

Homework Assignment 3 – 601.455/655 Fall 2023

Instructions and Score Sheet (hand in with answers)

| | |
|------------------------------------------------------------------------------------|------------------------------------------------------------------------------------|
| Name | Name |
| Email | Email |
| Other contact information (optional) | Other contact information (optional) |
| Signature (required) I/We have followed the rules in completing this assignment | Signature (required) I/We have followed the rules in completing this assignment |

| Question | Points | | Score | Totals |
|--------------|-----------------|------------|-------|--------|
| 1A | 5 | | | |
| 1B | 5 | | | |
| 1C | 15 | | | |
| 1D | 15 | | | |
| 1E | 10 | | | |
| | Subtotal | 50 | | |
| 2A | 15 | | | |
| 2B | 5 | | | |
| 2C | 10 | | | |
| 2D | 10 | | | |
| 2E | 10 | | | |
| 3F | 15 | | | |
| | Subtotal | 65 | | |
| Total | | 115 | | |

Note: There 115 total possible points in this assignment, but at most 100 will count toward your final letter grade.

1. Remember that this is a graded homework assignment. It is the functional equivalent of a take-home exam.
2. You are to work alone or in teams of two and are not to discuss the problems with anyone other than the TAs or the instructor.
3. It is otherwise open book, notes, and web. But you should cite any references you consult.
4. Please refer to the course organizational notes for a fuller listing of all the rules. I am not reciting them all here, but they are still in effect.
5. Unless I say otherwise in class, it is due before the start of class on the due date posted on the web.
6. Sign and hand in the score sheet as the first sheet of your assignment.

Question 1 (Calibration)

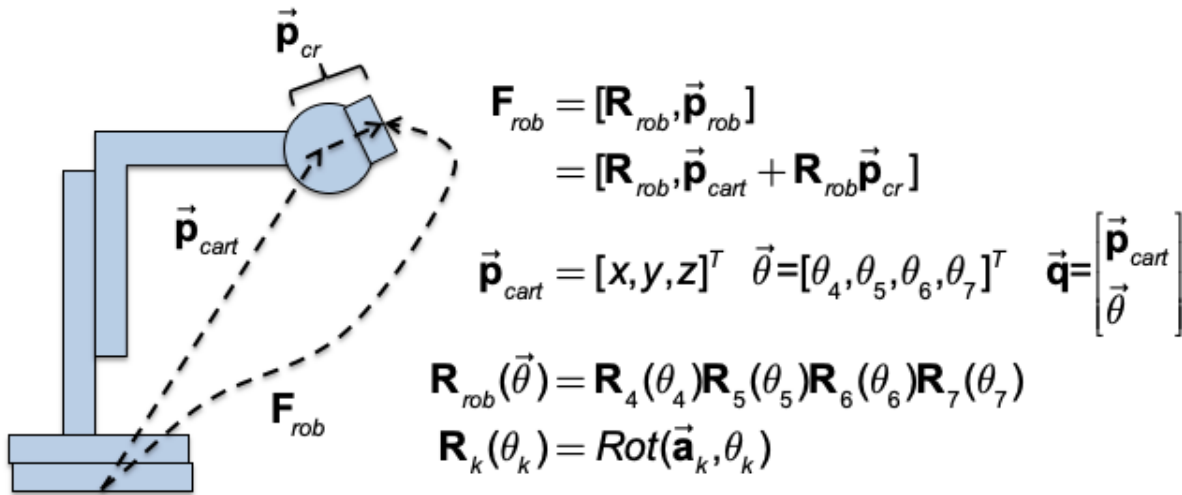


Fig. 1: Robot Kinematics

Consider the robot shown in Fig. 1. This robot consists of a Cartesian base, a multi-axis wrist mechanism, and a tool holder. The transformation between the robot's base and the tool holder is given by $\mathbf{F}_{rob}(\vec{\mathbf{q}})$, as shown in the figure.

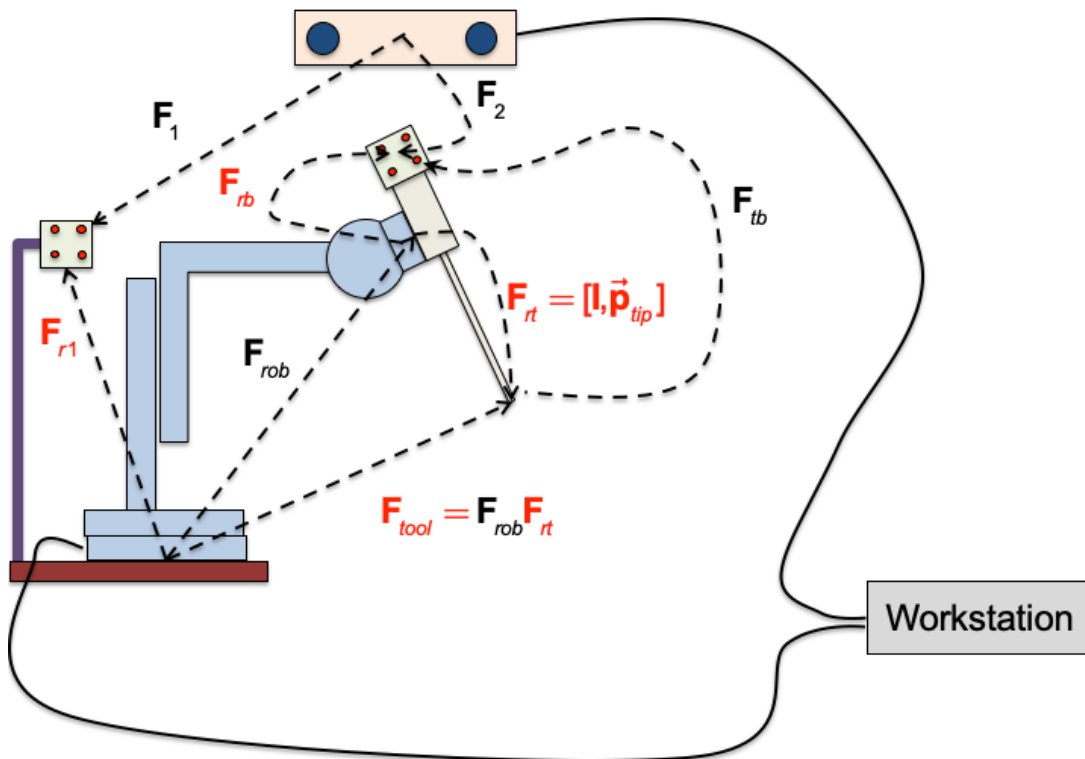


Fig. 2: Robot with tool and tracker bodies

Now consider the setup in Fig. 2, in which the robot from Question 1 has been equipped with a surgical tool which has been attached to the robot's wrist at an unknown pose $\mathbf{F}_{rb} = [\mathbf{R}_{rb}, \vec{\mathbf{p}}_{rb}]$. The origin of the tool's coordinate system is located at the tip of the tool. An optical tracking system marker body is attached to the tool at a known pose $\mathbf{F}_{tb} = [\mathbf{R}_{tb}, \vec{\mathbf{p}}_{tb}]$. The (time varying) pose of this marker body relative to the tracking system is \mathbf{F}_2 , as shown in the figure. An additional tracker marker body has been attached to the base frame of the robot at a fixed, but unknown pose \mathbf{F}_{r1} . The (time varying) pose of this marker body relative to the tracking system is \mathbf{F}_1 , as shown in the figure.

- A. Assume that \mathbf{F}_1 is not available (e.g., it could be obscured). Give a formula for computing the predicted pose \mathbf{F}_2 of the tool marker body relative to the tracking system, based on \mathbf{F}_{rob} and other quantities in the problem.
- B. Assume that \mathbf{F}_{rob} is not available (e.g., its controller may be offline). Give a formula for computing the predicted pose \mathbf{F}_2 of the tool marker body relative to the tracking system, based on \mathbf{F}_1 and other quantities in the problem.
- C. Suppose that the values measured by the encoders of the robot are highly repeatable and that they are equipped with a reliable index mark so that the reported encoder values $\vec{\mathbf{q}}_k = 0$ when joint k is at the index point. However, the encoders readings are subject to small systematic distortions, so that the actual value at any given time the true positions (i.e., translations of the prismatic joints and angles for the revolute joints) of the robot joints are given by $\vec{\mathbf{q}}^* = \vec{\mathbf{q}} + \Delta\vec{\mathbf{q}}(\vec{\mathbf{q}})$. The error associated with each joint is independent of all the other joints of the robot. Also, the rate of change is small, so that

$$\left| \frac{d\Delta(q_k)}{dq_k} \right| \leq \rho_k$$

For now, you can assume that the optical tracking system is highly accurate. Describe an efficient calibration procedure that can be used to produce a correction function for estimating the true value for each joint value to within a specified accuracy. If q_k^{est} is the corrected value and δ_k is the desired maximum error, then you need to ensure that $|q_k^* - q_k^{est}| \leq \delta_k$.

Here, you should give a step-by-step workflow describing any commanded robot motions and calculations that you need to perform. **Hint:** The amount of data required should be roughly in the number of joints.

- D. Suppose now that you have successfully calibrated the joint encoders and incorporated the results into the robot controller software, so that you can simply use the reported values of the joint positions in your calculations. But the robot's mechanical structure is slightly deformed, so that the true direction of each

cartesian axis relative to the base of the robot is $\vec{n}_j^* = \Delta\mathbf{R}_j \vec{n}_j$ and the true direction of each rotational axis is $\vec{a}_k^* = \Delta\mathbf{R}_k \vec{a}_k$. Describe an efficient calibration method for correcting for these structural deformations. Again, you should give a step-by-step workflow describing any commanded robot motions and calculations that you need to perform. **Hint:** The choice of the base coordinate system is somewhat arbitrary and can depend on how the base frame of the robot is defined. Try to align the corrected cartesian axes as close as possible to the canonical cartesian axes $[\vec{x}, \vec{y}, \vec{z}]$. I.e., assume that the base frame of the robot is $\mathbf{F}_{base} = [\mathbf{I}, \vec{0}]$ in robot coordinates. **Hint:** This will lead to an estimate of \mathbf{F}_{r1} .

- E. Assume now that your robot is calibrated and that all results have been incorporated into the robot controller software, so that values reported for \mathbf{F}_{rob} have at most small random errors. However, suppose that the marker body associated \mathbf{F}_1 has been removed from the robot and reattached in an unknown pose relative to the robot. Give a procedure for estimating the unknown values of \mathbf{F}_{r1} and \mathbf{F}_{rb} . Here you may assume that \mathbf{F}_1 , \mathbf{F}_2 , and \mathbf{F}_{rob} are subject to only small random errors. Again, you should give a step-by-step workflow describing any commanded robot motions and calculations that you need to perform. You may identify known algorithms but should clearly identify the formulations of the inputs and outputs.

Question 3 (Robot-Assisted Surgery)

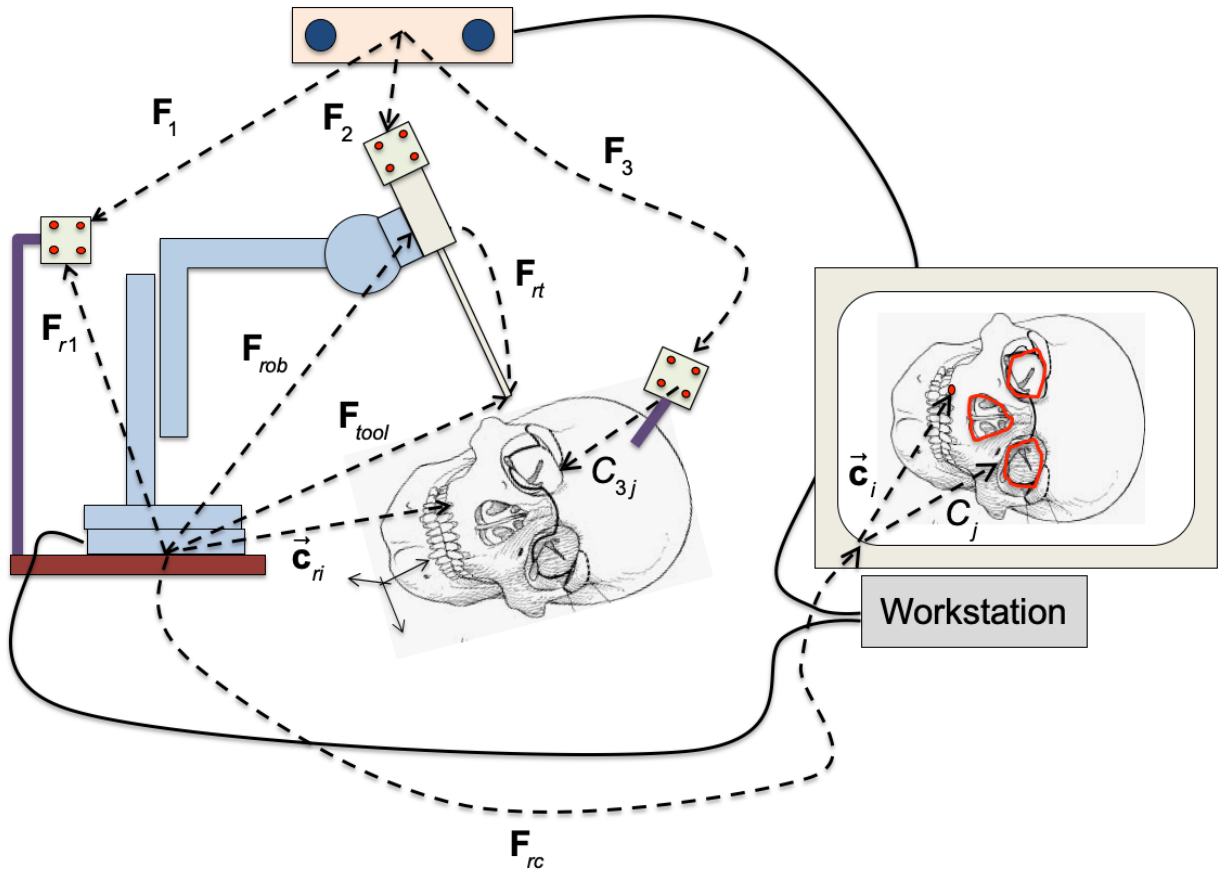


Fig. 3: Robot-Assisted Surgery

Consider now the situation shown in Fig. , in which the robot described in Question 2 has been integrated into a surgical application. All calibration steps have been performed correctly, so that \mathbf{F}_{r1} and \mathbf{F}_{rt} are known. A third marker body has been attached to the patient. The pose of this marker body relative to the tracking system is \mathbf{F}_3 .

A CT scan of the patient is available and image processing has been performed to locate a number of anatomical features at positions $\vec{\mathbf{c}}_i$ relative to CT coordinates and several 3D contour features C_j represented by linked short line segments in CT coordinates. Through the use of a tracked pointer (not shown), the corresponding contour features C_{3j} have been located on the patient, represented as dense sets of 3D points relative to marker \mathbf{F}_3 . I.e., if a point $\vec{\mathbf{a}} \in C_{3j}$ it lies somewhere on the anatomic contour C_j identified in the CT image.

- A.** Describe a method for computing the transformation \mathbf{F}_{rc} between robot coordinates and CT coordinates, so that the position of an anatomical feature at $\vec{\mathbf{c}}_i$ in CT coordinates is given by $\vec{\mathbf{c}}_{ri} = \mathbf{F}_{rc} \vec{\mathbf{c}}_i$ in robot coordinates. Here, you should give a step-by-step

procedure explaining what data you will use together with the inputs and outputs of any known algorithms that you will use.

- B. What value of \mathbf{F}_{rob} will place the tool tip at a position $\vec{\mathbf{c}}_{ri} = \mathbf{F}_{rc} \vec{\mathbf{c}}_i$?
- C. Suppose now that \mathbf{F}_{rob} and \mathbf{F}_{r1} are known accurately, but that the tracker's accuracy is limited, so that $\mathbf{F}_m^* = \mathbf{F}_m \Delta \mathbf{F}_m \approx \mathbf{F}_m \cdot [\mathbf{I} + sk(\vec{\alpha}_m), \vec{\epsilon}_m]$ for $m \in \{1, 2, 3\}$ and that we know that $\|\vec{\alpha}_m\| \leq \gamma$ and $\|\vec{\epsilon}_m\| \leq \sigma$. Provide an estimated bound $\|\vec{\epsilon}_{ri}\| \leq \rho$ on the error $\vec{\epsilon}_{ri} = \vec{\mathbf{p}}_{tool}^* - \vec{\mathbf{c}}_{ri}$ when the robot is placed so that $\vec{\mathbf{c}}_{ri} = \mathbf{F}_{rc} \vec{\mathbf{c}}_i$. For now, you can assume that the robot is perfectly accurate. **Note:** In answering this question, you should assume that the value of \mathbf{F}_2 is not available.
- D. Suppose now that the robot is subject to some error, so that $\mathbf{F}_{rob}^* = \mathbf{F}_{rob} \Delta \mathbf{F}_{rob}$ where $\Delta \mathbf{F}_{rob} \approx [\mathbf{I} + sk(\vec{\alpha}_{rob}), \vec{\epsilon}_{rob}]$ and that the tracker's accuracy is as in Question 3C. Suppose that you also have bounds $\|\vec{\alpha}_{rob}\| \leq \gamma_{rob}$ and $\|\vec{\epsilon}_{rob}\| \leq \sigma_{rob}$. Provide an estimated bound $\|\vec{\epsilon}_{ri}\| \leq \rho$ on the error $\vec{\epsilon}_{ri} = \vec{\mathbf{p}}_{tool}^* - \vec{\mathbf{c}}_{ri}$ when the robot is placed so that $\vec{\mathbf{c}}_{ri} = \mathbf{F}_{rc} \vec{\mathbf{c}}_i$. Here, you may express your answer in terms of your bound ρ_c from Question 2C, together with γ_{rob} and σ_{rob} . **Note:** In answering this question, you should assume that the value of \mathbf{F}_2 is not available.
- E. The pose \mathbf{F}_{tool} can actually be measured in two separate ways, one using \mathbf{F}_{rob} and another using \mathbf{F}_1 and \mathbf{F}_2 . Suppose that \mathbf{F}_{rob} is not available. Produce a formula for $\vec{\epsilon}_{tool} = \Delta \vec{\mathbf{p}}_{tool}$ based on \mathbf{F}_{r1} , \mathbf{F}_m , $\vec{\alpha}_m$, and $\vec{\epsilon}_m$ for $m \in \{1, 2\}$ and the other quantities in the problem.
- F. Suppose now that we have statistical information about our errors, rather than strict bounds, so that

$$\text{Cov}(\vec{\eta}) = \mathbf{C}_\eta, \text{ where } \vec{\eta} = \begin{bmatrix} \vec{\alpha} \\ \vec{\epsilon} \end{bmatrix}$$

Produce formulas for $\text{Cov}(\vec{\epsilon}_{tool})$ based on $\text{Cov}(\vec{\eta}_{rob})$, $\text{Cov}(\vec{\eta}_{rc})$, and $\text{Cov}(\eta_m)$ for $m \in \{1, 2, 3\}$ and other variables in the problem.