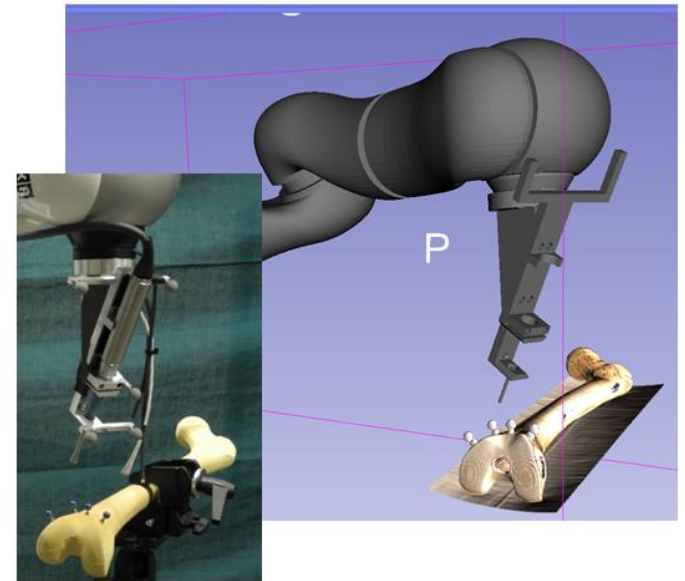
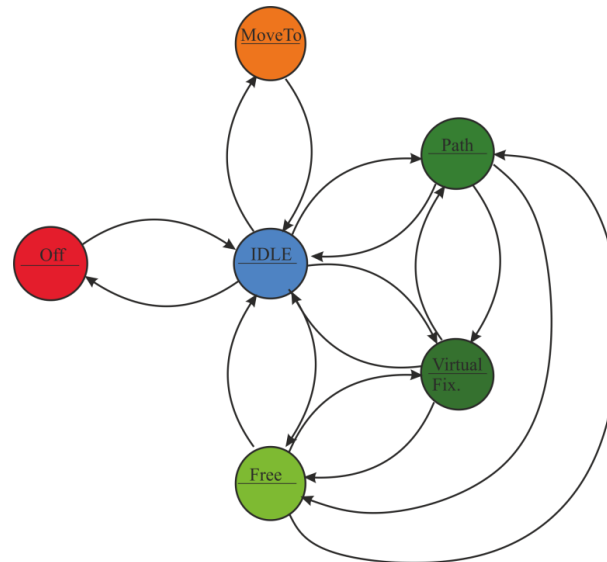


Tutorial

LightWeightRobotIGT – Interface Concept

S. Tauscher



Outline

Introduction

Interface concept

Visualisation

State control

State machine

Motivation

Integration of robots into IGT systems

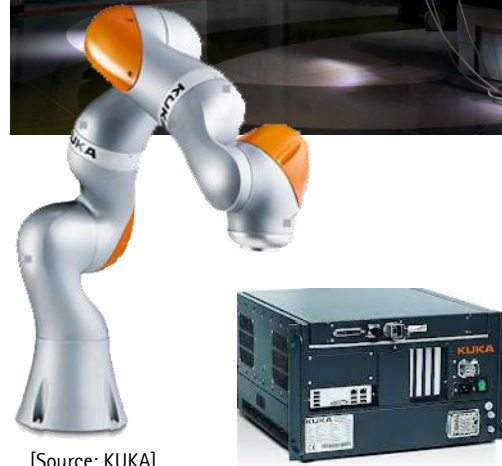
- Time consuming process
- Customized solution for each project
- No widely accepted standard

Future vision

- Standardized interface
- ⇒ Easy integration



[Source: openIGTlink.org]



[Source: KUKA]

State of the art

Current research

- IHE & DICOM for surgery
 - OR.NET
 - OpenIGTLink
- ⇒ Growing importance

Unmet needs

- No widely accepted standard for inter device communication

Aim

- Integration concept for a robot into IGT system



[Source: openIGTlink.org]



[Source: KUKA]



Outline

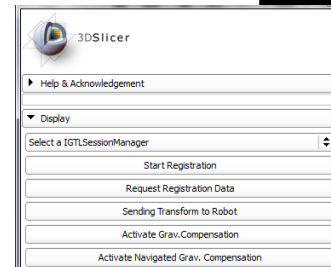
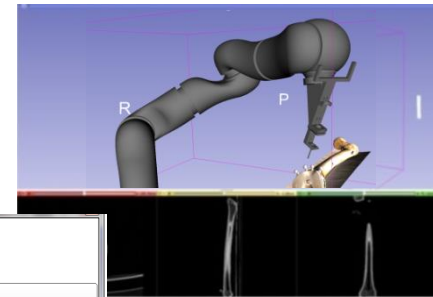
Introduction

Interface concept

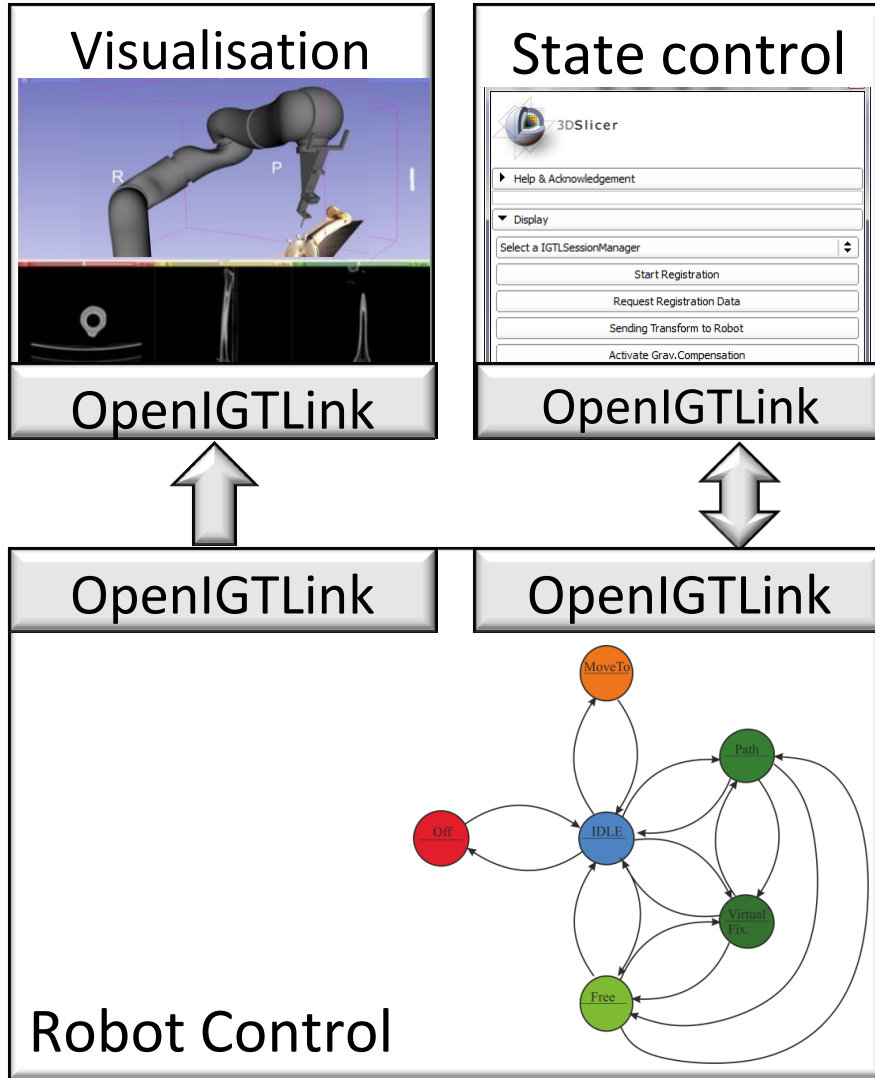
Visualisation

State control

State machine



Interface – Concept



Robot as element of IGT system

Separate visualisation & state control interface

OpenIGTLink based

- Small foot print & widely used
- Open protocol for IGT

State machine for intuitive and direct control

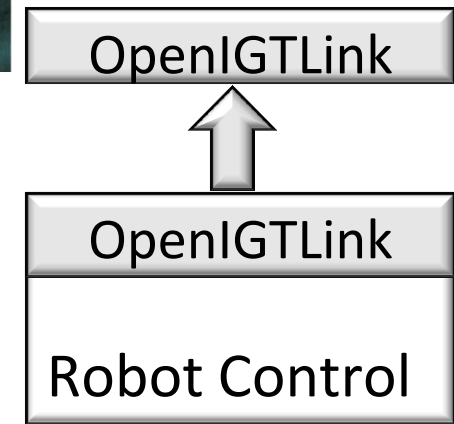
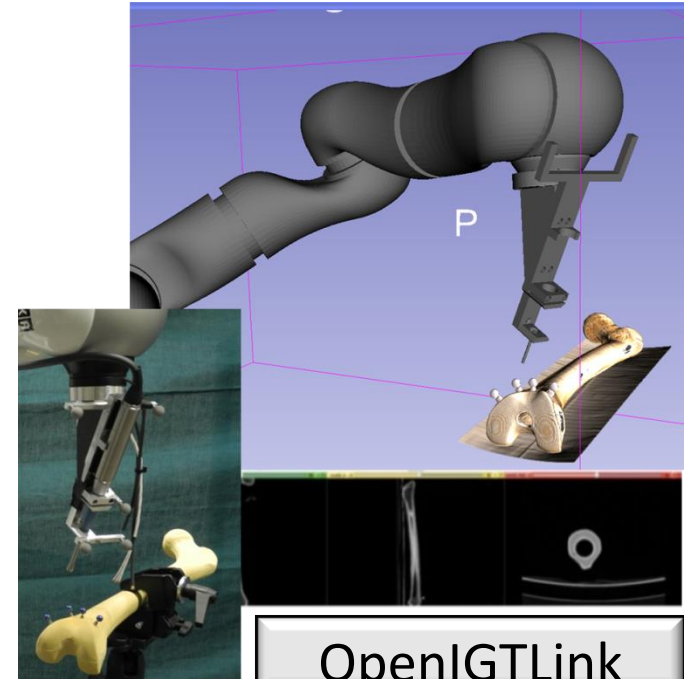
Interface – Visualisation

Requirements

- Real-time ability > 30 Hz
- Latency < 100 ms
- Unidirectional

Data type

- Transformation matrices
 - Image space or robot coordinate system
 - End-effector or joint pose
- ⇒ OpenIGTLink TRANSFORM



Interface – State control

Requirements

- Reliability
- „Is Alive“ check
- Bidirectional

Data type

- Command string + parameter (p)
 - Unified identifier (UID)
- ⇒ OpenIGTLink STRING

Data format

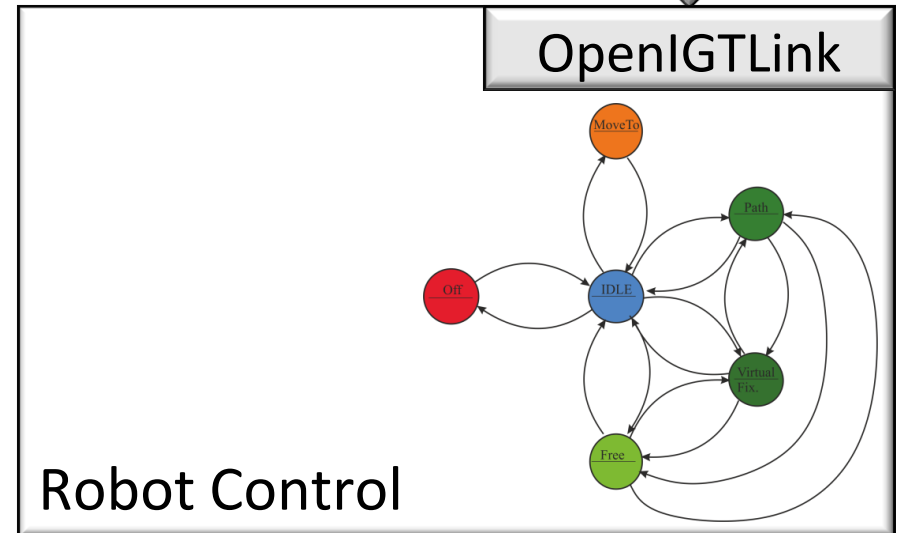
- Device name: “CMD_UID”/”ACK_UID”
- String: “*Commandname;p1;...;pn;*”



OpenIGTLink



OpenIGTLink



Robot Control

Outline

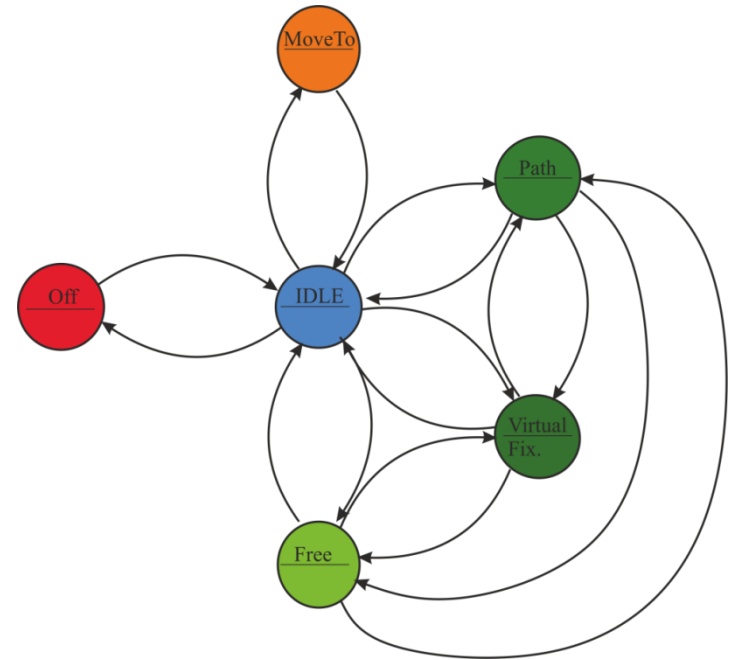
Introduction

Interface concept

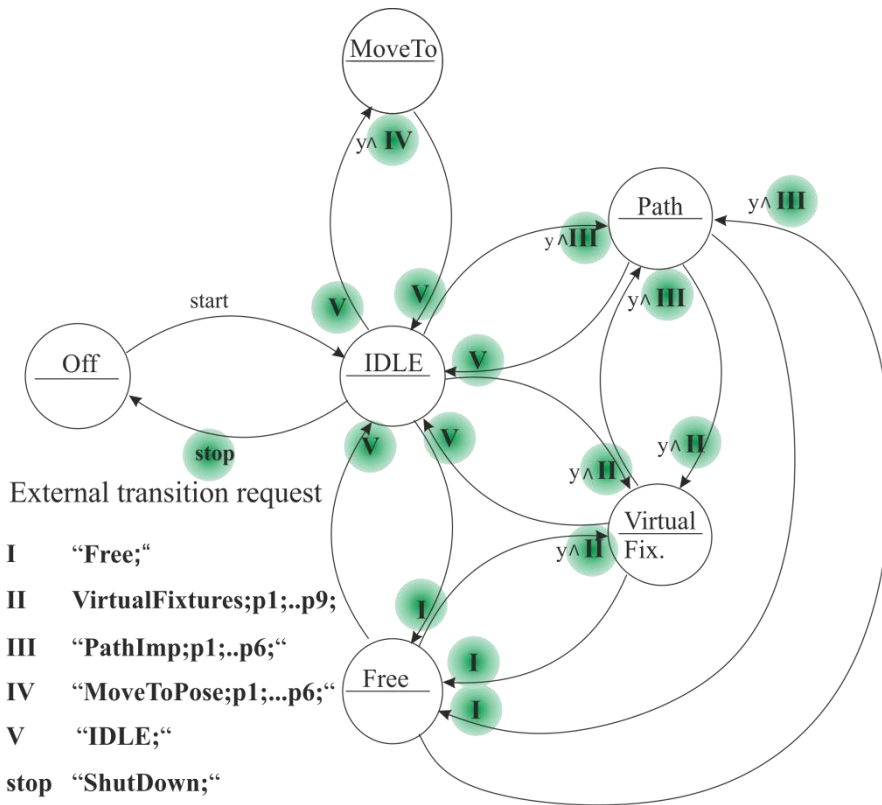
Visualisation

State control

State machine



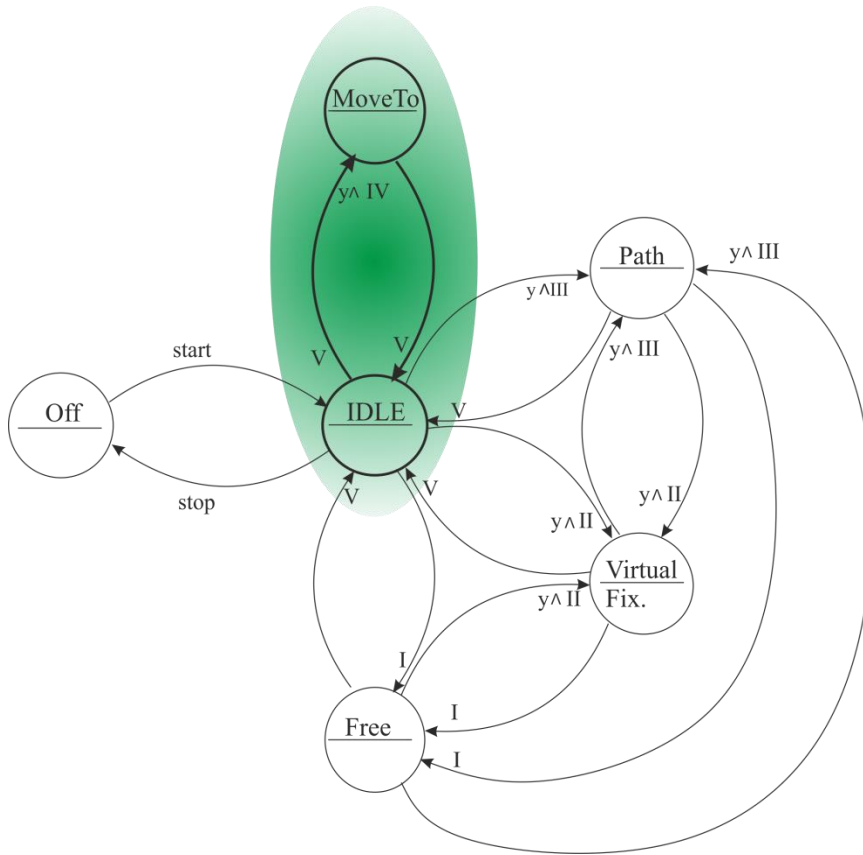
State machine – Transitions



Transitions

- By external request besides in case of error

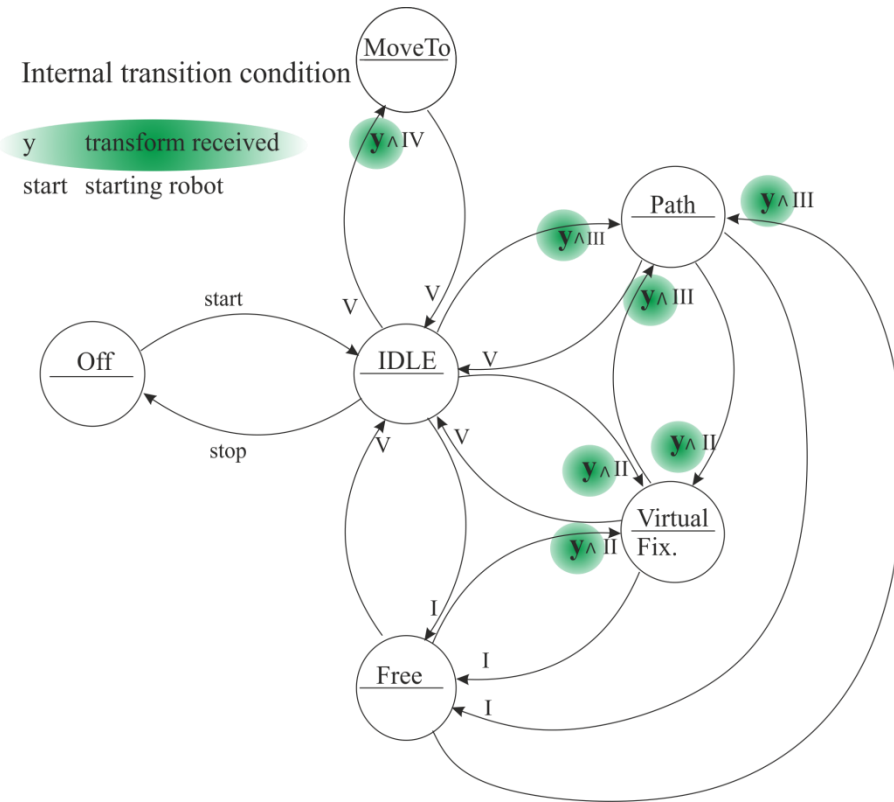
State machine – Transitions



Transitions

- By external request besides in case of error
- From position to impedance controlled states only via IDLE

State machine – Transitions



Transitions

- By external request besides in case of error
- From position to impedance controlled states only via IDLE
- To repositioning and targeting states after registration

LightWeightRobotIGT – Interface Concept

State machine – Control

IGTSessionManager

LWR State Control

Start cyclic communication

Get Fiducial from Robot

Init Phase

Start Visualization

Stop Visualization

Img/Rob

Joint

C:\Users\OptTrack_user\Documents\GitHub\RobotModell\

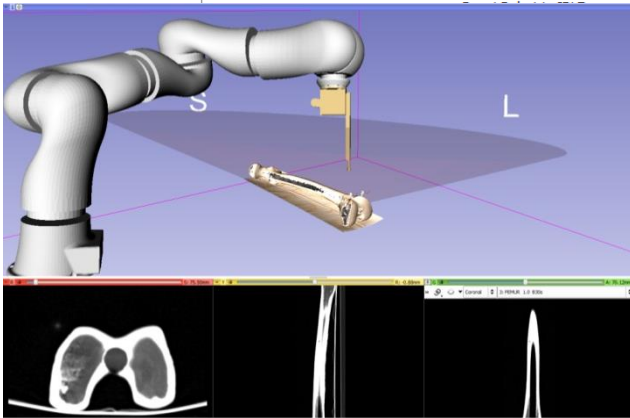
Load Robot STL

GravComp Virtual Fix. Move to PathImp

Path Impedance Control

End Point x,y,z 580 0 100

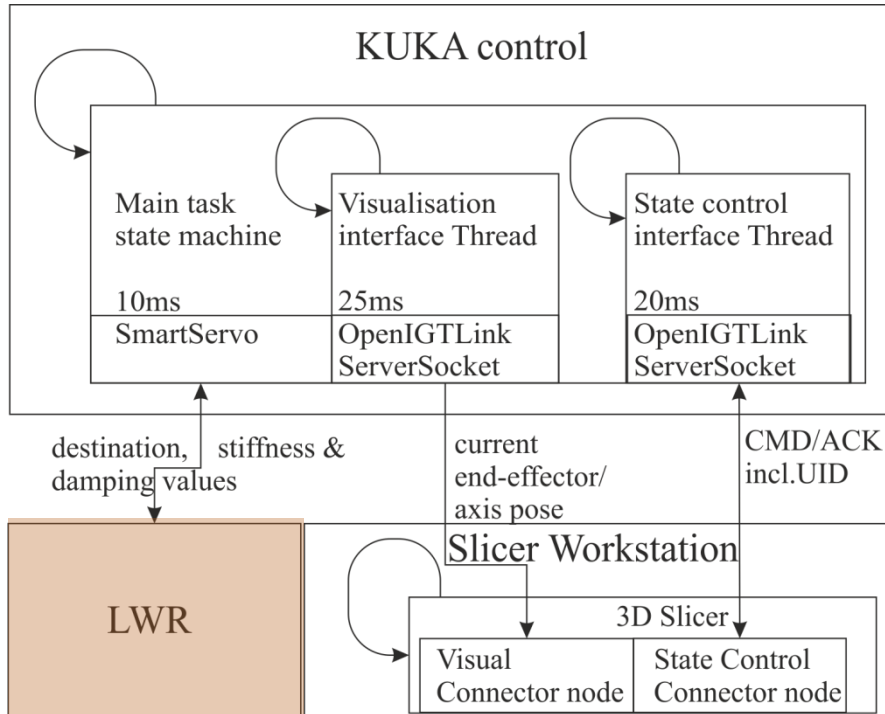
COFrame Robbase



3D Slicer Module LightWeightRobotIGT

- Sending commands strings
- Editing parameter for states
- Acquiring points for point based registration
- Visualisation of robot model and active virtual fixtures
- Cyclic communication

Test setup



Slicer workstation

- 3D Slicer module
LightWeightRobotIGT as state control

KUKA control

- Java robot application
 - Visualisation & state control interface thread
 - State machine thread

KUKA Light weight robot (LWR)

Tutorial

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