joint. In both cases the joint movement lasted 1.5 seconds. The movements were not large enough or fast enough to
induce the oscillations. Additionally, for the same reasons a step response was needed during the performance measurements, a step response movement should have been used when gain tuning the controller. Therefore, a better method for gain tuning the controller must be developed.

When experimenting with the joint four gains, I found that the $K_p$ and $K_d$ gains could be set to 125 and 3.5 respectively and the $K_i$ gain could be set to 1.5 without the oscillations occurring. When $K_i$ was set above 1.5 with these $K_p$ and $K_d$ values, evidence of the oscillations began. Therefore, implementing UTAP limited the range of gain values that could be used without causing oscillations. By limiting the gain values, it is possible that the joint could not be tuned to optimal performance.

III.3. Summary

This chapter has presented the methods used to obtain the performance measurements of Anchor's UTAP implementation. It described gain tuning the controller and obtaining a measurement baseline. This was followed by a description of the measurement of the two types of step response. Some other tests were discussed that proved to be not feasible.

The chapter then moved on to analyze the data. It indicated that performance was greatly enhanced by gain tuning the controller. The performance was enhanced so much that it appeared to perform better than the original controller. This suggested that the original controller would also benefit from gain tuning. Gain tuning the original controller would likely return the performance ratio between the original controller and the UTAP controller back to that observed by Anchor.
The step response testing performed on the UTAP controller identified a problem with the UTAP controller gains. The procedures used to gain tune the controller did not take into consideration the method used to move the manipulator, the size of the movement, or the speed of the movement.
IV. Implementation of UTAP on the Adept 550 Manipulator

This chapter presents the methods used to implement the UTAP specification on the Adept 550 manipulator. It describes the methods involved with the preparation of the application, development of the interface layer, testing, and performance measurement. Next, the chapter presents an analysis of the performance data.

IV.1. Methodology

This section of the chapter describes the implementation of the UTAP specification on the Adept 550 manipulator. The overall approach to the task was to find an existing application written for the Adept system, convert it to UTAP compliance, and develop an interface layer that would allow the UTAP-compliant application to run on the Adept system. These steps are described below and are followed by a description of the methods involved with the performance measurement of the implementation.

IV.1.1. Determination of the Appropriate Application

There were three major criteria to consider in choosing the application. First, the application must incorporate a variety of functions such as robot control, use of the manual control pendant (MCP), operator input, and disk file IO. This ensured that a respectable portion of the UTAP specification would be implemented. Second, the application must not be too large and complex or there would not have been time to finish the project. Third, AFIT must have legal rights to use and alter the application.

Previously, ACG had provided AFIT with numerous applications that demonstrated various capabilities of the Adept system. After reviewing these applications, I found that they were either too complex (several thousand lines of code) or
too specialized (only involved robot control and output to the screen). I also reviewed two projects from the Robotic Fundamentals course. These were not complex enough for this purpose.

The application eventually chosen was one I had written during a V+ programming course given by Adept Technologies. The primary function of the application is to move parts from one pallet to another. Additional functions include MCP control of the application, screen display of location information, screen display of system information, and writing location information to an audit trail file. I also added two force control functions to the application. The first simulates attempting to insert a part into a recess. If the part will not slide into the recess smoothly, it is returned to the pallet and another part is tried. The second force control function slowly lowers a part to the work surface. It uses force sensing to determine when the part is sitting on the work surface. It then releases the part and moves to a safe position. Appendix G contains the original source code for the application.

IV.1.2. Conversion of the Application to UTAP Compliance

In order to begin the conversion, I needed to decide how to implement the UTAP messages. Anchor had to choose between using Chimera’s Interprocessor Message Passing or implementing them as subroutine calls [3]. The choice turned out to be very easy since V+ does not support any type of interprocess messages. Therefore, the only option was to implement the UTAP messages as V+ subroutine calls. A small problem did arise from this. V+ allows a subroutine to have up to 256 characters in its name.
However, V+ only recognizes the first 15. Therefore, UTAP messages with long names could be interpreted as the same message. For example, the UTAP messages US_AXIS_SERVO_USE_ABS_POSITION_MODE and US_AXIS_SERVO_USE_REL_POSITION_MODE would be interpreted by V+ as the same message, US_AXIS_SERVO_U. During a telephone conversation, John Michaloski of the Intelligent Systems division of NIST and I decided that the best alternate would be to abbreviate the message names. Therefore, “US_” was dropped from the front of all the messages implemented. Most messages also have a three letter abbreviation of the module name following the “US_.” This was standardized to a two letter abbreviation as shown in table IV.1.

Additionally, other words were abbreviated as needed. For example, the UTAP message US_TLC_START_FINE_MOTION became tl_str_fine_mot. Consistency was maintained in all the abbreviations made. Appendix C contains a list of all the messages defined in the UTAP specification.

<table>
<thead>
<tr>
<th>UTAP MODULE NAME</th>
<th>UTAP ABBREVIATION</th>
<th>V+ ABBREVIATION</th>
</tr>
</thead>
<tbody>
<tr>
<td>Analysis &amp; Diagnostics</td>
<td>ADS</td>
<td>AD</td>
</tr>
<tr>
<td>Object Calibration</td>
<td>OC</td>
<td>OC</td>
</tr>
<tr>
<td>Operator Input Devices</td>
<td>OI</td>
<td>OI</td>
</tr>
<tr>
<td>Object Knowledge</td>
<td>OK</td>
<td>OK</td>
</tr>
<tr>
<td>Object Modeling</td>
<td>OM</td>
<td>OM</td>
</tr>
<tr>
<td>Parent Task Program Sequencer</td>
<td>PTPS</td>
<td>PS</td>
</tr>
<tr>
<td>Robot/Axis Servo Control</td>
<td>RSC (or Axis Servo)</td>
<td>AS</td>
</tr>
<tr>
<td>Sensor Control</td>
<td>SC (or Sensor)</td>
<td>SC</td>
</tr>
<tr>
<td>Status Graphics &amp; Display</td>
<td>SGD</td>
<td>SG</td>
</tr>
<tr>
<td>Subsystem Simulators</td>
<td>SS</td>
<td>SS</td>
</tr>
<tr>
<td>Tool Control</td>
<td>TC</td>
<td>TC</td>
</tr>
<tr>
<td>Trajectory Description</td>
<td>TD</td>
<td>TR</td>
</tr>
<tr>
<td>Task Description &amp; Supervision</td>
<td>TDS</td>
<td>TD</td>
</tr>
<tr>
<td>Task Knowledge</td>
<td>TK</td>
<td>TK</td>
</tr>
<tr>
<td>Task Program Sequencer</td>
<td>TPS</td>
<td>TS</td>
</tr>
<tr>
<td>Subsystem Task Level Control</td>
<td>TLC</td>
<td>TL</td>
</tr>
<tr>
<td>Virtual Sensor</td>
<td>VS</td>
<td>VS</td>
</tr>
</tbody>
</table>

Table IV.1. UTAP Module Name Abbreviations
Since the focus of the UTAP specification is on the interfaces, conversion of the application to UTAP compliance was approached with the concept that anytime the application communicated with the operating system, the operator, or between processes, the communication must be in the form of a UTAP message. The major difficulty was determining which UTAP message should be associated with each V+ command or system call used in the application. This difficulty arose from the fact that the UTAP specification does not provide the meaning or usage of the messages it imposes. Table IV.2 shows the UTAP messages that were implemented.

<table>
<thead>
<tr>
<th>UTAP MESSAGE</th>
<th>V+ FUNCTION NAME</th>
<th>V+ COMMAND</th>
</tr>
</thead>
<tbody>
<tr>
<td>AXIS_SERVO</td>
<td></td>
<td></td>
</tr>
<tr>
<td>US_AXIS_SERVO_SET_POSITION</td>
<td>as_set_position</td>
<td>MOVE</td>
</tr>
<tr>
<td>US_AXIS_SERVO_SET_VELOCITY</td>
<td>as_set_velocity</td>
<td>SPEED</td>
</tr>
<tr>
<td>GENERIC</td>
<td></td>
<td></td>
</tr>
<tr>
<td>US_HOLD</td>
<td>hold</td>
<td>WAIT</td>
</tr>
<tr>
<td>US_INIT_OK</td>
<td>init_ok</td>
<td>GLOBAL</td>
</tr>
<tr>
<td>US_GET_EXT_DATA_VALUE</td>
<td>get_ext_data</td>
<td>PROMPT</td>
</tr>
<tr>
<td>US_POST_EXT_DATA_VALUE</td>
<td>post_ext_data</td>
<td>TYPE</td>
</tr>
<tr>
<td>OBJECT KNOWLEDGE</td>
<td></td>
<td></td>
</tr>
<tr>
<td>US_OK_ATTRIBUTE_QUERY</td>
<td>ok_attrib_query</td>
<td>SPEED, SWITCH, CONFIG,...</td>
</tr>
<tr>
<td>PROGRAMMABLE_IO</td>
<td></td>
<td></td>
</tr>
<tr>
<td>US_PIO_BIT_READ</td>
<td>pi_bit_read</td>
<td>SIG, PENDANT</td>
</tr>
<tr>
<td>US_PIO_BIT_SET</td>
<td>pi_bit_set</td>
<td>KEYMODE</td>
</tr>
<tr>
<td>US_PIO_DISABLE</td>
<td>pi_disable</td>
<td>FCLOSE, DETACH</td>
</tr>
<tr>
<td>US_PIO_ENABLE</td>
<td>pi_enable</td>
<td>ATTACH</td>
</tr>
<tr>
<td>US_PIO_SET_MODE</td>
<td>pi_set_mode</td>
<td>FOPENA, FOPENR, FOPENW</td>
</tr>
<tr>
<td>PARENT TASK PROGRAM SEQUENCER</td>
<td></td>
<td>EXECUTE</td>
</tr>
<tr>
<td>US_PTPS_SELECT_AGENT</td>
<td>ps_select_agent</td>
<td>EXECUTE</td>
</tr>
<tr>
<td>SENSOR</td>
<td></td>
<td></td>
</tr>
<tr>
<td>US_SENSOR_GET_ATTRIBUTES_READING</td>
<td>sc_get_att_read</td>
<td>FORCE.READ, FORCE.OFFSET</td>
</tr>
<tr>
<td>US_SENSOR_GET_READING</td>
<td>sc_get_reading</td>
<td>LATCH, LATCHED, FORCE.READ</td>
</tr>
<tr>
<td>TASK DESCRIPTION</td>
<td></td>
<td></td>
</tr>
<tr>
<td>US_TDS_EXECUTE_PROGRAM</td>
<td>td_exec_prog</td>
<td>CALL</td>
</tr>
<tr>
<td>TASK LEVEL CONTROL</td>
<td></td>
<td></td>
</tr>
<tr>
<td>US_TLC_START_FINE_MOTION</td>
<td>tl_str_fine_mot</td>
<td>FINE</td>
</tr>
</tbody>
</table>

Table IV.2. UTAP Messages Implemented
The table gives the UTAP message name, the V+ function name, and the V+ command to which the message equates. Additionally, there were several functions that did not have corresponding UTAP messages. In these cases, messages were created to fill the needed function. Table IV.3 lists these messages. My main concern while converting the application code to UTAP compliance was to maintain the exact functionality of the original application. This would aid the comparison between the performance measurements of the original system and the UTAP-compliant system. More importantly, this would aid in proving the feasibility of UTAP. If an operational system, such as the F-15 paint booth, were being converted to UTAP compliance, we certainly could not change the functionality of the system. Appendix H contains the source code for the UTAP-compliant application.

<table>
<thead>
<tr>
<th>UTAP MESSAGE</th>
<th>V+ FUNCTION NAME</th>
<th>V+ COMMAND</th>
</tr>
</thead>
<tbody>
<tr>
<td>GENERIC</td>
<td></td>
<td></td>
</tr>
<tr>
<td>US_GET_EXT_LOCATION_DATA</td>
<td>get_ext_loc_dat</td>
<td>SET</td>
</tr>
<tr>
<td>US_SET_EXT_LOCATION_DATA</td>
<td>set_ext_loc_dat</td>
<td>SET</td>
</tr>
<tr>
<td>SENSOR</td>
<td></td>
<td></td>
</tr>
<tr>
<td>US FT SENSOR DISABLE</td>
<td>ft_sc_disable</td>
<td>FORCE.MODE</td>
</tr>
<tr>
<td>US FT SENSOR ENABLE</td>
<td>ft_sc_enable</td>
<td>FORCE.MODE</td>
</tr>
<tr>
<td>US FT SENSOR MODE SELECT</td>
<td>ft_sc_mode_sel</td>
<td>FORCE.MODE</td>
</tr>
<tr>
<td>TOOL CONTROL</td>
<td></td>
<td></td>
</tr>
<tr>
<td>US_GRIPPER_CLOSE</td>
<td>gripper_close</td>
<td>SIGNAL 1</td>
</tr>
<tr>
<td>US_GRIPPER_OPEN</td>
<td>gripper_open</td>
<td>SIGNAL -1</td>
</tr>
</tbody>
</table>

Table IV.3. Additional Messages Created

IV.1.3. Development of the Interface Layer

Once the application had been re-written to be UTAP-compliant, a program layer needed to be written that accepted UTAP messages and translated them into V+
commands. The interface layer consists of a set of V+ program files and each program file corresponds to a UTAP module. For example, the program file pi.pg contains the V+ code that implements the functionality of the UTAP programmable input/output module. The following sections discuss general issues common to all the modules and the specific issues related to each module. Throughout this chapter I will refer to message names. When doing so, the V+ function name will be used, not the UTAP message name. This will make it easier for the reader to locate the message within the interface layer V+ programming code (Appendix I).

IV.1.3.1. General Programming Issues

While developing the interface layer, I incorporated programming techniques that ensured the easy expansion of the layer in the event that additional UTAP messages need to be implemented. For example, one of the parameters of the GET_EXT_DATA message is "channel." For the application selected, the keyboard is the only channel that inputs data via the GET_EXT_DATA message. However, within the code for the GET_EXT_DATA message, I used a case statement based on the channel to the select the operations that need to be completed. The keyboard section is the only one implemented, but adding the MCP, file, or other channel would be much easier under this design.

Several new messages were added to those defined by the UTAP specification. When this was done, the naming conventions used throughout the UTAP specification were adhered to.
IV.1.3.2. Axis Servo Module

Two UTAP messages were implemented from the axis servo module message list. Both messages were direct mappings to V+ commands. Of special interest was the parameter to the AS_SET_POSITION message. The UTAP specification defines the parameter to this message as a pointer to a double precision number. Instead, it was implemented as a V+ transformation location variable indicating a desired manipulator position. This was an example of the UTAP message name and parameters not matching the desired use of the message. However, a more suitable message could not be found, so this one was chosen. See Appendix B for a definition of the different V+ location variable types.

IV.1.3.3. Generic Module

This module implements a portion of the generic messages defined by the UTAP specification. The get_ext_data message was used to get operator input from the keyboard and the post_ext_data message was used to send output to the screen, MCP, or file. It is possible that the Operator Interface module should contain messages that serve the input and output functions implemented here. However, the UTAP specification did not provide such messages in the OI module, but instead placed these messages in the UTAP Data Definitions module. Two messages were added to this module that were not defined by the UTAP specification: get_ext_loc_dat and set_ext_loc_dat. These messages are used to store and retrieve V+ transformation location variables. The UTAP specification does not have messages of this type with the appropriate parameters. Therefore, I was forced to create the new messages.
IV.1.3.4. Object Knowledge Module

The purpose of the Object Knowledge module is to store and maintain specific knowledge of the various objects forming the entire system. This includes manipulator information such as model number as well as information about the part being worked on such as shape, mass, or hardness. For the purposes of this research, only the portions of the Object Knowledge module needed for the application were implemented. Therefore, the messages implemented in this module are the ones used to access system information.

IV.1.3.5. Programmable Input/Output Module

The messages in this module were used to enable, disable, and set the mode of the disk access and MCP. Also, they are used to read data from and write data to the MCP, signals, and system timers.

IV.1.3.6. Parent Task Program Sequencer Module

A typical robotic application will have several different processes controlling different aspects of the overall task. The palletizing application chosen uses separate processes to control the manipulator, manage the MCP, display the coordinate information, and display system information. The Parent Task Program Sequencer module manages the processes' execution sequence. Since it was the appropriate location for this type of message, the ps_select_agent message was used to start the execution of additional processes.

IV.1.3.7. Sensor Module

The UTAP specification is lacking in force/torque sensor messages. Therefore, I was required to create three new messages in this module. The messages are used to
enable, disable, and select the mode of a force/torque sensor. Existing UTAP messages were used to read the values from the sensor.

IV.1.3.8. Tool Control Module

The UTAP specification focuses primarily on aircraft painting and stripping operations. Thus, tool control messages are only defined for spindle and flow type tools, such as sanders and paint guns. For this reason, I was required to define two new messages for gripper operation: gripper_open and gripper_close. These messages are simple mappings to V+ gripper commands.

IV.1.3.9. Task Description Module

The Task Description module maintains information about what the task needs to accomplish. As a part of that, the module determines which subroutines should be used and when. The td_exec_prog message was part of this module and mapped directly to the V+ “call” command for initiating subroutines.

IV.1.3.10. Task Level Control Module

The Task Level Control module manages the events within each process. It controls positioning modes, motion types, feed rates, etc. The tl_str_fine_mot message was a direct mapping to the V+ FINE command.

IV.1.4. Testing

Testing occurred throughout the development of the interface layer. Each UTAP message was individually tested to ensure appropriate functionality. As stated earlier, an important part of my effort was to make sure that the UTAP-compliant version of the application produced the exact same results as the original version. With this in mind, I
wrote test drivers for each implemented message. The test driver would execute a V+ command or set of commands and then execute the UTAP message corresponding to the commands. I would then compare the output of each to ensure they matched. I used input values such that all categories of outcome were experienced.

Once all the messages had been tested separately, I began combining them to ensure they functioned together as expected. Again, I used test drivers to test the range of input and output possibilities.

After the individual tests were complete, I loaded the application and the interface layer and executed the application. I tested each function of the application to ensure it performed as expected and the output matched that of the original application.

IV.1.5. Performance Measurement

Performance of the implementation was measured in four different ways. First, the number of source lines of code (SLOC) in the original and the UTAP-compliant versions of the application were compared. V+ is an interpretive language. This means that a program’s source code is not compiled into some form of machine language. Instead, each line of the program is parsed as execution occurs. The V+ system preprocesses one line ahead of the current execution. Source code optimization could not be accomplished by the system due to the interpretive nature of the language. Therefore, the SLOC number can provide meaningful insight into the complexity of a program.

The second measurement conducted was a calculation of the architectural design complexity of the source code using Card and Agresti’s method [4] and provided a measure of the software quality. The method calculates the complexity of a design by
computing and summing two values. The first value defines the structural complexity of the code. It is derived from the relationships between the modules of a system. The relationships are quantified by squaring the number of modules called by each module (called the fanout or \( f_i \)) and dividing the sum of the squares by the number of modules \( (n) \) to normalize the value. Thus, the formula for structural complexity is: 
\[
S = \frac{\sum f_i}{n}
\]
The second value is the local complexity. This value indicates the amount of complexity within each module and is measured based on the amount of work performed within the module. The workload is calculated based on the number of input and output variables associated with the module \( (v_i) \) and the amount of work passed to other modules. The amount of work passed is quantitized by the same fanout value \( (f_i) \) used in the calculation of \( S \). The whole value is normalized over the number of modules \( (n) \). Thus, the formula for local complexity is:
\[
L = \frac{\sum v_i}{f_i + 1}
\]
These two values are added to give the total complexity of the code: 
\[
C = S + L
\]
The important thing to remember is that complexity measurement is simply one way to gage the quality of a software package. High complexity within a software package indicates that the software is susceptible to more design errors and will be more difficult to maintain.

The third measure of performance I gathered was the amount of system random access memory (RAM) needed by the original and UTAP-compliant versions of the application. Robotic systems have a finite amount of RAM. If UTAP compliance
required too much RAM, then the feasibility of the specification (on Adept systems) would be in question.

Finally, the fourth and most important measurement involved timing the two versions of the application. V+ has built-in timers that can be used in programs. One of these timers was used to measure the execution time of each of the two versions of the application. To ensure that operator response time was not involved in the times, the timer was initialized just after the last operator input was entered. The timer’s value was then displayed when execution finished.

Since the execution time varied depending on the starting pallet, I timed both versions with both pallets as starting points. Both versions were timed at 25, 50, 75, and 100 percent of maximum speed. Five measurements were collected for each scenario.

The amount of time a program takes is a much more concrete figure than the number of source lines of code or complexity values involved with a program. This figure gives a vivid view of the amount of overhead added to the application by UTAP compliance.

IV.2. Analysis

This section presents the data obtained while measuring the performance of the Adept 550 UTAP Implementation. The number of source lines of code is the first data presented. Next, I address the Card and Agresti complexity metrics. Third, the amount of random access memory used is presented. Finally, the execution time data is discussed.
IV.2.1. Source Lines of Code

There were 434 total source lines of code for the non-UTAP version of the application. The UTAP version of the application had 769 lines of code. Although the number of code lines almost doubled, we must consider that the number for the UTAP version includes 303 lines of code that comprise the UTAP interface layer. Any new operating system that is developed to be UTAP-compliant will not require an interface layer. Therefore, if the interface layer is considered as part of the operating system, then the UTAP version only had 466 source lines of code. This is only 32 lines, or 7 percent, more that the original version.

IV.2.2. Complexity Measures

Following the method for computing the complexity measures as described in Chapter III, we find that the original application had a structural complexity of 5.78 and a local complexity of 1.65. This equals a total design complexity of 7.43. When applied to the interface layer and the UTAP application combined, the method yields a structural complexity of 10.88, a local complexity of 1.49, and a total design complexity of 12.37. These values indicate that the UTAP version has a much more complex design than the original version. Once again, we can consider the interface layer part of the operating system. When this is done, the UTAP application has a structural complexity of 5.78, a local complexity of 2.00, and a total design complexity of 7.78. Comparing these values to those of the original application, we see that the structural complexity is the same for both. The additional complexity of the UTAP application lies in the local complexity. The structural complexity is the same because the calls to the UTAP interface are
considered operating system calls. Operating system calls are not considered when computing fanout. Therefore, the original and the UTAP applications have the same fanout and the structural complexities are the same. The local complexity is higher for the UTAP application because it uses more global variables than the original application. Several of these global variables are used to indicate the channel name parameter in a UTAP message. In a UTAP-compliant operating system, the channel names would not be considered global variables. If we did not count these as global variables when computing the local complexity of the UTAP application, the local complexity value would be much closer to that of the original application. The similarity in the complexity measures of the original and the UTAP applications indicates that developing and maintaining a UTAP-compliant application will not be any more difficult than implementing a non-UTAP-compliant application.

IV.2.3. Random Access Memory

The original application required 29.297 kilobytes of random access memory (RAM). The UTAP application and interface layer combined required 41.815 kilobytes of RAM. Again, we can view the interface layer as part of the operating system. The UTAP application alone required 30.332 kilobytes of RAM. Comparing this to the amount of RAM required by the original application, we find there is only a 1.035 kilobyte increase. This equates to only a 3.5 percent increase over the original application.
### IV.2.4. Execution Time

The execution times for the original and the UTAP applications are given in Table IV.4. The $1 \rightarrow 2$ column indicates moving the parts from pallet one to pallet two. The $2 \rightarrow 1$ column indicates moving the parts from pallet two to pallet one. All times are in seconds.

<table>
<thead>
<tr>
<th>Speed:</th>
<th>Original</th>
<th>UTAP</th>
<th>Original</th>
<th>UTAP</th>
</tr>
</thead>
<tbody>
<tr>
<td>100</td>
<td>81.049</td>
<td>85.330</td>
<td>91.081</td>
<td>95.514</td>
</tr>
<tr>
<td>75</td>
<td>81.199</td>
<td>85.877</td>
<td>91.249</td>
<td>95.339</td>
</tr>
<tr>
<td>50%</td>
<td>81.043</td>
<td>84.878</td>
<td>91.288</td>
<td>95.849</td>
</tr>
<tr>
<td>25%</td>
<td>80.923</td>
<td>84.857</td>
<td>91.316</td>
<td>95.697</td>
</tr>
<tr>
<td>Ave:</td>
<td>81.073</td>
<td>85.193</td>
<td>91.257</td>
<td>95.606</td>
</tr>
<tr>
<td>Speed:</td>
<td>50%</td>
<td>Ave:</td>
<td>91.860</td>
<td>98.580</td>
</tr>
<tr>
<td>113.625</td>
<td>125.905</td>
<td>123.968</td>
<td>135.033</td>
<td></td>
</tr>
<tr>
<td>114.199</td>
<td>125.749</td>
<td>124.082</td>
<td>134.824</td>
<td></td>
</tr>
<tr>
<td>114.559</td>
<td>125.820</td>
<td>124.334</td>
<td>134.804</td>
<td></td>
</tr>
<tr>
<td>114.413</td>
<td>125.751</td>
<td>124.090</td>
<td>135.155</td>
<td></td>
</tr>
<tr>
<td>114.816</td>
<td>125.689</td>
<td>123.971</td>
<td>135.242</td>
<td></td>
</tr>
<tr>
<td>Ave:</td>
<td>114.322</td>
<td>125.783</td>
<td>124.089</td>
<td>135.012</td>
</tr>
</tbody>
</table>

Table IV.4. Execution Times (seconds)

Table IV.5 shows the differences in execution times between the original and the UTAP-compliant application. The values were obtained by subtracting the execution time of the original application from the execution time of the UTAP application. From this table, it
can be seen that, at all speeds, the original application runs faster than the UTAP
application.

<table>
<thead>
<tr>
<th>Percentage of Maximum Speed</th>
<th>100%</th>
<th>75%</th>
<th>50%</th>
<th>25%</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 → 2</td>
<td>10.184</td>
<td>10.007</td>
<td>9.767</td>
<td>7.326</td>
</tr>
<tr>
<td>2 → 1</td>
<td>10.413</td>
<td>9.995</td>
<td>9.229</td>
<td>7.368</td>
</tr>
<tr>
<td>Average</td>
<td>10.299</td>
<td>10.001</td>
<td>9.498</td>
<td>7.347</td>
</tr>
</tbody>
</table>

Table IV.5. Execution Time Differences (seconds)

This was expected because of the increased processing required by the additional lines of
code in the UTAP application. It is also noticeable that, as the speed decreases, the time
difference between the original and the UTAP applications decreases. The
implementation of UTAP on the Adept system did not affect the time required to move
the manipulator from one position to another. The added time required by the UTAP
application is a result of processing the additional lines of code. V+ continues to process
program lines concurrent with robot motion as long as the lines do not require robot
position information, sensor information, or cause another robot motion. Because of this,
slower robot speeds allow more program processing during robot movement. Therefore,
the smaller difference between execution times of the original and the UTAP applications
during slower robot movement is explained by the increased processing time available
during the robot movements.

Counting the interface layer, the UTAP application had 335 more lines of code
than the original application. At maximum speed, the UTAP application took
approximately 10.3 seconds longer to execute than the original application. Using these
values, we can determine that each additional line of code adds 30.7 milliseconds to the
execution time. At 25 percent of maximum speed, the UTAP application took approximately 7.3 seconds longer. At this speed, each additional line of code adds 21.8 milliseconds to the execution time. Even if we add 1000 lines of code when we convert an application to UTAP compliance, we only add 31 seconds to the execution time. Of course, this assumes we are using V+, we have the same ratio of amount of movement to lines of code, and we use the larger value above to calculate the additional time.

**IV.3. Summary**

This chapter presented the methods used to implement the UTAP specification on the Adept manipulator. It presented the application chosen to convert to UTAP compliance and some of the difficulties faced during the conversion. The interface layer and how it was developed was then described. The chapter then gave a discussion of the test procedures and the performance measurements of the system.

The data obtained while measuring the Adept UTAP performance was then presented. It showed that the system performance was degraded by the implementation of UTAP. When comparing the original system to the UTAP application and the interface layer, performance degradation seemed high. However, the interface layer would not exist in a purely UTAP-compliant operating system. Thus, the original application can be compared to just the UTAP application and the interface layer viewed as part of the operating system. Under these circumstances, the UTAP application showed very little performance degradation. This indicates that retrofitting an existing robot system to UTAP would likely be unfeasible due to the performance issues.
However, a new robotic system design that incorporated UTAP would not have the performance degradation and would be feasible.
V. Conclusions and Recommendations

V.1. Conclusions

Several conclusions can be made from this thesis effort. First and foremost, implementing UTAP on two vastly different systems has shown that UTAP is a feasible telerobotic control architecture. Both systems were made UTAP-compliant for specific applications and the applications continued to performed all original tasks.

As expected, retrofitting both the Chimera system and the Adept system to UTAP compliance adversely affected the system performance. Unfortunately, difficulties with the Chimera system hindered the quantification of the performance degradation. Gain tuning Anchor’s UTAP-compliant controller greatly improved it’s performance. However, the data indicated that the original controller also needed gain tuning. The performance ratio between it and the UTAP controller would likely be returned back to that observed by Anchor by gain tuning the original controller.

Implementing UTAP on the Adept system has shown that retrofitting a system adds large amounts of overhead in the form of the interface layer. However, a system designed for UTAP compliance from the start will not have that overhead. Therefore, such a system should be able to perform as well as a non-compliant system.

The data obtained from the complexity measurements, source lines of code calculations, and RAM measurements of the Adept implementation indicates that developing and maintaining a UTAP-compliant application will not be any more difficult than implementing a non-UTAP-compliant application.
UTAP begins the telerobotic control architecture standardization effort. However, it has a long way to go. But, the effort has to start somewhere and UTAP has made a good start. It addresses the same goals as other successful standardization efforts and provides the building blocks to achieve those goals. With a continued effort to remove the inconsistencies in the UTAP specification and to provide the meaning behind each message, UTAP can make the next step towards standardizing the robotics community.

V.2. Recommendations

V.2.1. Improvements to the UTAP Specification

Determining the purpose of each UTAP message and which message to use for a particular task was the most difficult part of this thesis effort. The UTAP specification states that “the intent and meaning of UTAP API messages should be apparent from the message name” [9]. For most of the messages, this is true. However, finding the appropriate message for even basic tasks was sometimes difficult. For example, to move joint one of the manipulator, should the US_AXIS_S even BASIC TASKS WAS SOMETIMES DIFFICULT. FOR EXAMPLE, TO MOVE joint one of the manipulator, should the US_AXIS>SERVO_SET_POSITION message or the US_TLC_START_AUTOMATIC_MOTION message be used? What about the US_TLC_START_MANUAL_MOTION message? The UTAP specification should clearly define every message. The purpose of the message should be explicitly stated and guidelines presented for the use of the message. Additionally, the parameters associated with each message should be completely described, including whether they are input or output parameters and, where possible, the expected range of values.

In addition to defining the messages, the UTAP specification should define the purpose of each UTAP module. I had expected the Operator Interface module to contain
messages related to the input and output of information between the system and the operator. However, the specification does not define messages for these tasks under this module. This may not be the purpose of this module. The specification does not make the purpose of this or other modules clear. Clarifying each module’s purpose would aid the understanding of the messages contained within the module. Implementors would also be less likely incorporate into a module the wrong functionality.

Focusing on “what to pass” rather than “how to pass” allows the specification to remain generalized. However, an implementation depends on the decision of “how to pass.” A UTAP-compliant application based on passing information and control flow via function calls will not run on a system that uses message passing. The UTAP specification must specify one or the other method or it must state that UTAP-compliant systems must accommodate applications using either method.

Anchor correctly states that “the UTAP document is 'C-centric', but the specification is intended to be language-independent” [3]. The examples and message definitions should be modified as Anchor suggests. I recommend using some form of pseudo-code.

V.2.2. Future Research

A valid method for gain tuning the Chimera/PUMA system should be developed. The method should then be used to tune both the UTAP-compliant and the non-UTAP-compliant controllers. Once both controllers are tuned, the performance of the UTAP-compliant controller could be more accurately quantified.
Capt Lemley’s research efforts toward designing a purely UTAP-compliant operating system (OS) should be continued [8]. The OS should be developed for a hardware platform that has an existing non-UTAP robotic control OS. Once the UTAP-compliant OS is in place, applications could be written with identical functionality for both the UTAP-compliant OS and the original OS. Neither application would require an interface layer since they both were written for their native OS. Comparing the performance of the two applications would define the impact on the system levied by UTAP conformance.

Finally, the Adept UTAP implementation should be expanded to include more of the messages defined by the UTAP specification. This would further cement the feasibility of UTAP and provide more data on the performance issues.

V.3. Summary

Table V.1 provides a summary of the conclusions of this thesis. Table V.2 summarizes my recommendations for improvements to the UTAP specification and Table V.3 summarizes my recommendations for future research. This thesis effort investigated the feasibility of the Unified Telerobotic Architecture by implementing the UTAP specification on an existing robotic system and measuring the performance of this and a previous implementation. This effort has shown that the architecture is feasible but requires additional clarification. This thesis has also shown that retrofitting existing systems exacts a heavy performance toll on the system, but designing a new system to be UTAP-compliant is an appropriate activity to pursue. The results of this thesis will aid in
making the decision to continue pursuing the UTAP specification as an Air Force standard.

<table>
<thead>
<tr>
<th>Conclusions</th>
</tr>
</thead>
<tbody>
<tr>
<td>1. Gain tuning improved the performance of Anchor’s UTAP controller</td>
</tr>
<tr>
<td>2. The original controller needs be have the gains tuned</td>
</tr>
<tr>
<td>3. Tuning the original controller would return the performance ratio between it and Anchor’s back to ratio observed by Anchor</td>
</tr>
<tr>
<td>4. UTAP is a feasible telerobotic control architecture</td>
</tr>
<tr>
<td>5. Retrofitting a system adversely affects its performance</td>
</tr>
<tr>
<td>6. A system designed from the beginning to be UTAP-compliant will not have the adverse performance effects</td>
</tr>
<tr>
<td>7. Developing applications for a UTAP-compliant system is not any more difficult than developing applications for a non-UTAP-compliant system</td>
</tr>
</tbody>
</table>

Table V.1. Summary of Conclusions

<table>
<thead>
<tr>
<th>Recommendations</th>
</tr>
</thead>
<tbody>
<tr>
<td>1. Explicitly define each UTAP message including the parameters</td>
</tr>
<tr>
<td>2. Explicitly define each UTAP module including the functions and purpose</td>
</tr>
<tr>
<td>3. Decide on a message passing format or state that both must be supported</td>
</tr>
<tr>
<td>4. Use pseudo-code instead of C code for examples</td>
</tr>
</tbody>
</table>

Table V.2. Summary of Recommendations for the UTAP Specification

<table>
<thead>
<tr>
<th>Recommendations</th>
</tr>
</thead>
<tbody>
<tr>
<td>1. Develop a gain tuning method and conduct further measurements on Anchor’s UTAP-compliant controller</td>
</tr>
<tr>
<td>2. Continue Capt Lemley’s development of an originally designed UTAP-compliant system</td>
</tr>
<tr>
<td>3. Expand the Adept UTAP implementation</td>
</tr>
</tbody>
</table>

Table V.3. Summary of Recommendations for Future Research
Bibliography


APPENDIX A

V+/UTAP System Users Manual

Note: User input and system prompts are shown in a different font than the rest of the test. User input is also shown in boldface. Text in italics represents a placeholder for some other test (i.e., a variable name).

Adept System Power-up and Calibration

Steps:

1. Turn the Adept system’s power switch to “On”.

2. Plug in the air dryer power cord.

3. Open the air valve on the compressor tank.

4. Turn the compressor power switch to “Auto”.

5. Open both air valves located at the back of the manipulator table.

6. Enable power to the manipulator by typing the following at the monitor prompt:
   
   . enable power

7. Calibrate the Adept manipulator by typing the following at the monitor prompt:

   . calibrate

8. Confirm that calibration should occur by responding with a “y”:

   Are you sure (y/n): y

Loading the V+/UTAP Interface

Steps:

1. Change to the UTAP directory by issuing the following monitor command:

   . def = c:\utap

55
2. Load the V+/UTAP interface modules into system memory. Each module can be loaded individually with the `load` command. For example, the sensor module can be loaded with the following command:

```plaintext
.load sc.pg
```

A script can be used to load all of the modules instead of loading them individually. This is accomplished with the following commands:

```plaintext
.load utap.pg
.commands setup
```

At this point, a UTAP-compliant application can be loaded and executed.

### Loading and Executing an Application

Steps:

1. Change to the directory containing the application. For example, the following command will change to the directory containing a palletizing application:

```plaintext
.def = c:\utap\app
```

2. Load the application into system memory using the `load` command. The UTAP-compliant palletizing application is loaded as follows:

```plaintext
.load demo.v2
.load pallet.pg
.load force.pg
```

3. Begin application execution by issuing the `execute` command with the main program. The palletizing application is started with the following command:

```plaintext
.execute utap.demo
```

### Adept System Shutdown

Steps:

1. Close the air valves on the back of the manipulator table.
2. Turn the air compressor power switch to "Off".

3. Close the air valve on the compressor tank.

4. Unplug the air dryer.

5. Turn the Adept System power switch to "Off".
APPENDIX B

Adept V+ Tutorial

I. Introduction.

V+ is Adept Technology’s proprietary control system and programming language used with their industrial robots. This tutorial presents excerpts and information from the V+ Language User’s Guide [1] and the V+ Quick Reference Guide [2]. It presents the basic information needed to operate and program the Adept 550 manipulator. The tutorial is divided into three sections. The first section covers general V+ issues. The second section describes the basic control system commands (called monitor commands). The third section describes some programming language commands (called language commands).

II. General V+ Issues

II.1. Program Types

There are two types of V+ programs, executable and command.

II.1.1. Executable Programs

There are two classes of executable programs, robot control programs and general programs. A robot control program is a V+ program that directly controls a robot. A general program is any program that does not control a robot. A mixture of robot control and general programs can execute at the same time, but only one robot control program can have control of the robot at any given time. Robot control programs can contain any of the V+ program instructions. With the exception of the BRAKE instruction, a general program cannot execute any instruction that affects the robot motion. They can access all other V+ features including AdeptVision, digital signal lines, and the manual control pendant. Executable programs are initiated by the EXECUTE monitor command.

II.1.2. Command Programs

Command programs are similar to MS_DOS batch programs or UNIX scripts. They can contain any monitor command and can access language commands through the monitor DO command. Command programs are initiated by the COMMANDS monitor command.
II.2. Data Types

II.2.1. Declaration and Allocation

V+ does not require you to declare variables or their data types. The first use of a variable will determine its data type and allocated space for that variable.

II.2.2. Variable Name Requirements

The requirements for a valid variable name are:

1. Adept reserved keywords cannot be used.
2. The first character of a variable name must be a letter.
3. The characters after the first character may be letters, numbers, periods, and the underline character.
4. Only the first 15 characters in a variable name are significant.

II.2.3. String Data Type

Variable names are preceded with a “$” sign to indicate that they contain character string data. The dollar sign is not considered in the character count of the variable name. For example, the program instruction:

\[
\$\text{string}_1 = \text{"Adept V+"}
\]

allocates the string variable “\$string_1” and assigns it the value “Adept V+”. The character count of the variable name “\$string_1” is 8. String variables can contain from 0 to 128 characters and any ASCII character can appear in a string variable. String constants can also have 0 to 128 characters. However, only ASCII characters 32 through 126 (excluding ASCII 34, “” can appear in a string constant.

II.2.4. Real and Integer Data Types

Numbers that have a whole number and a fractional part belong to the data type “real”. Numeric values having only a whole number belong to the data type “integer”. In general, V+ does not require you to differentiate between these two data types. If an integer is required and you supply a real, V+ will promote the real to an integer by rounding (not truncation). Where real values are required, V+ considers an integer a special case of a real that does not have a fractional part. The default real type is a signed, 32-bit IEEE single-precision number. Real values can also be stored as 64-bit IEEE double-precision numbers if they are specifically typed using the DOUBLE instruction.

The range of integer values is:
The range of single-precision real values is:

\[ \pm 3.4 \times 10^{38} \]

The range of double-precision real values is:

\[ \pm 1.8 \times 10^{307} \]

In almost all situations where a numeric value of variable can be used, a numeric expression can also be used. The following examples all result in “x” having the same value:

\[
\begin{align*}
x &= 3 \\
x &= 6 / 2 \\
x &= \sqrt{9} \\
x &= \sqrt{2} - 1 \\
x &= 9 \mod 6
\end{align*}
\]

V+ does not have a specific logical (Boolean) data type. Any numeric value, variable, or expression can be used as a logical data type. V+ considers 0 to be false and any other value to be true. When a real value is used as a logical data type, the value is first promoted (rounded) to an integer. There are four logical constants, TRUE and ON that will resolve to -1, and FALSE and OFF that will resolve to 0. These constants can be used anywhere a Boolean expression is expected.

### 11.2.5. Location Data Types

V+ uses two data types to represent locations, transformations and precision points. A transformation is a set of six components that uniquely identifies a location in Cartesian space and the orientation of the motion device end-of-arm tooling at that location. A transformation can also represent the location of an arbitrary local reference frame. The first three components of a transformation variable are the values for the points on the X, Y, and Z axes. The second three components of a transformation variable specify the orientation of the end-of-arm tooling. These three components are yaw, pitch, and roll.

A precision point includes an element for each “joint” in the motion device. Rotational joint values are measured in degrees; translational joint values are measured in millimeters. These values are absolute with respect to the motion device’s home sensors and cannot be made relative to other locations or coordinate frames.

### 11.2.6. Arrays
V+ supports arrays of up to three dimensions. Any V+ data type can be stored in an array. Like simple variables, array allocation and typing is dynamic.

II.2.7. Variable Classes

In addition to having a data type, variables belong to one of three classes, GLOBAL, LOCAL, or AUTOMATIC. These classes determine how a variable can be altered by different calling instances of a program.

II.2.7.1. Global Variables

This is the default class. Unless a variable is specifically declared to be LOCAL or AUTO, a newly created variable will be considered global. Global variables can be accessed by any executing program.

II.2.7.2. Local Variables

Local variables are created by a program instruction similar to:

```
LOCAL the_local_var
```

In this example, “the_local_var” is declared as a local variable. Local variables are available to all calling instances of a program. In other words, a local variable that is changed during a recursive call of a program will be changed in all instances of the recursive program.

II.2.7.3. Automatic Variables

Automatic variables are created by a program instruction similar to:

```
AUTO the_auto_var
```

In this example, “the_auto_var” is declared as an automatic variable. Automatic variables can only be changed by a particular calling instance of a program.

II.3. Operators

II.3.1. Assignment Operator

The equal sign (=) is used to assign a value to a numeric or string variable. The variable being assigned a value must appear by itself on the left side of the operator. The right side of the equal sign can contain any variable or value of the same data type as the left side, or any expression that resolves to the same data type. Location variables use the SET instruction for assignment and may not use the equal sign assignment operator.
II.3.2. Mathematical Operators

V+ uses the standard mathematical operators; +, -, *, /, and MOD.

II.3.3. Relational Operators

V+ uses the standard relational operators; ==, <, >, <=, >=, and <>.

II.3.4. Logical Operators

V+ uses the standard logical operators; NOT, AND, OR, and XOR.

II.3.5. String Operator

In V+, strings can be concatenated, or joined, using the “+” operator.

II.3.6. Order of Evaluation

Expressions are not evaluated in a simple left to right fashion in V+. Table B.1 shows the order of evaluation. Operators on the same line have the same precedence and are evaluated left to right. Parenthesis can be used in the normal manner to change the evaluation order within an expression.

<table>
<thead>
<tr>
<th>Evaluation Order</th>
<th>Operator</th>
</tr>
</thead>
<tbody>
<tr>
<td>First</td>
<td>NOT</td>
</tr>
<tr>
<td></td>
<td>- (Unary minus)</td>
</tr>
<tr>
<td></td>
<td>*, /, MOD, AND</td>
</tr>
<tr>
<td></td>
<td>+, -, OR, XOR</td>
</tr>
<tr>
<td>Last</td>
<td>==, &lt;=, =&gt;, &lt;, &gt;, &lt;&gt;</td>
</tr>
</tbody>
</table>

Table B.1. Order of Operator Evaluation

II.4. The SEE Editor

The SEE editor is a full functioned screen editor that is provided with the V+ control system and programming language. The SEE editor performs syntax checks on each line as it is entered. The beginning of each invalid line is marked with a question mark. The editor automatically capitalizes language keywords and insert the appropriate amount of spaces between keywords, variables, and operators. Additionally, the editor automatically indents program lines by the proper amount based on the level of nesting. The “.PROGRAM” line of each program is inserted when the SEE editor first creates the program. The editor also places the .END statement at the end of each program. It is important to note that the editor works on programs in system memory. It does not read
programs from disk or write programs to disk. This must be accomplished with monitor commands. Use of the SEE editor is described in the appropriate Adept Manuals.

III. Monitor Commands

Monitor commands are commands that are entered at the system prompt. The following section describes some of the most used commands. They are grouped into the following three categories; system control and information, disk commands, and program control.

*Note:* Keywords are shown in uppercase and arguments are shown in lowercase. Required keywords, parameters, and marks such as equal signs and parenthesis are shown in bold type; optional keywords, parameters, and marks are shown in regular type.

### III.1. System Control and Information Commands

These commands control various aspects of the system or provide information about the system.

**CALIBRATE**
- Initialize the robot positioning system.

**DELETEL loc_var, ..., loc_var**
- Delete the named location variables from the system memory.

**DELETER real_var, ..., real_var**
- Delete the named real-valued variables from the system memory.

**DELETES str_var, ..., str_var**
- Delete the named string variables from the system memory.

**DIRECTORY select**
- Display the names of some or all the programs in the system memory.

**DO instruction**
- Execute a single program instruction as though it were the next step in the current main control program, or the next step in the specified task/program context.

**ENABLE switch, ..., switch**
- Turn on one or more system control switches.

**FREE select**
- Display the percentage of available system memory not currently in use.

**HERE loc_variable**
Define the value of a transformation or precision-point variable to be equal to the current robot location.

**LISTL location, . . . , location**
Display the values of the list locations.

**LISTR expression, . . . , expression**
Display the values of the real variables specified.

**LISTS string, . . . , string**
Display the values of the string variables specified.

**SEE program_name/qualifier**
Invoke the screen-oriented program editor to allow a program to be created, viewed, or modified.

**STATUS select**
Display status information for the system and the programs being executed.

**SPEED speed_factor**
Specify the speed of all subsequent robot motions commanded by a robot control program.

**ZERO select**
Reinitialize the V+ system and delete all programs and data in the system memory.
Delete all user-defined windows, fonts, and icons from graphics memory.

### III.2. Program Control Commands

These commands control programs that are currently loaded in memory.

**ABORT task_num**
Terminate execution of a control program.

**COMMANDS program**
Initiate processing of a command program.

**COPY new_program = old_program**
Create a new program in system memory as a copy of an existing program in system memory.

**DELETE program, . . . , program**
Delete the listed programs from the system memory.

**EXECUTE task_num program(param_list), cycles, step, priority[i]**
Begin execution of a control program.

**KILL** `task_num`
Clear a program execution stack and detach any I/O devices that are attached.

**RENAME** `new_program_name = old_program_name`
Change the name of a user program in memory to the new name provided.

### III.3. Disk Commands

These commands perform functions related to files and magnetic storage media.

**FCOPY** `new_file = old_file`
Copy the information in an existing disk file to a new disk file.

**FDELETE** `file_spec`
Delete one or more disk files matching the given file specification.

**FDIRECTORY** `/qualifier file_spec`
Display information about the files on a disk, along with the amount of space still available for storage. Create and delete subdirectories on disks.

**FLIST** `file_spec`
List the contents of the specified disk file on the system terminal.

**FORMAT** `A:/qualifier`
Initialize and erase a FLOPPY disk.

**FRENAME** `new_file = old_file`
Change the name of a disk file.

**LOAD** `switch file_spec`
Load the contents of the specified disk file into the system memory.

**STORE** `/levels file_spec = program_name, ... , program_name`
Store programs and variables in a disk file.

**STOREL** `/levels file_spec = program_name, ... , program_name`
Store location variables in a disk file.

**STORER** `/levels file_spec = program_name, ... , program_name`
Store real variables in a disk file.

**STORES** `/levels file_spec = program_name, ... , program_name`
Store string variables in a disk file.
IV. Language Commands

Language commands are commands that are used within executable programs. The following section describes some of the most used commands.

Note: Keywords are shown in uppercase and arguments are shown in lowercase. Required keywords, parameters, and marks such as equal signs and parenthesis are shown in bold type; optional keywords, parameters, and marks are shown in regular type.

APPRO location, distance
APPROS location, distance
Start a robot motion toward a location defined relative to the specified location.

ATTACH (lun)
ATTACH (alun, mode) $device
Make a device available for use by the application program.

AUTO variable, .., variable
AUTO type variable, .., variable
Declare temporary variables that are automatically created on the program stack when the program is entered.

BRAKE
Abort the current robot motion

BREAK
Suspend program execution until the current motion completes.

CALL program(arg_list)
Suspend execution of the current program and continue execution with a new program (that is, a subroutine).

CASE value OF
Initiate processing of a CASE structure by defining the value of interest.

DEPART distance
DEPARTS distance
Start a robot motion away from the current location.

DETACH (logical unit)
Release a specified device from the control of the application program.

DO
Introduce a DO program structure.
DOS string, error
  Execute a program instruction defined by a string expression.

END
  Mark the end of a control structure.

EXECUTE program(param_list)
EXECUTE task_num program(param_list)
  Begin execution of a control program.

FOPENR (lun, record_len, mode) file_spec
FOPENW...
FOPENA...
FOPEND...
  Open a disk file for read-only, read-write, read-write-append, or read-directory,
  respectively, as indicated by the last letter of the instruction name.

FOR loop_var = initial TO final STEP increment
  Execute a group of program instructions a certain number of times.

GLOBAL type var, ..., var
  Declare a variable to be global and specify the type of the variable.

GOTO label
  Perform an unconditional branch to the program step identified by the given label.

HALT
  Stop program execution and do not allow the program to be resumed.

IF logical_expr GOTO label
  Branch to the specified label if the value of a logical expression is TRUE (nonzero).

IF logical_expr THEN
  Conditionally execute a group of instructions (or one of two groups) depending on
  the result of a logical expression.

KEYMODE first_key, last_key = mode, setting
  Set the behavior of a group of keys on the manual control pendant.

LATCH ()
  Return a transformation value representing the location of the robot at the
  occurrence of the last external trigger.

LATCHED (select)
Return the status of the external trigger, and of the information it causes to be "latched".

**LOCAL** type variable, . . . , variable
Declare permanent variables that are defined only within the current program.

**MOVE** location
**MOVES** location
Initiate a robot motion to the position and orientation described by the given location.

**PAUSE**
Stop program execution but allow the program to be resumed.

**PENDANT** (select)
Return input from the manual control pendant.

**PROMPT** output_string, variable_list
Display a string on the system terminal and wait for operator input.

**REACT** signal_num, program, priority
Initiate continuous monitoring of a specified digital signal and automatically trigger a subroutine call if the signal properly transitions.

**REACTI** signal_num, program, priority
Initiate continuous monitoring of a specified digital signal. Automatically stop the current robot motion if the signal properly transitions and optionally trigger a subroutine call.

**READ** (lun, record_num, mode) var_list
Read a record from an open file, or from an attached device that is not file oriented.

**RETURN**
Terminate execution of the current subroutine and resume execution of the last-suspended program at the step following the CALL or CALLS instruction that caused the subroutine to be invoked.

**SET** location_var = location_value
Set the value of the location variable on the left equal to the location value on the right of the equal sign.

**SIG** (signal_num, . . . , signal_num)
Return the logical AND of the states of the indicated digital signals.

**SIGNAL** signal_num, . . . , signal_num
Turn “on” or “off” external digital output signals or internal software signals.

**SPEED** speed_factor
Set the nominal speed for subsequent robot motions.

**SPEED (select)**
Return one of the system motion speed factors.

**STOP**
Terminate execution of the current program cycle.

**TIMER** timer_number = time_value
Set the specified system timer to the given time value.

**TIMER (timer_number)**
Return the current time value (in seconds) of the specified system timer.

**UNTIL** expression
Indicate the end of a DO ... UNTIL control structure and specify the expression that is evaluated to determine when to exit the loop. The loop continues to be executed until the expression value is non-zero.

**WAIT.EVENT** mask, timeout
Suspend program execution until a specified event has occurred, or until a specified amount of time has elapsed.

**WHILE** condition **DO**
Initiate processing of a WHILE structure if the condition is TRUE, or skipping of the WHILE structure if the condition is initially FALSE.

**WRITE** (lun, record_num, mode) format_list
Write a record to an open file, or to an attached device that is file oriented.
APPENDIX C

UTAP Messages

Note: Bold and Italicized messages have been implemented in this Thesis Project. An asterisk indicates a message added to the specification for the purpose of this Project.

**GENERIC (42)**

US_STARTUP
US_SHUTDOWN
US_RESET
US_ENABLE
US_DISABLE
US_ESTOP
US_START
US_STOP
US_ABORT
US_HALT
US_INIT
US_HOLD
US_PAUSE
US_RESUME
US_ZERO
US_BEGIN_SINGLE_STEP
US_NEXT_SINGLE_STEP
US_CLEAR_SINGLE_STEP
US_BEGIN_BLOCK
US_END_BLOCK
US_BEGIN_PLAN
US_END_PLAN
US_USE_PLAN
US_BEGIN_MACRO
US_END_MACRO
US_USE_MACRO
US_BEGIN_EVENT
US_END_EVENT
US_MARK_BREAKPOINT
US_MARK_EVENT
US_GET_SELECTION_ID
US_POST_SELECTION_ID
US_USE_SELECTION
US_USE_AXIS_MASK
US_USE_EXT_ALGORITHM
US_LOAD_EXT_PARAMETER
US_GET_EXT_DATA_VALUE
US_POST_EXT_DATA_VALUE
US_SET_EXT_DATA_VALUE
US_LOAD_STATUS_TYPE
US_LOAD_STATUS_PERIOD
US_GENERIC_STATUS_REPORT

**ERRORS (9)**

US_ERROR_COMMAND_NOT_IMPLEMENTED
US_ERROR_COMMAND_ENTRY
US_ERROR_DUPLICATE_NAME
US_ERROR_BAD_DATA
US_ERROR_NO_DATA_AVAILABLE
US_ERROR_SAFETY_VIOLATION
US_ERROR_LIMIT_EXCEEDED

**US_ERROR_OVER_SPECIFIED**

**US_ERROR_UNDER_SPECIFIED**

**AXIS SERVO (34)**

US_AXIS_SERVO_USE_ANGLE_UNITS
US_AXIS_SERVO_USE_RADIAN_UNITS
US_AXIS_SERVO_USE_ABS_POSITION_MODE
US_AXIS_SERVO_USE_REL_POSITION_MODE
US_AXIS_SERVO_USE_ABS_VELOCITY_MODE
US_AXIS_SERVO_USE_REL_VELOCITY_MODE
US_AXIS_SERVO_USE_PID
US_AXIS_SERVO_USE_FEEDFORWARD_TORQUE
US_AXIS_SERVO_USE_CURRENT
US_AXIS_SERVO_USE_VOLTAGE
US_AXIS_SERVO_USE_STIFFNESS
US_AXIS_SERVO_USE_COMPLIANCE
US_AXIS_SERVO_USE_IMPEDEANCE
US_AXIS_SERVO_START_GRAVITY_COMPENSATION
US_AXIS_SERVO_STOP_GRAVITY_COMPENSATION

US_AXIS_SERVO_LOAD_DOF
US_AXIS_SERVO_LOAD_CYCLE_TIME
US_AXIS_SERVO_LOAD_PID_GAIN
US_AXIS_SERVO_LOAD_BETWEEN_LIMIT
US_AXIS_SERVO_LOAD_VELOCITY_LIMIT
US_AXIS_SERVO_LOAD_GAIN_LIMIT
US_AXIS_SERVO_LOAD_DAMPING_VALUES
US_AXIS_SERVO_HOME
US_AXIS_SERVO_SET_Breaks
US_AXIS_SERVO_CLEAR_Breaks
US_AXIS_SERVO_SET_TORQUE
US_AXIS_SERVO_SET_CURRENT
US_AXIS_SERVO_SET_VOLTAGE
US_AXIS_SERVO_SET_POSITION
US_AXIS_SERVO_SET_ACCELERATION
US_AXIS_SERVO_SET_FORCEs
US_AXIS_SERVO_JOG
US_AXIS_SERVO_JOG_STOP

**TOOL (14)**

US_SPINDLE_RETRACT_TRAVERSE
US_SPINDLE_LOAD_SPEED
US_SPINDLE_START_TURNING
US_SPINDLE_STOP_TURNING
US_SPINDLE_RETRACT
US_SPINDLE_Orient
US_SPINDLE_LOCK_Z
US_SPINDLE_USE_FORCE
US_SPINDLE_USE_NO_FORCE
US_Flow_START_MIST
US_FLOW_STOP_MIST  US_TLC_LOAD_PARAMETERS
US_FLOW_START_FLOOD
US_FLOW_STOP_FLOOD

SENSOR (45)
US_START_TRANSFORM
US_STOP_TRANSFORM
US_START_FILTER
US_STOP_FILTER
US_SENSOR_USE_MEASUREMENT_UNITS
US_SENSOR_LOAD_SAMPLING_SPEED
US_SENSOR_LOAD_FREQUENCY
US_SENSOR_LOAD_TRANSFORM
US_SENSOR_LOAD_FILTER

US_SENSOR_GET_READING
US_SENSOR_GET_ATTRIBUTES_READING
US_VECTOR_SENSOR_GET_READING
US_FT_SENSOR_POST_READING
US_SCALAR_SENSOR_POST_READING
US_VECTOR_SENSOR_POST_READING
US_2D_SENSOR_LOAD_ARRAY_PATTERN
US_2D_SENSOR_USE_ARRAY_TYPE
US_2D_SENSOR_GET_READING
US_2D_SENSOR_POST_READING
US_IMAGE_USE_FRAME_GRAB_MODE
US_IMAGE_USE_HISTOGRAM_MODE
US_IMAGE_USE_CENTROID_MODE
US_IMAGE_USE_GRAY_LEVEL_MODE
US_IMAGE_USE_THRESHOLD_MODE
US_IMAGE_USE_FRAME_GRAB_MODE
US_IMAGE_USE_HISTOGRAM_MODE
US_IMAGE_USE_CENTROID_MODE
US_IMAGE_USE_GRAY_LEVEL_MODE
US_IMAGE_USE_THRESHOLD_MODE
US_IMAGE_USE_FRAME_GRAB_MODE
US_IMAGE_USE_HISTOGRAM_MODE
US_IMAGE_USE_CENTROID_MODE
US_IMAGE_USE_GRAY_LEVEL_MODE
US_IMAGE_USE_THRESHOLD_MODE

PROGRAMMABLE_IO (11)
USPIO_ENABLE
USPIO_DISABLE
USPIO_SET_MODE
USPIO_LOAD_SCALE
USPIO_DATA_WRITE
USPIO_DATA_READ
USPIO_BIT_READ
USPIO_BIT_SET
USPIO_TOGGLE_BIT
USPIO_POST_DATA

TASK_LEVEL_CONTROL (78)
US_TLC_USE_JOINT_REFERENCE_FRAME
US_TLC_USE_CARTESIAN_REFERENCE_FRAME
US_TLC_USE_REPRESENTATION_UNITS
US_TLC_USE_ABSOLUTE_POSITIONING_MODE
US_TLC_USE_RELATIVE_POSITIONING_MODE
US_TLC_USE_WRIST_COORDINATE_FRAME
US_TLC_USE_TOOL_TIP_COORDINATE_FRAME
US_TLC_CHANGE_TOOL
US_TLC_USE_MODIFIED_TOOL_LENGTH_OFFSETS
US_TLC_USE_NORMAL_TOOL_LENGTH_OFFSETS
US_TLC_USE_NO_TOOL_LENGTH_OFFSETS
US_TLC_USE_KINEMATIC_RING_POSITIONING_MODE
US_TLC_START_FINE_MOTION
US_TLC_STOP_FINE_MOTION
US_TLC_START_MOVE_UNTIL_MOTION
US_TLC_STOP_MOVE_UNTIL_MOTION
US_TLC_START_STANOFFDISTANCE
US_TLC_STOP_STANOFFDISTANCE
US_TLC_START_FORCE_POSITIONING_MODE
US_TLC_STOP_FORCE_POSITIONING_MODE
US_TLC_LOAD_DOF
US_TLC_LOAD_CYCLE_TIME
US_TLC_LOAD_REPRESENTATION_UNITS
US_TLC_LOAD_LENGTH_UNITS
US_TLC_LOAD_RELATIVE_POSITIONING
US_TLC_ZERO_RELATIVE_POSITIONING
US_TLCZERO_PROGRAM_ORIGIN
US_TLCLOAD_KINEMATIC_RING_POSITIONING_MODE
US_TLC_LOAD_BASE_PARAMETERS
US_TLC_LOAD_TOOL_PARAMETERS
US_TLC_LOAD_OBJECT
US_TLC_LOAD_OBJECT_BASE
US_TLC_LOAD_OBJECT_OFFSET
US_TLC_LOAD_DELTA
US_TLC_LOAD_OBSTACLE_VOLUME
US_TLC_LOAD_NEIGHBORHOOD
US_TLC_LOAD_FEED_RATE
US_TLC_LOAD_TRAVERSE_RATE
US_TLC_LOAD_ACCELERATION
US_TLC_LOAD_JERK
US_TLC_LOAD_PROXIMITY
US_TLC_LOAD_CONTACT_FORCES
US_TLC_LOAD_JOINT_LIMIT
US_TLC_LOAD_CONTACT_FORCE_LIMIT
US_TLC_LOAD_CONTACT_TORQUE_LIMIT
US_TLC_LOAD_SENSOR_FUSION_POS_LIMIT
US_TLC_LOAD_SENSOR_FUSION_ORIENTATION_LIMIT
US_TLC_LOAD_SEGMENT_TIME
US_TLC_LOAD_TERMINATION_CONDITION
US_TLC_INCREMENT_VELOCITY
US_ATTRIBUTE_GET_MASS
US_ATTRIBUTE_GET_TEMPERATURE
US_ATTRIBUTE_GET_PRESSURE
US_ATTRIBUTE_GET_VISCOSITY
US_ATTRIBUTE_GET_LUMINANCE
US_ATTRIBUTE_GET_HUMIDITY
US_ATTRIBUTE_GET_FLOW
US_ATTRIBUTE_GET_HARDNESS
US_ATTRIBUTE_GET_ROUGHNESS
US_ATTRIBUTE_GET_GEOMETRY
US_ATTRIBUTE_GET_TOPOLOGY
US_ATTRIBUTE_GET_SHAPE
US_ATTRIBUTE_GET_PATTERN
US_ATTRIBUTE_GET_MATERIAL
US_ATTRIBUTE_GET_KINEMATICS

Messages Added for this Project
(Not in the UTAP Specification)

*US_GET_EXT_LOCATION_DATA
*US_SET_EXT_LOCATION_DATA
*US_GRIPPER_CLOSE
*US_GRIPPER_OPEN
*US_FT_SENSOR_DISABLE
*US_FT_SENSOR_ENABLE
*US_FT_SENSOR_MODE_SELECT
APPENDIX D

Trajectory Plots
After Tuning
Before Tuning

Figure D.1. Joint 1 Position Plots

Figure D.2. Joint 2 Position Plots
After Tuning ———
Before Tuning ———

Figure D.3. Joint 3 Position Plots

Current Gains ———

Figure D.4. Joint 4 Position Plots
Figure D.5. Joint 5 Position Plots

Figure D.6. Joint 6 Position Plots
APPENDIX E

Position Error Plots
Figure E.1. Joint 1 Error for Nominal Trajectory

Figure E.2. Joint 2 Error for Nominal Trajectory
Figure E.3. Joint 3 Error for Nominal Trajectory

Figure E.4. Joint 4 Error for Nominal Trajectory
Figure E.5. Joint 5 Error for Nominal Trajectory

Figure E.6. Joint 6 Error for Nominal Trajectory
Figure E.7. Joint 1 Error for Slow Trajectory

Figure E.8. Joint 2 Error for Slow Trajectory
Figure E.9. Joint 3 Error for Slow Trajectory

Figure E.10. Joint 4 Error for Slow Trajectory
Figure E.11. Joint 5 Error for Slow Trajectory

Figure E.12. Joint 6 Error for Slow Trajectory
Figure E.13. Joint 1 Error for Fast Trajectory

Figure E.14. Joint 2 Error for Fast Trajectory
Figure E.15. Joint 3 Error for Fast Trajectory

Figure E.16. Joint 4 Error for Fast Trajectory
Figure E.17. Joint 5 Error for Fast Trajectory

Figure E.18. Joint 6 Error for Fast Trajectory
APPENDIX F

TrijgenCycle Function Source Code
Original TrjjgenCycle Code

```c
int trjjgenCycle(local, task)
{slocal; sbTask_t *task;
  int flag, i, n = *(local->N dof), type = local->type;
  float *qmez = local->Qmez, *qref = local->Qref;
  double nt, temp;
  double *qdelta = local->qdelta, *qinit = local->qinit;

  /* Calculate the next set of joint positions. */
  if ((nt = local->stepnum++ * local->stepsize) > 1.0)
    temp = 1.0;
  else
    temp = profilefunc(nt, type);

  for (i = 0; i < n; ++i)
    *(qref++) = (float) (*(qini++ + temp * *(qdelta++));

  /* See if it is time to stop. Ideally, when nt == 1.0, the robot */
  /* has reached the desired position, but just to be sure, check the */
  /* actual position against the desired position before turning off. */
  if (nt > 1.0)
    qref = local->qref;
    flag = 1;
    for (i = 0; i < n; ++i)
      if (!fabs(*(qref++) - *(qmez++)) > EPSILON)
        flag = 0;

      if (flag)
        return SRS_OFF;

  /* Return at the end of each cycle. */
  return I_OK;
}
```

Modified TrjjgenCycle Code

```c
int trjjgenCycle(local, task)
{slocal; sbTask_t *task;
  int flag, i, n = *(local->N dof), type = local->type;
  float *qmez = local->Qmez, *qref = local->Qref;
  double nt, temp;
  double *qdelta = local->qdelta, *qinit = local->qinit;

  for (i = 0; i < n; ++i)
    *(qref++) = (float) (*(qini++ + temp * *(qdelta++));

  /* Return at the end of each cycle. */
  return I_OK;
}
```
APPENDIX G

Original Palletizing Application V+ Source Code
.PROGRAM nonutap.demo()

; Name: nonutap.demo
; Author: Capt Matthew L. June - GCS-96D

; Abstract: This is the main program that starts the pallet, force1,
; and force2 programs. It prompts the user for number of rows and
; columns on a pallet, the approach and depart height, and the number
; of the pallet with parts on it.

AUTO $rows, $cols, $ht, rows, cols, ht, $pal, pal, flun, $fname
FINE ALWAYS

; Clear the screen

TYPE /CS0, /U25

; LUN for disk I/O

flun = 5

; Attach to LUN

ATTACH (flun) "disk"

; Prompt for audit trail file name

PROMPT "Enter the file name for the audit trail (include drive
letter): ", $fname

TYPE

; Open the file in append mode

OPENA (flun, 0, 0) $fname

; Prompt for the number of rows

10 PROMPT "Enter the number of rows on the pallet: ", $rows
rows = VAL($rows)
IF ((rows < 1) OR (rows > 5)) GOTO 10

; Prompt for the number of columns

20 PROMPT "Enter the number of columns on the pallet: ", $cols
cols = VAL($cols)
IF ((cols < 1) OR (cols > 5)) GOTO 20

; Prompt for the approach and depart height

PROMPT "Enter an approach height: ", $ht
ht = VAL($ht)

; Prompt for the pallet number with parts on it

30 PROMPT "Enter the number of the pallet with parts on it: ", $pal
pal = VAL($pal)
IF ((pal < 1) OR (pal > 2)) GOTO 30

; Call the palletizing program

CALL pallet(rows, cols, pal, ht, flun)

IF pal == 1 THEN
    pal = 2
ELSE
    pal = 1
END

; Call the first force program

CALL force1(pal, rows, cols, flun)

; Call the second force program

CALL force2(pal, flun)

; Close and detach file access

CLOSE (flun)
DETACH (flun)

RETURN

.END

.PROGRAM audit(pick, place, row, col, flun)

; Name: audit
; Author: Capt Matthew L. June - GCS-96D

; Abstract: This program writes pick and place location information
; and row and column information to a disk file specified by a logical
; unit number.

AUTO pic[5], plac[5], i

; Get the six values from locations pick and place

DECOMPOSE pic[] = pick
DECOMPOSE plac[] = place

; Write the date, time, row, and col info to the audit file
WRITE (flun) "$TIME()"
WRITE (flun) "Row = ", row, " Col = ", col

; Write the pick location info to the audit file
WRITE (flun) "The pick location coordinates are:"
WRITE (flun) ", /S"
FOR i = 0 TO 5
WRITE (flun) pic[i], /S
END
WRITE (flun) ""

; Write the place location info to the audit file
WRITE (flun) "The place location coordinates are:"
WRITE (flun) ", /S"
FOR i = 0 TO 5
WRITE (flun) plac[i], /S
END
WRITE (flun) ""

RETURN

.PROGRAM display.info()
; Name: display.info
; Author: Capt Matthew L. June - GCS-96D
; Abstract: When a software signal is activated, this program displays
; various system values to the screen.
; While the RC Task is running
WHILE SIG(2100) DO
; Wait for a signal
WAIT (SIG(2101) OR SIG(-2100))
; If it was the display signal
IF SIG(2101) THEN
; Clear the screen
AUTO curr.loc
; While the RC Task is running
WHILE SIG(2100) DO
; Wait for a signal
WAIT SIG(2102) OR SIG(-2100)
; If the signal was for coordinate display
IF SIG(2102) THEN
SST curr.loc = HERE

.PROGRAM coords.info()
; Name: coords.info
; Author: Capt Matthew L. June - GCS-96D
; Abstract: When a software signal is activated, this program displays
; the manipulator's current world coordinate system values to the
; screen.
IF SWITCH(CF) THEN
  TYPE "Enabled"
ELSE
  TYPE "Disabled"
END

TYPE "Null / NoNull setting for next motion: ", /S
IF CONFIG(3) HEND 4 THEN
  TYPE "NONULL"
ELSE
  TYPE "NULL"
END

TYPE "Fine / Coarse setting for next motion: ", /S
IF CONFIG(3) HEND 2 THEN
  TYPE "COARSE"
ELSE
  TYPE "FINE"
END

END

RETURN

.PROGRAM mcp.main()

; Name: mcp.main
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program monitors the manual control pendant for input
; and, based on the input, activates certain software signal or calls
; other programs.

AUTO quit, mcp
mcp = 1
quit = FALSE

ATTACH (mcp)

KEYMODE 1, 3 = 0  ; Keyboard mode
KEYMODE 4, 5 = 1  ; Toggle mode

WHILE SIG(2100) DO
  DO
    CALL mcp.disp.menu()
    CASE TRUE OF
      VALUE PENDANT(1): ; Stop button
        WRITE (mcp) $CHR(31), $CHR(1), /S
        CALL mcp.main.quit.quit()
        WRITE (mcp) $CHR(28), $CHR(1), /S
      VALUE PENDANT(2): ; React button
        WRITE (mcp) $CHR(31), $CHR(2), /S
        SIGNAL 2004
        WAIT [SIG(-2004) OR SIG(-2100)]
        WRITE (mcp) $CHR(28), $CHR(2), /S
      VALUE PENDANT(3): ; React button
        WRITE (mcp) $CHR(31), $CHR(3), /S
        SIGNAL 2003
        WAIT [SIG(-2003) OR SIG(-2100)]
        WRITE (mcp) $CHR(28), $CHR(3), /S
    END
  END
END

.PROGRAM mcp.disp.menu()

; Name: mcp.disp.menu
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program writes a menu to the manual control pendant
; display.

AUTO mcp
mcp = 1

; Clear the display and write the top line
WRITE (mcp) $CHR(12), $CHR(18), $CHR(16), "MAIN MENU", /S

; Write the menu options
WRITE (mcp) $CHR(18), $CHR(41), /S
WRITE (mcp) "Cycle", $CHR(9), "Posit", $CHR(9), /S
WRITE (mcp) "React", $CHR(9), "Reacti", $CHR(9), " Stop", /S

RETURN

.END
IF NOT quit THEN

IF PENDANT(4) THEN ; Posit button
  SIGNAL 2102
  WAIT (NOT PENDANT(4)) OR SIG(-2100)
  SIGNAL -2102
END

IF PENDANT(5) THEN ; Cycle info button
  SIGNAL 2101
  WAIT (NOT PENDANT(5)) OR SIG(-2100)
  SIGNAL -2101
END

END
UNTIL quit OR SIG(-2100)
END

; Detach the MCP
DETACH (mcp)
RETURN

; PROGRAM mcp.main.quit
; Name: mcp.main.quit
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program displays the quit menu on the manual control
; pendant and activates a software signal if the "yes" button is
; pressed.
AUTO button, mcp
quit = FALSE
mcp = 1

; Set softkeys 1 and 2 to keyboard mode
KEYMODE 1, 2 = 0

; Display sub-menu and start the "NO" option blinking
WRITE (mcp) $CHR(12), "Quit. Are you sure?"
WRITE (mcp) $CHR(9), $CHR(9), $CHR(9), * YES*, /S
WRITE (mcp) $CHR(9), $CHR(2), * NO*, $CHR(3), /S
button = PENDANT(0)

; Signal 2005 and set quit to true if verified
IF button == 2 THEN
  SIGNAL 2005
  quit = TRUE
END

RETURN

; PROGRAM pallet(rows, cols, pal, ht, flun)
; Name: pallet
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This is the main program for the palletizing application.
; It initializes the reactions to certain signals, launches the other
; programs, and moves the parts from one pallet to another.
; Signals used:
; 2100 - runsig
; 2101 - Cycle info display
; 2102 - Position info display
; 2003 - React, move to safe and resume exec when return is pressed
; 2004 - React, move to safe and go back to where leftoff when
;        return is pressed
; 2005 - React, Halt program
AUTO $speed, speed, i, j

; Prompt for the operating speed
10 PROMPT *Enter the speed for this operation: *, $speed
   speed = VAL($speed)
IF ((speed < 1) OR (speed > 100)) GOTO 10

; set timer 2 for testing purposes
TIMER 2 = 0

; Initialize signals
SIGNAL -2101, -2102, -2003, -2004, -2005

; Signal that program is running
RUNSIG 2100

; Setup reaction to signals 2003, 2004, and 2005
.PROGRAM pnp(pick, place, ht)

; Name: pnp
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This is a simple pick and place program. It is given the
; pick and place locations and a height for approaches and departures.
; It obtains a part from the pick location and deposits it at the place
; location.
AUTO grip.sig.open, grip.sig.close, grip.delay

; Set gripper signals
    grip.sig.open = -1
    grip.sig.close = 1
    grip.delay = 0.5

; move to the pick location
    SIGNAL grip.sig.open
    APPRO pick, ht
    MOVE pick
    BREAK
    SIGNAL grip.sig.close
    WAIT.EVENT 0, grip.delay

; move to a location clear of the pick location
    DEPART ht

; move to the place location
    APPRO place, ht
    MOVE place
    BREAK
    SIGNAL grip.sig.open
    WAIT.EVENT 0, grip.delay

; move to a location clear of the place location
    DEPART ht

; END

.END

.PROGRAM safe.goback()

; Name: safe.goback
; Author: Capt Matthew L. June - GCS-96D

; END
; Abstract: This program is used in conjunction with a react statement
; in another program. It moves the manipulator to a safe location.
; When the user presses the return key, it moves back to the location
; where it is left off and continues the motion to the destination.

AUTO left.off, going.to, $cont

; Save locations
SET left.off = HERE
SET going.to = DEST

; Move to safe location
MOVE safe

; Clear the screen
TYPE /CS0, /U25

; Prompt to continue
TYPE "Robot has been moved to a safe position"
TYPE "Press return to go back to where the robot"
PROMPT "left off and continue execution", $cont

; Move to where the robot stopped
APPRO left.off, 20
MOVE left.off

; Move to the interrupted destination
MOVE going.to

; Clear the react signal
SIGNAL -2004

; Reset the react signal
REACTI 2004, safe.goback
RETURN

.END

.PROGRAM stop.prog()
; Name: stop.prog
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program moves the manipulator to a safe location
; and halts execution of the program.
MOVE safe
BREAK
HALT
RETURN
.END

.PROGRAM acquire.part(pallet, i, j)
; Name: acquire.part
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program moves the manipulator to a position
determined from the pallet number and i and j offsets. Once there,
pick up a part and move to a position 75mm above the pick location.

AUTO pick

SPEED 100

IF pallet == 1 THEN
  SET pick = pal.1:TRANS(50*i,50*j)
ELSE
  SET pick = pal.2:TRANS(50*i,50*j)
END

SIGNAL -1
WAIT,EVENT 0, 0.5

APPRO pick, 75
MOVE pick
BREAK

SIGNAL 1
WAIT,EVENT 0, 0.5

DEPART 75

RETURN

.END

.PROGRAM force.move

; Name: force.move
; Author: Capt Matthew L. June - GCS-96D
; Abstract: Enables guarded mode force sensing and attempts to move
to the goal location. Returns trip status of the sensor, forces at
the time of the trip, and the trip location.

IF zero_force THEN
  FORCE.OFFSET (1)
END

FORCE.MODE (1)
MOVE goal.loc
BREAK

trip = LATCHED(1)
IF trip THEN
  FORCE.READ (1) forces[]
  SET trip.pos = LATCH(1)
END

FORCE.MODE (-1)

RETURN

.END

.PROGRAM force1(pallet, row, col, flun)

; Name: force1
; Author: Capt Matthew L. June - GCS-96D
; Abstract: Specifies a vertical insertion, where if the forces are
too high the insertion is jammed (force > 2 lb). A high-speed
approach to 100mm above the assembly location "goal" is attempted
first, followed by a fast approach to 20mm above the insertion
location and a slow guarded move to the goal location. Using a
second, low approach point minimizes the length of the relatively
slow guarded move.

The program acquires a part from a pallet and attempts to "insert"
it. If the insertion fails, the part is returned to the pallet and
another part is tried. If the insertion succeeds, the part is
released, the manipulator moves to a safe location, and the program
terminates.

The initial insertion location is below the table surface. Therefore
a failure is guaranteed. The insertion location is incremented up by
1mm for each iteration until the part is placed on the table surface.

AUTO trip, trip.pos, offset, quit, i, j
GLOBAL forces[]

; Initialize variables
offset = -1
quit = FALSE
trip = FALSE
i = 0
j = 0

; Initialize force sensor and enable protected mode
CALL force.init()

; Set force limits but don't enable guarded mode
FORCE.MODE (-1) "H12, 2
MOVE safe
BREAK

; Write initial lines to audit file and screen
TYPE "START OF FORCE1 INFORMATION"
TYPE "attempting first part"
WRITE (flun) "START OF FORCE1 INFORMATION"
WRITE (flun) "attempting first part"

; Start operation to 'insert' a part
WHILE NOT quit DO
    CALL acquire.part(pallet, i, j)
    SPEED 100
    APPRO goal1:TRANS(0,0,-offset), 100
    BREAK

    SPEED 50
    APPRO goal1:TRANS(0,0,-offset), 20
    BREAK

    SPEED 5
    CALL force.move(goal1:TRANS(0,0,-offset), TRUE, trip, forces[], trip.pos)
    BREAK
    IF trip THEN ; guard force limit exceeded

    TYPE "Insertion jammed",
    DISTANCE(goal1:TRANS(0,0,-offset),trip.pos), " mm from goal"
    TYPE "Z direction force at time of jam: ", forces[2]
    TYPE WRITE (flun) "Insertion jammed",
    DISTANCE(goal1:TRANS(0,0,-offset),trip.pos), " mm from goal"
    WRITE (flun) "Z direction force at time of jam: ", forces[2]
    WRITE (flun)

    DEPART 75
    CALL replace.part(pallet, i, j) ; return the part
    offset = offset+1
    IF (i <= row-1) THEN ; increment to next part
        IF j < col-1 THEN
            j = j+1
        ELSE
            i = i+1
            j = 0
        END ; if-else
    END ; if
    IF i == row THEN ; last part has been tried
        TYPE "Last part failed, part cannot be inserted"
        TYPE WRITE (flun) "Last part failed, part cannot be inserted"
        WRITE (flun)
        MOVE safe
        BREAK
        quit = TRUE
    ELSE ; last part hasn't been tried
        TYPE "Attempting next part"
        WRITE (flun) "Attempting next part"
    END ; if-else
    ELSE ; successful insert
        TYPE "Insertion succeeded."
        TYPE WRITE (flun) "Insertion succeeded."
        WRITE (flun)
SIGNAL -1
WAIT.EVENT 0, 0.5
DEPART 80
MOVE safe
BREAK
quit = TRUE
END ; if-else
END ; while
RETURN

.END

.PROGRAM force2(pallet, flun)

; Name: force2
; Author: Capt Matthew L. June - GCS-963
; Abstract: This program acquires a part from a pallet and sets it on
; the table surface. It accomplishes this by moving the part to a
; position above the surface and repeatedly moving the part down 1mm
; until the Z direction force exceeds 2 lbs. At this point, the part
; is released and the manipulator moves to a safe location

AUTO trip, trip.pos, offset, i

; Initialize variables
i = 1
offset = 0
trip = FALSE

; Initialize force sensor and enable protected mode
CALL force.init()

; Set force limits but don't enable guarded mode
FORCE.MODE (-1) "H12, 2
MOVE safe
CALL acquire.part(pallet, 3, 1)

SPEED 100
APPRO goal2, 100
BREAK

SPEED 50
APPRO goal2, 20

BREAK
; Write initial lines to audit file
TYPE "START OF FORCE2 INFORMATION"
TYPE
WRITE (flun) "START OF FORCE2 INFORMATION"
WRITE (flun)

; Start the operation to place the part on the surface
WHILE NOT trip DO
SPEED 5
CALL force.moveg(goal2:TRANS(0,0,-offset), TRUE, trip,
forces[], trip.pos)
BREAK

IF NOT trip THEN ; part is not touching the surface
TYPE "Failed attempt ", i
WRITE (flun) "Failed attempt ", i
offset = offset-1
i = i+1
ELSE ; part is touching the surface
SIGNAL -1
WAIT.EVENT 0, 0.5
TYPE "Succeeded on attempt", i
TYPE "Actual position is", DISTANCE(goal2,trip.pos),
; " mm from the first attempt"
TYPE
WRITE (flun) "Succeeded on attempt", i
WRITE (flun) "Actual position is",
DISTANCE(goal2,trip.pos),
; " mm from the first attempt"
WRITE (flun)
DEPART 80
MOVE safe
BREAK
END ; if-else
END ; while
RETURN

.END
.PROGRAM replace_part(pallet, i, j)

; Name: replace_part
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program starts with a part in the gripper. It moves
; the part to a location specified by a pallet number and i and j
; offsets. Then, it releases the part and moves to a location 75mm
; above the part.

AUTO place

SPRER 100

IF pallet == 1 THEN
   SET place = pal.1:TRANS(50*i,50*j)
ELSE
   SET place = pal.2:TRANS(50*i,50*j)
END

APPRO place, 75
MOVE place
BREAK

SIGNAL -1
WAIT.EVENT 0, 0.5

DEPART 75
RETURN

.END
APPENDIX H

UTAP-compliant Palletizing Application V+ Source Code
PROGRAM utap.demo()

; Name: utap.demo
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This is the UTAP-compliant main program that starts the
; pallet, force1, and force2 programs. It prompts the user for number
; of rows and columns on a pallet, the approach and depart height, and
; the number of the pallet with parts on it.
AUTO $rows, $cols, $ht, $pal, rows, cols
CALL init_ok()
CALL tl_str_fine_mot("ALL")
; Clear the screen
CALL post_ext_data(screen, "/C50, /U25")
; Enable append mode disk access
CALL pi_enable(disk)
CALL pi_set_mode(disk, "0,0")
; Prompt for the number of rows
10 CALL get_ext_data(keyboard, "Enter the number of rows on the
pallet: ", $rows)
   rows = VAL($rows)
   IF ((rows < 1) OR (rows > 5)) GOTO 10
; Prompt for the number of columns
20 CALL get_ext_data(keyboard, "Enter the number of columns on the
pallet: ", $cols)
   cols = VAL($cols)
   IF ((cols < 1) OR (cols > 5)) GOTO 20
; Prompt for the approach and depart height
CALL get_ext_data(keyboard, "Enter an approach height: ", $ht)
; Prompt for the pallet number with parts on it
30 CALL get_ext_data(keyboard, "Enter the number of the pallet with
parts on it: ", $pal)
   IF (($pal <> "1") AND ($pal <> "2")) GOTO 30
; Call the palletizing program
CALL td_exec_prog("pallet("+$rows+", "$cols+", "$pal+",
            "+$ht+)")
   IF $pal = "1" THEN
      $pal = "2"
   ELSE
      $pal = "1"
   END
; Call the first force program
CALL td_exec_prog("force1("+$pal+", "$rows+", "$cols+")")
; Call the second force program
CALL td_exec_prog("force2("+$pal+")")
; Close and detach file access
CALL pi_disable(disk)
RETURN

.PROGRAM audit(row, col)
; Name: audit
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program writes pick and place location information
; and row and column information to a disk file specified by a logical
; unit number.
; This program is UTAP-compliant
AUTO pick, place, pic[5], plac[5], i
; Get the pick and place locations
CALL get_ext_loc_dat("location_1", pick)
CALL get_ext_loc_dat("location_2", place)
; Get the six values from locations pick and place
DECOMPOSE pic[] = pick
DECOMPOSE plac[] = place
; Write the date, time, row, and col info to the audit file
CALL post_ext_data(disk, "$TIME()")
CALL post_ext_data(disk, "row = "+$SNCR$(row) +
            "+$SNCR$(col) " +col = +$SNCR$(col)"
; Write the pick location info to the audit file
CALL post_ext_data(disk, "The pick location coordinates are:")
CALL post_ext_data(disk, "*/")
FOR i = 0 TO 5
   CALL post_ext_data(disk, $ENCEOD(pixel[i])+"*/")
END
CALL post_ext_data(disk, ")")

; Write the place location info to the audit file
CALL post_ext_data(disk, "The place location coordinates are:")
CALL post_ext_data(disk, "*/")
FOR i = 0 TO 5
   CALL post_ext_data(disk, $ENCEOD(place[i])+"*/")
END
CALL post_ext_data(disk, ")")
RETURN

.PROGRAM coords.info()
; Name:     coords.info
; Author:   Capt Matthew L. June - GCS-96D
; Abstract: When a software signal is activated, this program displays
; the manipulator's current world coordinate system values to the
; screen.
; This program is UTAP-compliant
AUTO curr.loc, running, coord_info
; While the RC Task is running
CALL pi_bit_read(signal, 2100, running)
WHILE running DO
; Wait for a signal
CALL hold("signal 2102 -2100")
; If the signal was for coordinate display
CALL pi_bit_read(signal, 2102, coord_info)
IF coord_info THEN
   SET curr.loc = HERE
   CALL post_ext_data(screen, ")")
   CALL post_ext_data(screen, ")World Coordinate System X
value: /")
   CALL post_ext_data(screen, $ENCEOD(DX(curr.loc))
   CALL post_ext_data(screen, ")World Coordinate System Y
value: /")
   CALL post_ext_data(screen, $ENCEOD(DY(curr.loc))
   CALL post_ext_data(screen, ")World Coordinate System Z
value: /")
   CALL post_ext_data(screen, $ENCEOD(DZ(curr.loc))
   CALL post_ext_data(screen, ")")
END
END
RETURN

.PROGRAM display.info()
; Name:     display.info
; Author:   Capt Matthew L. June - GCS-96D
; Abstract: When a software signal is activated, this program displays
; various system values to the screen.
; This program is UTAP-compliant
AUTO running, disp_info, cycle_time, data
; While the RC Task is running
CALL pi_bit_read(signal, 2100, running)
WHILE running DO
; Wait for a signal
CALL hold("signal 2101 -2100")
; If it was the display signal
CALL pi_bit_read(signal, 2101, disp_info)
IF disp_info THEN
   Clear the screen
   CALL post_ext_data(screen, ")C50, /U25")
CALL pi_bit_read(timer, 1, cycle_time)  
CALL post_ext_data(screen, "Time since start")  
CALL post_ext_data(screen, *"$ENCODE(cycle_time)"")  
CALL post_ext_data(screen, "Monitor Perm Curr Next")  
CALL ok_attrib_query("Monitor Speed", $data)  
CALL post_ext_data(screen, *"$data"] /"S")  
CALL ok_attrib_query("Permanent Speed", $data)  
CALL post_ext_data(screen, *"$data"] /"S")  
CALL ok_attrib_query("Current Speed", $data)  
CALL post_ext_data(screen, *"$data"] /"S")  
CALL ok_attrib_query("Next Speed", $data)  
CALL post_ext_data(screen, *"$data")  
CALL post_ext_data(screen, **)  
CALL ok_attrib_query("Gripper Delay", $data)  
CALL post_ext_data(screen, "The gripper delay: "$data")  
CALL ok_attrib_query("Acceleration", $data)  
CALL post_ext_data(screen, "The acceleration: "$data")  
CALL ok_attrib_query("Deceleration", $data)  
CALL post_ext_data(screen, "The deceleration: "$data")  
CALL ok_attrib_query("Continuous Path", $data)  
CALL post_ext_data(screen, "Continuous path is "$data")  
CALL post_ext_data(screen, **)  
CALL ok_attrib_query("Null-NotNull", $data)  
CALL post_ext_data(screen, "Null - Null setting for next motion: "$data")  
CALL post_ext_data(screen, **)  
CALL ok_attrib_query("Fine-Coarse", $data)  
CALL post_ext_data(screen, "Fine - Coarse setting for next motion: "$data")  
END  
pˉ  
END  
RETURN

PROGRAM mcp.main()  
; Name: mcp.main  
; Author: Capt Matthew L. June - GCS-96D  
; Abstract: This program monitors the manual control pendant for input and, based on the input, activates certain software signal or calls other programs.  
; This program is UTAP-compliant  
AUTO running, button_value  
quit = FALSE  
CALL pi_bit_read(signal, 2100, running)  
CALL pi_enable(mcp)  
CALL pi_bit_set(mcp, 1, 0)  
CALL pi_bit_set(mcp, 2, 0)  
CALL pi_bit_set(mcp, 3, 0)  
CALL pi_bit_set(mcp, 4, 1)  
CALL pi_bit_set(mcp, 5, 1)  
WHILE running DO  
DO  
CALL td_execProg(\"mcp DISP menu\")  
CALL pi_bit_read(mcp, 1, button_value)  
;Stop button  
IF button_value THEN

.PROGRAM mcp DISP menu()  
; Name: mcp DISP menu  
; Author: Capt Matthew L. June - GCS-96D
CALL post_ext_data(mcp, "$CHR(31), $CHR(1)"
CALL td_exec_prog("mcp.main.quit()")
CALL post_ext_data(mcp, "$CHR(28), $CHR(1)"
END

CALL pi_bit_read(mcp, 2, button_value) ;React button
IF button_value THEN
CALL post_ext_data(mcp, "$CHR(31), $CHR(2)"
CALL pi_bit_set(signal, 2004, 1)
CALL hold("signal -2004 -2100")
CALL post_ext_data(mcp, "$CHR(28), $CHR(2)"
END

CALL pi_bit_read(mcp, 3, button_value) ;React button
IF button_value THEN
CALL post_ext_data(mcp, "$CHR(31), $CHR(3)"
CALL pi_bit_set(signal, 2003, 1)
CALL hold("signal -2003 -2100")
CALL post_ext_data(mcp, "$CHR(28), $CHR(3)"
END

IF NOT quit THEN
CALL pi_bit_read(mcp, 4, button_value)
IF button_value THEN ;Posit button
CALL pi_bit_set(signal, 2102, 1)
CALL hold("signal -2100 pendant -4")
CALL pi_bit_set(signal, 2102, -1)
END

CALL pi_bit_read(mcp, 5, button_value)
IF button_value THEN ;Cycle info button
CALL pi_bit_set(signal, 2101, 1)
CALL hold("signal -2100 pendant -5")
CALL pi_bit_set(signal, 2101, -1)
END

END
CALL pi_bit_read(signal, 2100, running)
UNTIL quit OR (NOT running)
END

; Detach the MCP
CALL pi_disable(mcp)
RETURN

.PROGRAM mcp.main.quit()
; Name: mcp.main.quit
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program displays the quit menu on the manual control
; pendant and activates a software signal if the *yes* button is
; pressed.
; This program is UTAP-compliant
AUTO button
; Set softkeys 1 and 2 to keyboard mode
CALL pi_bit_set(mcp, 1, 0)
CALL pi_bit_set(mcp, 2, 0)
; Display sub-menu and start the *NO* option blinking
CALL post_ext_data(mcp, "$CHR(12), Quit. Are you sure?"
CALL post_ext_data(mcp, "$CHR(18), $CHR(41)"
CALL post_ext_data(mcp, "$CHR(9), $CHR(9), $CHR(9), YES"
CALL post_ext_data(mcp, "$CHR(9), $CHR(2), NO, $CHR(3)"
CALL pi_bit_read(mcp, 0, button)
; Signal 2005 and set quit to true if verified
IF button == 2 THEN
CALL pi_bit_set(signal, 2005, 1) ; Signal to halt the robot
quit = TRUE
END
RETURN

.PROGRAM pallet(rows, cols, pal, ht)
; Name: pallet
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This is the main program for the palletizing application.
; It initializes the reaction to certain signals, launches the other
; programs, and moves the parts from one pallet to another.
; This program is UTAP-compliant
; Signals used:
; / 2100 - runsig
; / 2101 - Cycle info display
; 2102 - Position info display
; 2003 - React, move to $safe and resume exec when return is pressed
; 2004 - Reacti, move to $safe and go back to where leftoff when
; return is pressed
; 2005 - Reacti, Halt program

AUTO $speed, speed, i, j

; Prompt for the operating speed

10 CALL get_ext_data(keyboard, "Enter the speed for this
operation: ", $speed)
speed = VAL($speed)
IF ((speed < 1) OR (speed > 100)) GOTO 10

; Set timer 2 for testing purposes

TIMER 2 = 0

; Initialize signals

CALL pi_bit_set(signal, 2101, -1)
CALL pi_bit_set(signal, 2102, -1)
CALL pi_bit_set(signal, 2003, -1)
CALL pi_bit_set(signal, 2004, -1)
CALL pi_bit_set(signal, 2005, -1)

; Signal that program is running

CALL pi_set_mode(signal, "RUNSIG 2100")

; Setup reaction to signals 2003, 2004, and 2005

CALL pi_set_mode(signal, "REACT 2003, safe.resume")
CALL pi_set_mode(signal, "REACTI 2004, safe.goback")
CALL pi_set_mode(signal, "REACTI 2005, stop.prog")

; Execute programs

CALL ps_select_agent(3, "mcp.main()")
CALL ps_select_agent(4, "display.info()")
CALL ps_select_agent(5, "coords.info()")

; Establish two frames of reference for Pallet 1 and Pallet 2

SET pal.1 = FRAME(loc1, loc2, loc3, loc1)
SET pal.2 = FRAME(loc4, loc5, loc6, loc4)

CALL as_set_velocity(speed)

CALL post_ext_data(disk, "START OF FALLOUTING INFORMATION")
CALL post_ext_data(disk, "")

CALL as_set_position(safe)
CALL pi_bit_set(timer, 1, 0)
FOR i = 0 TO rows-1
    FOR j = 0 TO cols-1
        IF (pal == 1) THEN
            CALL set_ext_loc_dat("location.1",
pal.1:TRANS[50*1,50*j])
        ELSE
            CALL set_ext_loc_dat("location.1",
pal.1:TRANS[50*1,50*j])
        END
        CALL td_exec_prog("*pnp(*$ENCODE(ht)*")
    CALL td_exec_prog("*audit(*$ENCODE(i)*",
        +$ENCODE(j)*")
    END
END

; Move to a safe position

CALL as_set_position(safe)
RETURN

.END

.PROGRAM pnp(ht)

; Name: pnp
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This is a simple pick and place program. It is given the
; pick and place locations and a height for approaches and departures.
; It obtains a part from the pick location and deposits it at the place
; location.

; This program is UTAAP-compliant

AUTO pick, place
; get pick and place locations
    CALL get_ext_loc_dat("location_1", pick)
    CALL get_ext_loc_dat("location_2", place)

; move to the pick location
    CALL gripper_open()
    CALL as_set_position(pick:TRANS(0,0,-ht))
    CALL as_set_position(pick)
    BREAK
    CALL gripper_close()

; move to a location clear of the pick location
    CALL as_set_position(pick:TRANS(0,0,-ht))

; move to the place location
    CALL as_set_position(place:TRANS(0,0,-ht))
    CALL as_set_position(place)
    BREAK
    CALL gripper_open()

; move to a location clear of the place location
    CALL as_set_position(place:TRANS(0,0,-ht))
    RETURN

.END

.PROGRAM safe.goback()

; Name:    safe.goback
; Author:  Capt Matthew L. June - GCS-96D
; Abstract: This program used in conjunction with a reactl statement
; in another program. It moves the manipulator to a safe location.
; When the user presses the return key, it moves back to the location
; where is left off and continues the motion to the destination.
; This program is UTAP-compliant

AUTO left.off, going.to, $cont

; Save locations
    SBT left.off = HERE
    SBT going.to = DEST

; Move to safe location
    CALL as_set_position(safe)
; Clear the screen
    CALL post_ext_data(screen, "^C50, /U25")

; Prompt to continue
    CALL post_ext_data(screen, "Robot has been moved to a
safe position")
    CALL post_ext_data(screen, "Press return to go back to
where the robot")
    CALL get_ext_data(keyboard, "left off and continue execution", $cont)

; Move to where the robot stopped
    CALL as_set_position(left.off:TRANS(0,0,-20))
    CALL as_set_position(left.off)

; Move to the interrupted destination
    CALL as_set_position(going.to)
; Clear the react signal
    CALL pi_bit_set(signal, 2004, -1)
; Reset the react signal
    CALL pi_set_mode(signal, "REACTI 2004, safe.goback")

RETURN

.END

.PROGRAM safe.resume()

; Name:    safe.resume
; Author:  Capt Matthew L. June - GCS-96D
; Abstract: This program used in conjunction with a react statement
; in another program. It moves the manipulator to a safe location.
; When the user presses the return key, it moves the manipulator to
; the destination.
; This program is UTAP-compliant

LOCAL $cont

; Move to a safe position
CALL as_set_position(safe)
; Clear the screen
CALL post_ext_data(2, "/C50, /U25")
; Prompt to continue
CALL post_ext_data(screen, "Robot has been moved to a safe position")
CALL get_ext_data(keyboard, "Press enter to continue", $cont)
; Clear the react signal
CALL pi_bit_set(signal, 2003, -1)
; Reinstate the react
CALL pi_set_mode(signal, "REACT 2003, safe.resume")
RETURN
.END

.PROGRAM stop.prog()
; Name: stop.prog
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program moves the manipulator to a safe location and halts execution of the program.
; This program is UTAP-compliant
CALL as_set_position(safe)
BREAK
HALT
RETURN
.END

.PROGRAM acquire.part(pallet, i, j)
; Name: acquire.part
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program moves the manipulator to a position determined from the pallet number and i and j offsets. Once there, pick up a part and move to a position 75mm above the pick location.

; This program is UTAP-compliant
AUTO pick
CALL as_set_velocity(100)
IF pallet == 1 THEN
SET pick = pallet:TRANS(50*i,50*j)
ELSE
SET pick = pallet:TRANS(50*i,50*j)
ENDIF
CALL gripper_open()
CALL as_set_position(pick:TRANS(0,0,-75))
CALL as_set_position(pick)
BREAK
CALL gripper_close()
CALL as_set_position(pick:TRANS(0,0,-75))
RETURN
.END

.PROGRAM force.init()
; Name: force.init
; Author: Capt Matthew L. June - GCS-96D
; Abstract: Initialize the force sensor to its default state and enable protect mode with the trip condition set to the 2-force rating.
; This program is UTAP-compliant
AUTO ratings[5]
CALL ft_sc_mode_sel(21, "")
CALL sc_get_att_read("ratings", ratings[])
CALL ft_sc_mode_sel(3, $ENABLE(ratings[2]))
CALL ft_sc_enable(3)
RETURN
.END

.PROGRAM force.move(zero_force)
; Name: force.move
; Author: Capt Matthew L. June - GCS-96D
; Abstract: Enables guarded mode force sensing and attempts to move
; to the goal location. Returns trip status of the sensor, forces at
; the time of the trip, and the trip location.

; This program is UTAP-compliant

AUTO LOC goal.loc

CALL get_ext_loc_dat("location_1", goal.loc)

IF zero_force THEN
   CALL sc_get_att_read("offset")
END

CALL ft_sc_enable(1)

CALL as_set_position(goal.loc)
BREAK

CALL sc_get_reading("trip")
; trip = LATCHED(1)
IF trip THEN
   CALL sc_get_reading("forces")
   FORCE.READ(1) forces[]
   CALL sc_get_reading("trip.pos")
   SET trip.pos = LATCH(1)
END

CALL ft_sc_disable(1)

RETURN

.PROGRAM force1(pallet, row, col)

; Name: force1
; Author: Capt Matthew L. June - GCS-96D
; Abstract: Simulates a vertical insertion, where if the forces are
; too high the insertion is jammed (force > 2 lb). A high-speed
; approach to 100mm above the assembly location "goal1" is attempted
; first, followed by a fast approach to 20mm above the insertion
; location and a slow guarded move to the goal location. Using a
; second, low approach point minimizes the length of the relatively
; slow guarded move.

; The program acquires a part from a pallet and attempts to "insert"
; it. If the insertion fails, the part is returned to the pallet and
; another part is tried. If the insertion succeeds, the part is
; released, the manipulator moves to a safe location, and the program
; terminates.

; The initial insertion location is below the table surface. Therefore
; a failure is guaranteed. The insertion location is incremented up by

; 1mm for each iteration until the part is placed on the table surface.

; This program is UTAP-compliant

AUTO offset, quit, i, j

; Initialize variables

offset = -1
quit = FALSE
trip = FALSE
i = 0
j = 0

; Initialize force sensor and enable protected mode

CALL td_exec_prog("force.init!")

; Set force limits but don't enable guarded mode

CALL ft_sc_mode_sel(1, "H12, 2")

CALL as_set_position(safe)
BREAK

; Write initial lines to audit file and screen

CALL post_ext_data(screen, "START OF FORCE1 INFORMATION")
CALL post_ext_data(screen, ")")
CALL post_ext_data(screen, "attemting first part")
CALL post_ext_data(disk, "START OF FORCE1 INFORMATION")
CALL post_ext_data(disk, ")")
CALL post_ext_data(disk, "attemting first part")

; Start operation to 'insert' a part

WHILE NOT quit DO

CALL td_exec_prog("acquire.part("+$ENCODE(pallet)="",
                        ";+$ENCODE(1)+", ";+$ENCODE(j)+")")")

CALL as_set_velocity(100)
CALL as_set_position(goal1:TRANS(0,0,-offset-100))
BREAK

CALL as_set_velocity(50)
CALL as_set_position(goal1:TRANS(0,0,-offset-20))
BREAK

CALL as_set_velocity(5)
CALL set_ext_loc_dat("location_1", goal1:TRANS(0,0,-offset))
CALL td_exec_prog("force.moveg(TRUE)")
BREAK
CALL as_set_velocity(100)

IF trip THEN ; guard force limit exceeded
    CALL post_ext_data(screen, "Insertion jammed/S")
    CALL post_ext_data(screen, $ENCODE(DISTANCE (
goal:TRANS(0,0,-offset),
    trip.pos))"/S")
    CALL post_ext_data(screen, " mm from goal")
    CALL post_ext_data(screen, "$ENCODE(forces[2])")
    CALL post_ext_data(disk, "Insertion jammed/S")
    CALL post_ext_data(disk, $ENCODE(DISTANCE (
goal:TRANS(0,0,-offset),
    trip.pos))"/S")
    CALL post_ext_data(disk, " mm from goal")
    CALL post_ext_data(disk, $ENCODE(forces[2]))
    CALL as_set_position(trip.pos:TRANS(0,0,-75))
    CALL td_exec_prog("replace.part:+$ENCODE(pallet),+
    "$ENCODE(i)+" "$ENCODE(j)+")")
    offset = offset+1
    IF (1 <= row-1) THEN ; increment to next part
        IF j < col-1 THEN
            j = j+1
        ELSE
            i = i+1
            j = 0
        END ; if-else
    END ; if
    IF i == row THEN ; last part has been tried
        CALL post_ext_data(screen, "Last part failed, part
        cannot be inserted")
        CALL post_ext_data(screen, "")
        CALL post_ext_data(disk, "Last part failed, part
        cannot be inserted")
        CALL post_ext_data(disk, "")
        CALL as_set_position(safe)
    ELSE
        CALL post_ext_data(screen, "Attempting next part")
        CALL post_ext_data(disk, "Attempting next part")
    END ; if-else
    ELSE ; last part hasn't been tried
        CALL post_ext_data(screen, "Insertion succeeded.")
        CALL post_ext_data(screen, "")
        CALL post_ext_data(disk, "Insertion succeeded.")
        CALL post_ext_data(disk, "")
        CALL gripper_open()
        CALL as_set_position(goal:TRANS(0,0,-offset-80))
        CALL as_set_position(safe)
        BREAK
        quit = TRUE
    END ; if-else
END ; while

RETURN

.PROGRAM force2(pallet)
    ; Name: force2
    ; Author: Capt Matthew L. June - GCS-96D
    ; Abstract: This program acquires a part from a pallet and sets it on
    ; the table surface. It accomplishes this by moving the part to a
    ; position above the surface and repeatedly moving the part down 1mm
    ; until the Z direction force exceeds 2 lbs. At this point, the part
    ; is released and the manipulator moves to a safe location
    ; This program is UTAP-compliant

    AUTO offset, i
    ; Initialize variables
    i = 1
    offset = 0
    trip = FALSE
    ; Initialize force sensor and enable protected mode
CALL td_exec_prog("force.init()")
; Set force limits but don't enable guarded mode
CALL ft_sc_mode_set(1, "H12, 2")
CALL as_set_position(safe)
CALL td_exec_prog("acquire.part(""*"$ENCODE(pallet)""", 3, 1")")
CALL as_set_position(goal2:TRANS(0,0,-100))
BREAK
CALL as_set_position(goal2:TRANS(0,0,-50))
CALL as_set_position(goal2:TRANS(0,0,-20))
BREAK
; Write initial lines to audit file
CALL post_ext_data(screen, "START OF FORCE2 INFORMATION")
CALL post_ext_data(screen, ")")
CALL post_ext_data(disk, "START OF FORCE2 INFORMATION")
CALL post_ext_data(disk, "")
END ; if-else
END ; while
RETURN

.PROGRAM replace.part(pallet, i, j)
; Name: replace.part
; Author: Capt Matthew L. June - GCS-96D
; Abstract: This program starts with a part in the gripper. It moves
; the part to a location specified by a pallet number and i and j
; offsets. Then, it releases the part and moves to a location 75mm
; above the part.
; This program is UTAP-compliant
AUTO place
CALL as_set_velocity(100)
IF pallet = 1 THEN
SET place = pal.1:TRANS(50*i,50*j)
ELSE
SET place = pal.2:TRANS(50*i,50*j)
END
CALL as_set_position(place:TRANS(0,0,-75))
CALL as_set_position(place)
BREAK
CALL as_set_open()
CALL post_ext_data(screen, "Succeeded on attempt/"S")
CALL post_ext_data(screen, $ENCODE(i))
CALL post_ext_data(disk, "Actual position is/"S")
CALL post_ext_data(disk, $ENCODE(DISTANCE(
  goal2.trip.pos)*/)*/S")
CALL post_ext_data(screen, " mm from the first
attempt")
CALL post_ext_data(screen, ")")
CALL post_ext_data(disk, "Succeeded on attempt/"S")
CALL post_ext_data(disk, $ENCODE(i))
CALL post_ext_data(disk, "Actual position is/"S")
CALL post_ext_data(disk, $ENCODE(DISTANCE(
  goal2.trip.pos)*/)*/S")
CALL post_ext_data(disk, " mm from the first attempt")
CALL post_ext_data(disk, "")
CALL as_set_velocity(100)
CALL as_set_position(trip.pos:TRANS(0,0,-80))
CALL as_set_position(safe)
BREAK
END ; if-else
END ; while
RETURN
APPENDIX I

V+/UTAP Interface Source Code
Generic Module

.PROGRAM get_ext_data(channel, $text, $value)
; UTAP - V+ INTERFACE PROGRAM
; Name: get_ext_data
; UTAP Message: US_GET_EXT_DATA_VALUE
; Author: Capt Matthew L. June - GCS-96D
; Abstract: UTAP message to receive data from an IO device. Maps to the V+ "PROMPT" command.

CASE channel OF
  VALUE keyboard:
    PROMPT $text, $value
END
RETURN

.PROGRAM get_ext_loc_dat($loc_name, loc_value)
; UTAP - V+ INTERFACE PROGRAM
; Name: get_ext_loc_dat
; UTAP Message: US_GET_EXT_LOCATION_DATA_VALUE
; Author: Capt Matthew L. June - GCS-96D
; Abstract: New UTAP message to retrieve a V+ transformation location value from the Object Knowledgebase. Maps to the V+ "SET" command.

IF $loc_name == "location_1" THEN
  SET loc_value = location_1
END
IF $loc_name == "location_2" THEN
  SET loc_value = location_2
END
RETURN

.PROGRAM hold($condition)
; UTAP - V+ INTERFACE PROGRAM
; Name: hold
; UTAP Message: US_HOLD
; Author: Capt Matthew L. June - GCS-96D

; Abstract: UTAP message to suspend a program until a condition has been met. Maps to the V+ commands "WAIT", "SIG", and "PENDANT".

AUTO i, $arg[12], $temp, $command, temp

; Initialize argument array
FOR i = 0 TO 12
  $arg[i] = ""
END

; Parse $condition into argument array
$i = 0
DO
  $arg[i] = $DECODER($condition, " ", 0)
  $temp = $DECODER($condition, " ", 1)
  i = i+1
UNTIL ($condition == "") OR (i > 12)

$command = "WAIT"

; If the Hold condition is based on SIGNAL values, then create the signal portion of the "WAIT" instruction
$i = 0
IF $arg[i] == "signal" THEN
  $command = $command + "$SIG(+$arg[i]+)"
  i = i+1
END
WHILE $arg[i] <> "suspend" AND ($arg[i] <> "") DO
  $command = $command + OR ($arg[i]+)" "$SIG(+$arg[i]+)"
  i = i+1
END

; If the Hold condition includes waiting on pendant values, then add the pendant portion of the "WAIT" instruction
IF $arg[i] == "pendant" THEN
  $temp = $DECODER($condition, " ", 0)
  $arg[i] = $DECODER($condition, " ", 1)
  i = i+1
  WHILE $arg[i] <> "" DO
    IF i > 1 THEN
      $command = $command + OR "$temp"
    END
    $temp = $DECODER($condition, " ", 0)
    $arg[i] = $DECODER($condition, " ", 1)
    i = i+1
  END
  ELSE
    $command = $command + "$PENDANT(+$arg[i]+)"
  END
END
; Execute the instruction
DOS $command
RETURN

.PROGRAM post_ext_data(channel, $value)
; UTAP - V+ INTERFACE PROGRAM
; Name: post_ext_data
; UTAP Message: US_POST_EXT_DATA_VALUE
; Author: Capt Matthew L. June - GCS-96D
; Abstract: UTAP message to write data to an IO device. Maps to the V+ command "WRITE" and "TYPE".
AUTO $command, $temp
CASE channel OF
VALUE mcp:
$command = "" DO
$temp = $DECODE($value, ",", 0)
IF POS($temp, "+") THEN
IF $command = "" THEN
$command = $temp
ELSE
$command = $command "+" $temp
END
ELSE IF $command = "+" THEN
DOS "WRITE (mcp) "" $command "", /S"
END
WRITE (mcp) $temp, /S
$command = ""
END
$temp = $DECODE($value, ",", 1)
UNTIL $temp = ""
IF $command = "+" THEN
DOS "WRITE (mcp) "" $command "", /S"
END
VALUE screen; $temp = $INCDW($value, "/", 0)
TYPE $temp, /S

DOS "TYPE "+$value
VALUE disk; $temp = $DECODE($value, "/", 0)
WRITE (disk) $temp, /S
DOS "WRITE (disk) "" $value
END
RETURN

.PROGRAM set_ext_loc_data($loc_name, loc_value)
; UTAP - V+ INTERFACE PROGRAM
; Name: set_ext_loc_data
; UTAP Message: US_SET_EXTLOCATION_DATA_VALUE
; Author: Capt Matthew L. June - GCS-96D
; Abstract: New UTAP message to write a V+ transformation location value to the object knowledgebase. Maps to the V+ "SET" command.
IF $loc_name = "location_1" THEN
SET location_1 = loc_value
END
IF $loc_name = "location_2" THEN
SET location_2 = loc_value
END
RETURN

axis Servo Module

.PROGRAM as_set_position(joint_position)
; UTAP - V+ INTERFACE PROGRAM
; Name: as_set_position
; UTAP Message: US_AXIS_SERVO_SET_POSITION
; Author: Capt Matthew L. June - GCS-96D
; Abstract: UTAP message to move the manipulator. Maps to the V+ "MOVH" command.
MOVE joint_position
RETURN

.END
Object Knowledgebase Module

.PROGRAM init_ok()
; UTAP - Vx INTERFACE PROGRAM
; Name: init_ok
; UTAP Message: US_INIT_OK
; Author: Capt Matthew L. June - GCS-96D
; Abstract: UTAP message to initialize the Object Knowledgebase.

AUTO i

; System channel identifiers
GLOBAL robot, mcp, screen, keyboard, disk, signal, timer

; Global location variables
GLOBAL loc location_1, location_2, location_3

; Force sensor attributes
GLOBAL trip, trip.pos, forces[i]

; Initialize values
robot = 0
mcp = 1
screen = 2
keyboard = 3
disk = 5
signal = 6
timer = 7

SPT trip.pos = HERE
trip = FALSE
FOR i = 0 TO 5
forces[i] = 0
END
RETURN

.PROGRAM ok_attr_query($attrib, $data)
; UTAP - Vx INTERFACE PROGRAM
; Name: ok_attr_query
; UTAP Message: US_OK_ATTRIBUTE_QUERY
; Author: Capt Matthew L. June - GCS-96D
; Abstract: UTAP message to retrieve data from the Object
; Knowledgebase. Maps to the Vx commands "SPEED(x)", "ACCEL(x)",
; "SWITCH(x)", and "CONFIG(x)"

IF $attrib == "Monitor Speed" THEN
$data = $ENCODE(SPEED(1))
END

IF $attrib == "Permanent Speed" THEN
$data = $ENCODE(SPEED(2))
END

IF $attrib == "Current Speed" THEN
$data = $ENCODE(SPEED(3))
END

IF $attrib == "Next Speed" THEN
$data = $ENCODE(SPEED(4))
END

IF $attrib == "Acceleration" THEN
$data = $ENCODE(ACCEL(1))
END

IF $attrib == "Deceleration" THEN
$data = $ENCODE(ACCEL(2))
END

IF $attrib == "Gripper Delay" THEN
$data = $ENCODE(PARAMETER(HAND_TIME))
END

IF $attrib == "Continuous Path" THEN
IF SWITCH(CP) THEN
$data = "Enabled"
ELSE
$data = "Disabled"
END
Programmable I/O Module

! PROGRAM pi_bit_set(channel, bit, data)
  ; UTAP - V+ INTERFACE PROGRAM
  ; Name: pi_bit_set
  ; UTAP Message: USPIO_BIT_SET
  ; Author: Capt Matthew L. June - GCS-96D
  ; Abstract: UTAP message to write a value to a programmable I/O device. Maps to the V+ commands "KEYMODE", "SIGNAL", and "TIMER".
  
  CASE channel OF
    VALUE mcp:
      KEYMODE bit = data
    VALUE signal:
      IF data = -1 THEN SIGNAL -bit
      ELSE SIGNAL bit
    END
    VALUE timer:
      TIMER bit = data
  END

! RETURN

! PROGRAM pi_bit_read(channel, bit, data)
  ; UTAP - V+ INTERFACE PROGRAM
  ; Name: pi_bit_read
  ; UTAP Message: USPIO_BIT_READ
  ; Author: Capt Matthew L. June - GCS-96D
  ; Abstract: UTAP message to read a value from a programmable I/O device. Maps to the V+ commands "PENDANT(x)", "SIG(x)", and "TIMER(x)".
  
  CASE channel OF
    VALUE mcp:
      data = PENDANT(bit)
    END
    VALUE signal:
      data = SIG(bit)
    END
    VALUE timer:
      data = TIMER(bit)
  END

! RETURN

! PROGRAM pi_disable(channel)
  ; UTAP - V+ INTERFACE PROGRAM
  ; Name: pi_disable
  ; UTAP Message: USPIO_DISABLE
  ; Author: Capt Matthew L. June - GCS-96D
  ; Abstract: UTAP message to disable a programmable I/O device. Maps to the V+ commands "DETACH" and "PCLOSE".
  
  CASE channel OF
    VALUE mcp:
      DETACH (channel)
    VALUE disk:
      PCLOSE (channel)
      DETACH (channel)
Parent Task Program Sequencer Module

Sensor Module
FORCK_MODE (-mode)

RETURN
.END

.PROGRAM ft_sc_enable(mode)
;
UTAP - V+ INTERFACE PROGRAM
; Name: ft_sc_enable
; UTAP Message: US_FT_SENSOR_ENABLE
; Author: Capt Matthew L. June - GCS-96D
; Abstract: New UTAP message to select the mode of operation for
; a force/torque sensor. Maps to the V+ "FORCE.MODE" command.

FORCE.MODE (mode)
RETURN
.END

.PROGRAM ft_sc_mode_sel(mode, $attr)
;
UTAP - V+ INTERFACE PROGRAM
; Name: ft_sc_mode_sel
; UTAP Message: US_FT_SENSOR_MODE_SELECT
; Author: Capt Matthew L. June - GCS-96D
; Abstract: New UTAP message to select the mode of operation for
; a force/torque sensor. Maps to the V+ "FORCE.MODE" command.

IF (mode == 1) OR (mode <= 3) THEN
  DOG "FORCE.MODE (*$SRCMODE(-mode):*):" "$attr
ELSE
  FORCE.MODE (mode)
END
RETURN
.END

.PROGRAM sc_get_reading($attribute)
;
UTAP - V+ INTERFACE PROGRAM
; Name: sc_get_reading
; UTAP Message: US_SENSOR_GET_READING
; Author: Capt Matthew L. June - GCS-96D
; Abstract: UTAP message to retrieve sensor readings. Maps to the
; V+ commands "LATCH", "LATCHED", and "FORCER.READ".

IF $attribute == "trip" THEN
  trip = LATCHED(1)
END
IF $attribute == "trip.pos" THEN
  SET trip.pos = LATCH(1)
END
IF $attribute == "forces" THEN
  FORCE.READ (1) forces[]

.PROGRAM sc_get_att_read($attr_name, attr_val[])
;
UTAP - V+ INTERFACE PROGRAM
; Name: sc_get_att_read
; UTAP Message: US_SENSOR_GET_ATTRIBUTES_READING
; Author: Capt Matthew L. June - GCS-96D

; Abstract: UTAP message to read sensor attribute values. Maps
to the V+ commands "FORCER.READ" and "FORCER.OFFSET".

IF $attr_name == "ratings" THEN
  FORCE.READ (3) attr_val[]
END
IF $attr_name == "offset" THEN
  IF DEFINED(attr_val[]) THEN
    FORCE.OFFSET (2) attr_val[]
  ELSE
    FORCE.OFFSET (1)
  END
END
RETURN
.END
Task Description Module

.PROGRAM td_exec_prog($prog_name)

; UTAP - V+ INTERFACE PROGRAM
; Name: td_exec_prog
; UTAP Message: US_TDS_EXECUTE_PROGRAM
; Author: Capt Matthew L. June - GCS-96D
; Abstract: UTAP message to call a subroutine. Maps to the V+
; "CALL" command.

AUTO $command
DOS "CALL $*prog_name"

RETURN

.END

Task Level Control Module

.PROGRAM tl_str_fine_mot($axis_mask)

; UTAP - V+ INTERFACE PROGRAM
; Name: tl_str_fine_mot
; UTAP Message: US_US/tcp_FINE_MOTION
; Author: Capt Matthew L. June - GCS-96D
; Abstract: UTAP message to use f ine control for manipulator
; movements. Maps to the V+ "FINE" command.

FINE ALWAYS
RETURN

.END
APPENDIX J

Palletizing Application Output
Original Application Output
Part Movement from Pallet 1 to Pallet 2

START OF PALLETIZING INFORMATION

13-Sep-96 09:19:30
Row = 2  Col = 3
The pick location coordinates are:
( 330.6096 -198.1177 214.8365 0 179.9998 89.62424)
The place location coordinates are:
( 328.4753 102.031 214.8362 0 179.9993 90.22086)

13-Sep-96 09:19:34
Row = 3  Col = 1
The pick location coordinates are:
( 230.2838 -148.7746 214.8363 0 179.9998 89.62424)
The place location coordinates are:
( 228.6688 152.4161 214.8364 0 179.9993 90.22086)

13-Sep-96 09:19:37
Row = 3  Col = 2
The pick location coordinates are:
( 280.2827 -148.4467 214.8363 0 179.9998 89.62424)
The place location coordinates are:
( 278.6685 152.2234 214.8361 0 179.9993 90.22086)

13-Sep-96 09:19:41
Row = 3  Col = 3
The pick location coordinates are:
( 330.2816 -148.1188 214.8363 0 179.9998 89.62424)
The place location coordinates are:
( 328.6681 152.0307 214.8357 0 179.9993 90.22086)

13-Sep-96 09:19:45
Row = 4  Col = 1
The pick location coordinates are:
( 229.9559 -98.77571 214.8361 0 179.9998 89.62424)
The place location coordinates are:
( 228.6616 202.4157 214.836 0 179.9993 90.22086)

13-Sep-96 09:19:48
Row = 4  Col = 2
The pick location coordinates are:
( 279.9548 -98.44778 214.8362 0 179.9998 89.62424)
The place location coordinates are:
( 278.8612 202.223 214.8356 0 179.9993 90.22086)

13-Sep-96 09:19:52
Row = 4  Col = 3
The pick location coordinates are:
( 329.9537 -98.11987 214.8362 0 179.9998 89.62424)
The place location coordinates are:
( 328.8608 202.0303 214.8353 0 179.9993 90.22086)

START OF FORCE1 INFORMATION

attempting first part
Insertion jammed 8.63994 mm from goal
Z direction force at time of jam:  6.051636

Attempting next part
Insertion jammed 7.468828 mm from goal
Z direction force at time of jam:  5.245972

Attempting next part
Insertion jammed 6.51549 mm from goal
Z direction force at time of jam:  2.566528

Attempting next part
Insertion jammed 5.866747 mm from goal
Z direction force at time of jam:  5.386353

Attempting next part
Insertion jammed 4.540012 mm from goal
Z direction force at time of jam:  4.507446

Attempting next part
Insertion jammed 3.517776 mm from goal
Z direction force at time of jam:  2.624512

Attempting next part
Insertion jammed 2.449036 mm from goal
Z direction force at time of jam:  2.23999

Attempted next part
Insertion jammed 1.8489 mm from goal
Z direction force at time of jam:  5.648804

Attempted next part
Insertion jammed 0.8689575 mm from goal
Z direction force at time of jam:  2.606201

Attempted next part
Insertion succeeded.

START OF FORCE2 INFORMATION

Failed attempt # 1
Failed attempt # 2
Failed attempt # 3
Failed attempt # 4
Failed attempt # 5
Failed attempt # 6
Failed attempt # 7
Failed attempt # 8
Failed attempt # 9
Failed attempt # 10
Failed attempt # 11
Failed attempt # 12
Succeeded on attempt 13
Actual position is 11.26028 mm from the first attempt
Original Application Output
Part Movement from Pallet 2 to Pallet 1

START OF PALLETTIZING INFORMATION

13-Sep-96 09:22:11
Row = 1  Col = 1
The pick location coordinates are:
( 228.2834 52.41686 214.8373 0 179.9993 90.22086)
The place location coordinates are:
( 230.9396 -248.7725 214.8365 0 179.9998 89.62424)

13-Sep-96 09:22:14
Row = 1  Col = 2
The pick location coordinates are:
( 278.283 52.22413 214.837 0 179.9993 90.22086)
The place location coordinates are:
( 280.9395 -248.4446 214.8366 0 179.9998 89.62424)

13-Sep-96 09:22:18
Row = 1  Col = 3
The pick location coordinates are:
( 328.2826 52.0314 214.8367 0 179.9993 90.22086)
The place location coordinates are:
( 330.9375 -248.1167 214.8366 0 179.9998 89.62424)

13-Sep-96 09:22:21
Row = 2  Col = 1
The pick location coordinates are:
( 228.4761 102.4165 214.8369 0 179.9993 90.22086)
The place location coordinates are:
( 230.6117 -198.7736 214.8364 0 179.9998 89.62424)

13-Sep-96 09:22:25
Row = 2  Col = 2
The pick location coordinates are:
( 278.4757 102.2238 214.8365 0 179.9993 90.22086)
The place location coordinates are:
( 280.6106 -198.4456 214.8364 0 179.9998 89.62424)

13-Sep-96 09:22:28
Row = 2  Col = 3
The pick location coordinates are:
( 328.4753 102.031 214.8362 0 179.9993 90.22086)
The place location coordinates are:
( 330.6096 -198.1177 214.8365 0 179.9998 89.62424)

13-Sep-96 09:22:32
Row = 3  Col = 1
The pick location coordinates are:
( 228.6688 152.4161 214.8364 0 179.9993 90.22086)
The place location coordinates are:
( 230.2838 -148.7746 214.8363 0 179.9998 89.62424)

13-Sep-96 09:22:36
Row = 3  Col = 2
The pick location coordinates are:
( 278.6685 152.2234 214.8361 0 179.9993 90.22086)
The place location coordinates are:
( 280.2827 -148.4467 214.8363 0 179.9998 89.62424)

13-Sep-96 09:22:39
Row = 3  Col = 3
The pick location coordinates are:
( 328.6681 152.0307 214.8357 0 179.9993 90.22086)
The place location coordinates are:
( 330.2816 -148.1188 214.8363 0 179.9998 89.62424)

13-Sep-96 09:22:43
Row = 4  Col = 1
The pick location coordinates are:
( 228.8616 202.4157 214.836 0 179.9993 90.22086)
The place location coordinates are:
( 229.9559 -98.77571 214.8361 0 179.9998 89.62424)

13-Sep-96 09:22:47
Row = 4  Col = 2
The pick location coordinates are:
( 278.8612 202.223 214.8356 0 179.9993 90.22086)
UTAP-compliant Application Output
Part Movement from Pallet 1 to Pallet 2

START OF PALLETIZING INFORMATION

13-Sep-96 09:47:09
Row = 0  Col = 0
The pick location coordinates are:
( 230.9396 -248.7725 214.8365 0 179.9998 89.62424)
The place location coordinates are:
( 228.2834 52.41686 214.8373 0 179.9993 90.22086)

13-Sep-96 09:47:13
Row = 0  Col = 1
The pick location coordinates are:
( 280.9385 -248.4446 214.8366 0 179.9998 89.62424)
The place location coordinates are:
( 278.283 52.22413 214.837 0 179.9993 90.22086)

13-Sep-96 09:47:17
Row = 0  Col = 2
The pick location coordinates are:
( 330.9375 -248.1167 214.8366 0 179.9998 89.62424)
The place location coordinates are:
( 328.2826 52.0314 214.8367 0 179.9993 90.22086)

13-Sep-96 09:47:21
Row = 1  Col = 0
The pick location coordinates are:
( 230.6117 -198.7736 214.8364 0 179.9998 89.62424)
The place location coordinates are:
( 228.4761 102.4165 214.8369 0 179.9993 90.22086)

13-Sep-96 09:47:25
Row = 1  Col = 1
The pick location coordinates are:
( 280.6106 -198.4456 214.8364 0 179.9998 89.62424)
The place location coordinates are:
( 278.4757 102.2238 214.8365 0 179.9993 90.22086)

13-Sep-96 09:47:29
Row = 1  Col = 2
The pick location coordinates are:
( 330.6096 -198.1177 214.8365 0 179.9998 89.62424)
The place location coordinates are:
( 328.4753 102.031 214.8362 0 179.9993 90.22086)

13-Sep-96 09:47:33
Row = 2  Col = 0
The pick location coordinates are:
( 230.2838 -148.7746 214.8363 0 179.9998 89.62424)
The place location coordinates are:
( 228.6688 152.4161 214.8364 0 179.9993 90.22086)

13-Sep-96 09:47:37
Row = 2  Col = 1
The pick location coordinates are:
( 280.2827 -148.4467 214.8363 0 179.9998 89.62424)
The place location coordinates are:
( 278.6685 152.2234 214.8361 0 179.9993 90.22086)

13-Sep-96 09:47:41
Row = 2  Col = 2
The pick location coordinates are:
( 330.2816 -148.1188 214.8363 0 179.9998 89.62424)
The place location coordinates are:
( 328.6681 152.0307 214.8357 0 179.9993 90.22086)

13-Sep-96 09:47:45
Row = 3  Col = 0
The pick location coordinates are:
( 229.9559 -98.77571 214.8361 0 179.9998 89.62424)
The place location coordinates are:
( 228.8616 202.4157 214.836 0 179.9993 90.22086)

13-Sep-96 09:47:49
Row = 3  Col = 1
The pick location coordinates are:
( 279.9548 -98.44778 214.8362 0 179.9998 89.62424)
The place location coordinates are:
( 278.8612 202.223 214.8356 0 179.9993 90.22086)

13-Sep-96 09:47:53
Row = 3  Col = 2
The pick location coordinates are:
( 329.9537 -98.11987 214.8362 0 179.9998 89.62424)
The place location coordinates are:
( 328.8608 202.0303 214.8353 0 179.9993 90.22086)

START OF FORCE1 INFORMATION

attempting first part
Insertion jammed 8.613272 mm from goal
Z direction force at time of jam: 5.526733

Attempting next part
Insertion jammed 7.539873 mm from goal
Z direction force at time of jam: 3.741455

Attempting next part
Insertion jammed 6.320009 mm from goal
Z direction force at time of jam: 4.51355

Attempting next part
Insertion jammed 5.915636 mm from goal
Z direction force at time of jam: 5.285645

Attempting next part
Insertion jammed 4.56438 mm from goal
Z direction force at time of jam: 2.978516

Attempting next part
Insertion jammed 3.540012 mm from goal
Z direction force at time of jam: 2.526855

Attempting next part
Insertion jammed 2.449041 mm from goal
Z direction force at time of jam: 2.279663

START OF FORCE2 INFORMATION

Attempting next part
Insertion jammed 1.915497 mm from goal
Z direction force at time of jam: 2.255249

Attempting next part
Insertion jammed 0.9022217 mm from goal
Z direction force at time of jam: 3.442383

Attempting next part
Insertion succeeded.

START OF FORCE2 INFORMATION

Failed attempt # 1
Failed attempt # 2
Failed attempt # 3
Failed attempt # 4
Failed attempt # 5
Failed attempt # 6
Failed attempt # 7
Failed attempt # 8
Failed attempt # 9
Failed attempt # 10
Failed attempt # 11
Failed attempt # 12
Succeeded on attempt 13
Actual position is 11.27139 mm from the first attempt
UTAP-compliant Application Output
Part Movement from Pallet 2 to Pallet 1

START OF PALLETLIZING INFORMATION

13-Sep-96 09:54:19
Row = 0  Col = 0
The pick location coordinates are:
( 228.2834 52.41686 214.8373 0 179.9993 90.22086)
The place location coordinates are:
( 230.9396 -248.7725 214.8365 0 179.9998 89.62424)

13-Sep-96 09:54:23
Row = 0  Col = 1
The pick location coordinates are:
( 278.2835 52.22413 214.8370 0 179.9993 90.22086)
The place location coordinates are:
( 280.9385 -248.4446 214.8366 0 179.9998 89.62424)

13-Sep-96 09:54:27
Row = 0  Col = 2
The pick location coordinates are:
( 328.2826 52.0314 214.8367 0 179.9993 90.22086)
The place location coordinates are:
( 330.9375 -248.1167 214.8366 0 179.9998 89.62424)

13-Sep-96 09:54:31
Row = 1  Col = 0
The pick location coordinates are:
( 228.4765 102.4165 214.8369 0 179.9993 90.22086)
The place location coordinates are:
( 230.6117 -198.7736 214.8364 0 179.9998 89.62424)

13-Sep-96 09:54:35
Row = 1  Col = 1
The pick location coordinates are:
( 278.4757 102.2238 214.8365 0 179.9993 90.22086)
The place location coordinates are:
( 280.6106 -198.4456 214.8364 0 179.9998 89.62424)

13-Sep-96 09:54:39
Row = 1  Col = 2
The pick location coordinates are:
( 328.4753 102.0311 214.8362 0 179.9993 90.22086)
The place location coordinates are:
( 330.6096 -198.1177 214.8365 0 179.9998 89.62424)

13-Sep-96 09:54:43
Row = 2  Col = 0
The pick location coordinates are:
( 228.6688 152.4161 214.8364 0 179.9993 90.22086)
The place location coordinates are:
( 230.2838 -148.7746 214.8363 0 179.9998 89.62424)

13-Sep-96 09:54:47
Row = 2  Col = 1
The pick location coordinates are:
( 278.6685 152.2234 214.8361 0 179.9993 90.22086)
The place location coordinates are:
( 280.2827 -148.4467 214.8363 0 179.9998 89.62424)

13-Sep-96 09:54:51
Row = 2  Col = 2
The pick location coordinates are:
( 328.6681 152.0307 214.8357 0 179.9993 90.22086)
The place location coordinates are:
( 330.2816 -148.1188 214.8363 0 179.9998 89.62424)

13-Sep-96 09:54:55
Row = 3  Col = 0
The pick location coordinates are:
( 228.8616 202.4157 214.836 0 179.9993 90.22086)
The place location coordinates are:
( 229.9559 -98.77571 214.8361 0 179.9998 89.62424)

13-Sep-96 09:54:59
Row = 3  Col = 1
The pick location coordinates are:
( 278.8612 202.223 214.8356 0 179.9993 90.22086)
The place location coordinates are:
( 279.9548 -98.44778 214.8362 0 179.9998 89.62424)

13-Sep-96 09:55:04
Row = 3  Col = 2
The pick location coordinates are:
( 328.8608 202.0303 214.8353 0 179.9993 90.22086)
The place location coordinates are:
( 329.9537 -98.11987 214.8362 0 179.9998 89.62424)

START OF FORCE1 INFORMATION

attempting first part
Insertion jammed 8.815492 mm from goal
Z direction force at time of jam: 4.180908

Attempting next part
Insertion jammed 7.444384 mm from goal
Z direction force at time of jam: 4.504395

Attempting next part
Insertion jammed 6.615496 mm from goal
Z direction force at time of jam: 5.960083

Attempting next part
Insertion jammed 5.842226 mm from goal
Z direction force at time of jam: 6.265259

Attempting next part
Insertion jammed 4.591052 mm from goal
Z direction force at time of jam: 4.019165

Attempting next part
Insertion jammed 3.422165 mm from goal
Z direction force at time of jam: 4.440308

Attempting next part
Insertion jammed 2.59111 mm from goal
Z direction force at time of jam: 3.637695

Attempting next part
Insertion jammed 1.715569 mm from goal
Z direction force at time of jam: 2.74353

Attempting next part
Insertion jammed 0.6622521 mm from goal
Z direction force at time of jam: 4.174805

Attempting next part
Insertion succeeded.

START OF FORCE2 INFORMATION

Failed attempt # 1
Failed attempt # 2
Failed attempt # 3
Failed attempt # 4
Failed attempt # 5
Failed attempt # 6
Failed attempt # 7
Failed attempt # 8
Failed attempt # 9
Failed attempt # 10
Failed attempt # 11
Failed attempt # 12
Succeeded on attempt 13
Actual position is 11.83362 mm from the first attempt
VITA

Capt Matthew L. June graduated from Rogers High School in Wyoming, MI, in 1980. He enlisted in the United States Air Force and entered active duty on July 20, 1981. He received his Bachelor of Science degree in Computer Science from Wright State University on June 9, 1990 and received his Air Force commission on October 1, 1990.

His first assignment as a commissioned officer was at Ramstein AB, GE, as Chief, Network Design and Implementation Section. He then moved to Wright-Patterson AFB, OH where he served as the Computer Resource Manager for the F-15 System Program Office. In June of 1995 he entered the School of Engineering at the Air Force Institute of Technology.
Analysis And Design Of Standard Telerobotic Control Software

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The Robotics and Automation Center for Excellence (RACE) has defined an open telerobotics control architecture. This architecture, called the Unified Telerobotic Architecture Project (UTAP), is a proposed standard for all Air Force telerobotic systems. Implementation of UTAP will reduce the cost of robotic applications by increasing software modularity, portability, and reusability. This thesis continued the effort to prove the feasibility of UTAP. In December, 1995, 1st Lt Anchor implemented a portion of the UTAP specification on a PUMA robot. The UTAP-compliant controller exhibited some degradation in the system performance. However, the performance degradation was not fully measured. This thesis extended the measurements of Anchor’s implementation. Additionally, a portion of the UTAP specification was implemented on an Adept 550 manipulator and the performance effects were measured. The implementation included portions of the generic, robot/axis servo control, tool control, sensor control, programmable IO, subsystem task level control, task description and supervision, parent task program sequencer, task program sequencer, and object knowledge modules. Performance measurements of this implementation indicated that, although performance was adversely affected, the degradation was caused by the interface between the UTAP-compliant application and the non-UTAP-compliant operating system. There was little difference between the compliant and non-compliant applications. Successful implementation of the UTAP specification on the PUMA and Adept manipulators proves that it is a feasible telerobotic architecture. Further study of the specification is recommended. Specifically, the development of a UTAP-compliant operating system should be continued.