

HRI Lab #7, SP2024 525.786: Human Robotics Interaction

Introduction:

In this lab we will explore interfacing various types of motion tracking tools. These tools, in combination with the bioinstrumentation inputs you've used previously, can be used for natural and intuitive Human Robotic Interaction. The tools that we'll be using include the following devices:

- Inertial measurement Unit (3-axis, 6 Degrees of Freedom) on the Myo
- Kinect (20 Degrees of Freedom, Whole Body)

Setup the MiniVIE environment

```
thisPath = cd;
cd('C:\GitHub\MiniVIE');
MiniVIE.configurePath;

[MiniVIE.m] Configured MiniVIE path at: C:\GitHub\minivie

cd(thisPath);
```

Part 1: Inertial Measurement Unit on the Myo

Operating Principle: the Myo armband contains an Angular rate sensor, accelerometer, and magnetometer to resolve orientation. These sensors can be used to track motion of the arm in addition to the EMG signals

Before running the code below, be sure to start MyoUdp.exe in the MiniVIE/+Inputs folder

It might be more straightforward to run this in the Command Window (select, then hit F9)

```
% Setup the Myo Armband in matlab
hMyo = Inputs.MyoUdp.getInstance();

[MyoUdp] Calling constructor

hMyo.initialize()

[UserConfig.m] Calling constructor with config file
[UserConfig.m] No file found
[UserConfig.m] No file found
[UserConfig.m] No file found

Loaded pnet Version 2.0.5 2003-09-16 Copyright (C) Peter Rydesäter, Sweden, et al. , 1998 - 2003
[PnetClass] Opened pnet socket #0 at local port: 10001; Default destination: port 45001 @ 127.0.0.1
[PnetClass] Opened pnet socket #1 at local port: 10002; Default destination: port 45001 @ 127.0.0.1
[MyoUdp] UDP Data Stream 1-8 NOT Detected
[MyoUdp] UDP Data Stream 9-16 NOT Detected
ans = 0
```

```
pause(1)

% Ensure data is streaming
myoData = hMyo.getData();
```

```

if isempty(hMyo.Orientation)
    error('Setup Failed. MyoUdp Running?');
end

% Setup figure to show orientation
figure(1);
clf
daspect([1 1 1])
view(-170,15)

% Plot reference triad
PlotUtils.triad(eye(4),0.5)

```

ans = 10.0001

```

% Plot 'moving' triad
myoTriadHandle = PlotUtils.triad(eye(4),2);
StartStopForm([])
while StartStopForm()
    drawnow
    hMyo.getData(); % update stream receive
    Rxyz = hMyo.getEulerAngles; % Get roll pitch yaw
    disp(Rxyz)
    Rmat = LinAlg.makeRotationMtx(Rxyz); % create rotation matrix
    transMat = [Rmat [0; 0; 0]; 0 0 0 1];
    set(myoTriadHandle,'Matrix', transMat);
end

```

Warning: The JavaFrame figure property will be removed in a future release. For more information see UI Alternatives for MATLAB Apps on mathworks.com.

107.1941
29.6672
-141.7360

109.9814
29.7594
-138.5009

98.0325
27.8338
-158.6261

91.4443
22.8809
-169.8104

88.9113
15.3903
-178.7497

89.6040
10.0827
178.7190

91.4627
13.3717

179.3947

92.0965

17.9291

-179.7544

100.7285

33.4029

-173.6254

106.3653

39.7244

-168.4645

129.0708

51.6412

-146.8447

153.7129

52.2092

-122.8290

161.0280

50.1785

-115.9312

170.0095

44.9722

-108.1550

176.4553

39.5069

-104.0953

178.1866

37.9074

-103.6358

178.1871

34.4927

-107.1834

177.9701

29.8391

-112.1006

177.7071

28.1429

-114.2828

177.0480

24.9835

-119.4062

178.6591

23.9259

-121.4187

179.6831

24.2582

-121.5677

-178.3320

25.4084

-121.0565

-177.2728

26.0696

-120.3463

-174.9465

27.9696

-118.1073

-174.1929

29.6918

-117.3047

-171.1163

34.5985

-115.7503

-170.2851

36.6824

-114.3062

-172.1148

36.2173

-113.5047

-170.1974

32.3359

-110.5578

-168.5060

29.7072

-108.5941

-166.3405

28.6002

-107.3794

-163.9574

25.6177

-106.5480

-162.2480

24.2501

-104.7559

-159.4429

21.4584

-100.9070

-159.1489

19.4763

-100.7650

-160.7164

18.5960

-106.7665

-160.7112

18.1882

-107.5893

-159.3988

16.3976

-111.0098

-156.1409

14.6492

-111.1353

-151.9186

8.0726

-105.5318

-151.5082

7.4117

-104.8517

-150.8483

5.8557

-101.9113

-151.3668

5.9600

-99.8623

-151.5524

5.8165

-98.5803

-152.0410

5.8427

-98.3686

-152.1056

5.6273

-98.2651

-150.8585

4.0509

-96.7550

-149.9361

3.5357

-95.8680

-149.3173

3.5066

-94.3805

-148.3141

3.2673

-92.8686

-149.6427

6.8277

-94.9660

-155.3811

17.9163

-98.5604

-151.0476

27.1787

-98.9489

-150.3469

30.4721

-103.1837

-154.3445

26.5272

-109.7494

-156.2504

22.9854

-109.3142

-154.3631

19.6675

-104.6181

-153.8913

19.3086

-104.0264

-153.8159

19.0040

-103.5902

-154.1977

18.1638

-103.4984

-154.5036

18.4189

-104.4168

-154.1292

18.1173

-102.6628

-154.4991

17.8389

-102.2474

-152.7280

17.9526

-100.5577

-153.7264

17.8883

-100.6100

-153.0853

17.8506

-99.9087

-153.9828

17.1278

-99.5688

-152.3619

16.8163

-99.1079

-152.3619

16.8163

-99.1079

-153.6115

16.5144

-100.2358

-153.0627
16.4467
-99.7172

-153.3562
15.1786
-99.6525

-151.9539
14.1707
-99.4405

-151.3614
14.2954
-99.2089

-150.0531
14.8171
-98.0758

-149.4665
13.7497
-97.1827

-149.9745
12.8822
-97.4101

-149.6960
12.7431
-97.2029

-149.5364
13.4387
-96.9980

-149.6456
13.2968
-96.6734

-149.7378
12.9338
-96.8254

-150.2394
14.0659
-97.7405

-150.8357
14.8539
-98.4228

-151.5522
18.5119
-99.4985

-153.1775
36.3035
-98.3765

-147.5627
65.1111

-102.5228

-138.1780

85.0913

-103.2742

42.5698

70.1797

64.8283

43.0264

68.0439

64.5427

46.9588

60.3448

63.1633

53.3584

54.5966

62.3067

55.5040

56.6213

63.3423

54.8972

60.4056

66.1942

117.3005

81.0231

127.9763

-158.3234

50.4411

-151.7559

-163.8962

38.9422

-151.3205

-171.4679

19.9765

-146.6997

-178.7849

4.8388

-141.2014

-179.6092

2.1017

-138.9610

177.5846

-2.4812

-132.9506

176.0393

-3.9435

-127.3003

175.6039

-3.3380

-125.0037

175.6702

-3.3919

-125.1602

175.9318

-4.5312

-126.2860

176.5928

-4.6920

-127.0810

178.7248

4.9531

-135.4331

179.6604

26.1871

-151.3882

178.5882

32.6209

-155.6693

162.1171

55.6522

-174.6865

113.5766

68.4527

139.2425

92.4134

67.1515

118.4691

97.8546

70.6301

112.7562

92.5107

70.9843

103.9823

89.8187

71.4760

101.5994

119.9732

77.6464

134.1159

-167.6698

57.4001

-151.7543

-173.2134

29.5913

-152.6339

75.4100

75.3994

86.5355

45.2620
61.3482
69.6807

110.8609
73.2111
120.2391

162.9666
33.5133
-174.7757

147.7521
25.6887
-165.9190

133.1523
48.6848
176.6894

71.7762
50.9647
114.9776

65.9028
46.0284
107.4356

95.8234
23.5052
112.4984

114.2525
17.1085
129.2712

116.1080
14.6094
159.6934

121.8622
26.7555
-176.1734

121.7764
34.0731
-175.3310

119.9511
35.3282
178.2414

109.0590
36.6371
151.8509

27.7415
22.2884
97.6753

26.2083
5.5592

97.6268

27.1129

-0.1918

97.9521

28.9687

2.7400

98.4333

27.8752

9.1972

99.3393

27.0054

13.9434

98.9383

26.7978

14.8774

98.6172

26.2548

16.1677

98.0449

25.9386

16.1484

98.0007

26.0438

15.6348

98.6266

26.3197

15.8291

98.9474

26.2587

16.1677

98.9432

26.4961

17.1428

98.9697

42.0058

20.0655

99.2850

60.2212

27.2182

110.7498

61.1897

27.6768

113.8391

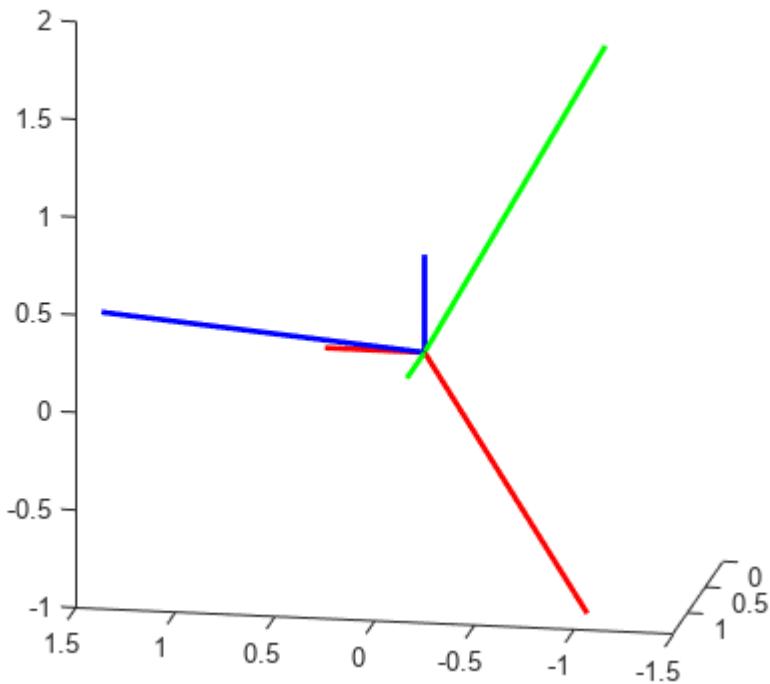
73.7195

27.0507

126.8496

78.4340

26.4962
132.4718



`hMyo.close()`

```
[MyoUdp] Deleting Udp comms object  
[PnetClass.m] Closed pnet socket #0 at local port: 10001  
[PnetClass.m] Closed pnet socket #1 at local port: 10002
```

cleanup;

```
cleanup
```

Questions:

1. What is the 'global' position of the myo armband?

The global position is (0,0,0)

1. What is its local coordinate frame?

The local coordinate frame is the orientation of the band relative to the global frame. The smaller axes represent the original axes of the myoband, where the local coordinate system sits in the middle of the myoband. The red axis runs horizontally through the middle of the band, the blue runs vertically through the band's logo, and the green runs orthogonally to both laterally.

1. What processing would you do to use the myo armband as a sensor to control the elbow flexion angle of a robotic device?

We would calculate the angles between the axes' orientations between the resting position of the arm and the final flexed position of the arm. We can use Linalg.Anglebetween to calculate this.

Use the Myo Orientation Sensors to Plot Arm Position

Edit the code below to show (in a streaming fashion) the real-time orientation and position of the forearm.

It might be more straightforward to run this in the Command Window (select, then hit F9)

```
hMyo = Inputs.MyoUdp.getInstance();
```

```
[MyoUdp] Returning existing object
```

```
hMyo.initialize()
```

```
[UserConfig.m] No file found  
[MyoUdp] UDP Comms already initialized  
ans = 0
```

```
pause(1)
```

```
% Ensure data is streaming  
myoData = hMyo.getData();  
if isempty(hMyo.Orientation)  
    error('Setup Failed. MyoUdp Running?');  
end
```

```

% Can you create a real time plot of your hand's position in space using
% the real-time orientation matrix from the Myo? assume the distance from
% Myo to hand is 25 cm.
myoOrigin = [0, 0, 0];
handPosStart = [0.25, 0, 0]; % in meters
figHandle = figure(1);
clf
daspect([1 1 1])
view(-170,15)

StartStopForm([])
while StartStopForm()

    hMyo.getData();
    Rxyz = hMyo.getEulerAngles;
    Rmat = LinAlg.makeRotationMtx(Rxyz);
    disp(Rmat)

    handPos = handPosStart * Rmat;

    plot3([0, handPos(1)], [0, handPos(2)], [0, handPos(3)], '.-');
    set(gca, 'XLim', [-0.25 0.25], 'YLim', [-0.25 0.25], 'ZLim', [-0.25 0.25]);
    xlabel('x'); ylabel('y'); zlabel('z');
    drawnow;

end

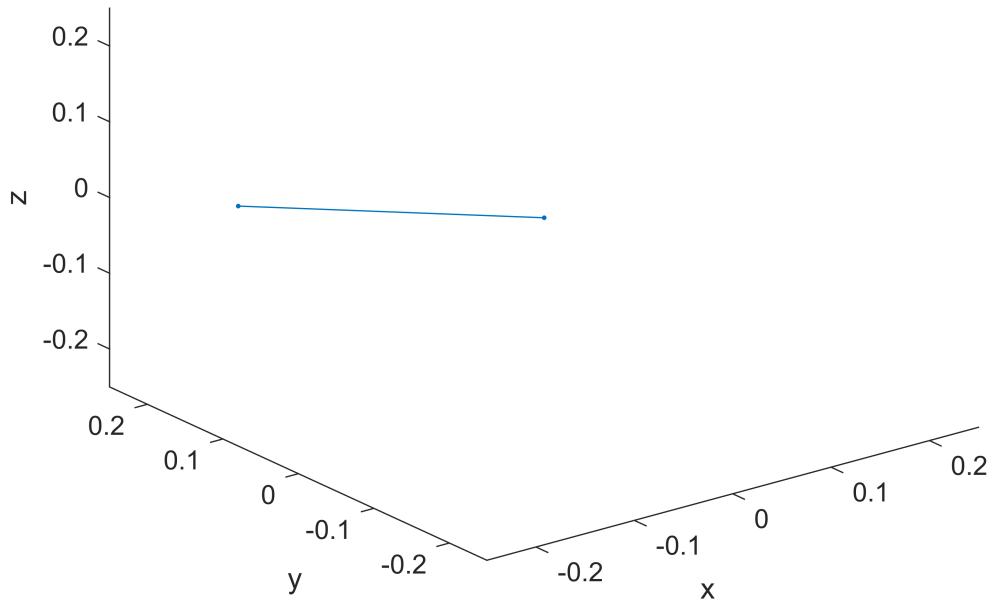
```

Warning: The JavaFrame figure property will be removed in a future release. For more information see UI Alternatives for MATLAB Apps on mathworks.com.

```

-0.8456    0.5201    0.1206
 0.0046   -0.2188    0.9758
 0.5339    0.8256    0.1826

```



$-0.8518 \quad 0.5050 \quad 0.1391$
 $0.0090 \quad -0.2515 \quad 0.9678$
 $0.5238 \quad 0.8257 \quad 0.2096$

$-0.8589 \quad 0.4878 \quad 0.1562$
 $0.0002 \quad -0.3045 \quad 0.9525$
 $0.5122 \quad 0.8181 \quad 0.2615$

$-0.8538 \quad 0.4935 \quad 0.1658$
 $0.0155 \quad -0.2943 \quad 0.9556$
 $0.5204 \quad 0.8185 \quad 0.2436$

$-0.8513 \quad 0.4977 \quad 0.1662$
 $0.0160 \quad -0.2920 \quad 0.9563$
 $0.5245 \quad 0.8167 \quad 0.2406$

$-0.8713 \quad 0.4585 \quad 0.1750$
 $-0.0001 \quad -0.3566 \quad 0.9343$
 $0.4908 \quad 0.8140 \quad 0.3107$

$-0.8881 \quad 0.4292 \quad 0.1645$
 $-0.0163 \quad -0.3871 \quad 0.9219$
 $0.4593 \quad 0.8160 \quad 0.3508$

$-0.8983 \quad 0.4167 \quad 0.1394$
 $-0.0321 \quad -0.3787 \quad 0.9250$
 $0.4383 \quad 0.8264 \quad 0.3536$

$-0.8724 \quad 0.4730 \quad 0.1231$
 $-0.0589 \quad -0.3518 \quad 0.9342$
 $0.4852 \quad 0.8078 \quad 0.3348$

$-0.8687 \quad 0.4836 \quad 0.1074$
 $-0.0629 \quad -0.3227 \quad 0.9444$

0.4913	0.8136	0.3108
-0.8649	0.4919	0.1004
-0.0640	-0.3064	0.9498
0.4979	0.8150	0.2965
-0.8670	0.4876	0.1028
-0.0620	-0.3102	0.9486
0.4944	0.8161	0.2992
-0.8710	0.4804	0.1033
-0.0571	-0.3078	0.9498
0.4880	0.8213	0.2955
-0.8719	0.4783	0.1048
-0.0536	-0.3060	0.9505
0.4867	0.8232	0.2924
-0.8729	0.4756	0.1086
-0.0489	-0.3069	0.9505
0.4854	0.8244	0.2912
-0.8736	0.4737	0.1118
-0.0437	-0.3051	0.9513
0.4847	0.8262	0.2873
-0.8732	0.4744	0.1121
-0.0425	-0.3033	0.9519
0.4856	0.8264	0.2850
-0.8758	0.4682	0.1177
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0.4816	0.8310	0.2783
-0.8728	0.4749	0.1124
-0.0398	-0.2990	0.9534
0.4864	0.8277	0.2799
-0.8775	0.4665	0.1114
-0.0464	-0.3137	0.9484
0.4774	0.8270	0.2969
-0.9162	0.3817	0.1220
-0.0404	-0.3909	0.9196
0.3986	0.8376	0.3736
-0.9636	0.2640	0.0416
-0.0890	-0.4636	0.8816
0.2520	0.8458	0.4702
-0.9588	0.2835	0.0202
-0.1116	-0.4409	0.8906
0.2613	0.8516	0.4544
-0.9527	0.3016	0.0377
-0.0922	-0.4052	0.9096
0.2896	0.8631	0.4138
-0.9526	0.2949	0.0746
-0.0610	-0.4255	0.9029
0.2980	0.8556	0.4233
-0.9677	0.2117	0.1366
0.0618	-0.3263	0.9433

0.2442	0.9213	0.3027
-0.9893	-0.0635	0.1316
0.1379	-0.1093	0.9844
-0.0482	0.9920	0.1169
-0.6451	-0.4761	0.5976
0.4517	0.3932	0.8009
-0.6163	0.7866	-0.0386
-0.4871	-0.5047	0.7128
0.4868	0.5207	0.7013
-0.7251	0.6886	-0.0079
-0.3038	-0.5107	0.8043
0.5969	0.5560	0.5784
-0.7426	0.6558	0.1359
-0.1668	-0.0573	0.9843
0.9065	0.3838	0.1759
-0.3879	0.9216	-0.0120
-0.2639	0.1571	0.9517
0.9602	0.1361	0.2438
-0.0913	0.9782	-0.1868
-0.7628	0.1320	0.6330
0.6454	0.0953	0.7579
0.0398	0.9867	-0.1579
-0.5880	-0.2832	0.7577
0.5545	0.5408	0.6325
-0.5889	0.7920	-0.1610
-0.2800	-0.2861	0.9164
0.7301	0.5563	0.3968
-0.6233	0.7802	0.0531
-0.0118	0.1032	0.9946
0.9999	-0.0101	0.0129
0.0114	0.9946	-0.1031
-0.1789	0.5688	0.8028
0.8584	-0.3085	0.4098
0.4808	0.7625	-0.4330
-0.5641	0.5941	0.5735
0.5589	-0.2366	0.7948
0.6079	0.7688	-0.1986
-0.6543	0.5941	0.4678
0.4551	-0.1846	0.8711
0.6039	0.7829	-0.1496
-0.7264	0.6309	0.2726
0.2706	-0.1021	0.9573
0.6318	0.7691	-0.0966
-0.6879	0.7100	0.1510
0.1429	-0.0715	0.9872
0.7116	0.7006	-0.0523
-0.6630	0.7359	0.1377
0.1679	-0.0331	0.9852

0.7296	0.6763	-0.1016
-0.5054	0.8190	0.2717
0.4025	-0.0548	0.9138
0.7633	0.5711	-0.3020
-0.3609	0.8781	0.3141
0.5399	-0.0779	0.8381
0.7605	0.4720	-0.4460
-0.1244	0.9079	0.4003
0.6991	-0.2060	0.6847
0.7041	0.3650	-0.6091
0.1494	0.8440	0.5152
0.8117	-0.4022	0.4235
0.5646	0.3549	-0.7452
0.3699	0.6778	0.6354
0.8402	-0.5359	0.0826
0.3965	0.5033	-0.7678
0.5299	0.4447	0.7221
0.8166	-0.4973	-0.2930
0.2288	0.7450	-0.6266
0.6332	0.2596	0.7292
0.7734	-0.2492	-0.5829
0.0304	0.9330	-0.3585
0.5994	0.1741	0.7813
0.7773	0.1067	-0.6201
-0.1913	0.9789	-0.0713
0.5586	0.1496	0.8158
0.7857	0.2198	-0.5783
-0.2658	0.9640	0.0053
0.4203	0.1269	0.8985
0.7909	0.4342	-0.4313
-0.4448	0.8918	0.0822
0.0789	0.0298	0.9964
0.6889	0.7208	-0.0761
-0.7205	0.6925	0.0363
-0.2581	-0.1141	0.9593
0.4340	0.8735	0.2207
-0.8631	0.4733	-0.1759
-0.5625	-0.4883	0.6671
-0.1749	0.8590	0.4813
-0.8081	0.1541	-0.5686
-0.5351	-0.6421	0.5490
-0.3603	0.7613	0.5392
-0.7641	0.0907	-0.6387
-0.5630	-0.6329	0.5315
-0.2772	0.7504	0.6000
-0.7786	0.1904	-0.5979
-0.6030	-0.5808	0.5469
-0.2071	0.7760	0.5957

-0.7704	0.2460	-0.5882
-0.6763	-0.5069	0.5345
-0.1669	0.8122	0.5590
-0.7174	0.2889	-0.6339
-0.7292	-0.4787	0.4889
-0.2024	0.8335	0.5142
-0.6536	0.2760	-0.7047
-0.8068	-0.4635	0.3663
-0.3131	0.8613	0.4002
-0.5010	0.2082	-0.8401
-0.8427	-0.5268	0.1111
-0.5010	0.8429	0.1962
-0.1970	0.1097	-0.9743
-0.7717	-0.5722	-0.2776
-0.6148	0.7828	0.0956
0.1626	0.2445	-0.9559
-0.7537	-0.5206	-0.4012
-0.6168	0.7711	0.1581
0.2270	0.3666	-0.9022
-0.8104	-0.4170	-0.4116
-0.5649	0.7424	0.3601
0.1554	0.5243	-0.8372
-0.8928	-0.4499	-0.0211
-0.3587	0.6819	0.6374
-0.2724	0.5766	-0.7702
-0.8178	-0.4766	0.3225
-0.1369	0.7054	0.6955
-0.5590	0.5246	-0.6421
-0.4415	-0.3084	0.8426
0.2329	0.8675	0.4395
-0.8665	0.3903	-0.3112
-0.2042	-0.1526	0.9670
0.5363	0.8089	0.2409
-0.8189	0.5678	-0.0833
0.0995	-0.0283	0.9946
0.7850	0.6165	-0.0610
-0.6115	0.7869	0.0835
0.3741	-0.1135	0.9204
0.8804	0.3553	-0.3140
-0.2914	0.9278	0.2329
0.5928	-0.1981	0.7806
0.7818	-0.0913	-0.6169
0.1935	0.9759	0.1007
0.6034	-0.1706	0.7790
0.7370	-0.2537	-0.6265
0.3045	0.9521	-0.0273
0.5207	-0.1090	0.8468
0.7391	-0.4389	-0.5110

0.4273	0.8919	-0.1479
0.3595	0.1322	0.9237
0.7717	-0.5986	-0.2147
0.5246	0.7900	-0.3172
0.0125	0.5198	0.8542
0.7530	-0.5670	0.3340
0.6579	0.6390	-0.3985
-0.2986	0.6554	0.6937
0.6475	-0.3949	0.6517
0.7011	0.6438	-0.3065
-0.4693	0.6467	0.6013
0.5187	-0.3492	0.7804
0.7146	0.6781	-0.1716
-0.7756	0.5296	0.3435
0.2616	-0.2256	0.9385
0.5744	0.8177	0.0364
-0.9278	0.3477	0.1351
0.0626	-0.2119	0.9753
0.3677	0.9133	0.1749
-0.9456	0.3244	0.0241
-0.0525	-0.2254	0.9728
0.3211	0.9186	0.2302
-0.9080	0.4178	0.0305
-0.0696	-0.2222	0.9725
0.4131	0.8809	0.2308
-0.8290	0.5470	0.1164
0.0219	-0.1762	0.9841
0.5588	0.8184	0.1341
-0.6502	0.7176	0.2497
0.2321	-0.1254	0.9646
0.7235	0.6851	-0.0850
-0.4388	0.8250	0.3561
0.4453	-0.1445	0.8836
0.7805	0.5463	-0.3040
-0.1692	0.8470	0.5040
0.6276	-0.3017	0.7177
0.7599	0.4377	-0.4805
0.0349	0.8087	0.5872
0.7589	-0.4037	0.5109
0.6502	0.4278	-0.6279
0.2455	0.5408	0.8045
0.8879	-0.4586	0.0374
0.3892	0.7052	-0.5927
0.4406	0.2589	0.8596
0.8845	-0.2887	-0.3664
0.1533	0.9218	-0.3562
0.4901	0.0511	0.8701
0.8711	0.0055	-0.4910

-0.0298	0.9987	-0.0418
0.1695	-0.1003	0.9804
0.9195	0.3742	-0.1207
-0.3548	0.9219	0.1557
-0.2497	-0.1913	0.9492
0.7306	0.6061	0.3144
-0.6355	0.7720	-0.0116
-0.4736	-0.3490	0.8087
0.3917	0.7389	0.5483
-0.7888	0.5764	-0.2132
-0.5250	-0.5089	0.6822
0.0793	0.7688	0.6345
-0.8474	0.3872	-0.3632
-0.4662	-0.7078	0.5308
-0.1785	0.6629	0.7271
-0.8665	0.2442	-0.4354
-0.4404	-0.7543	0.4869
-0.1978	0.6105	0.7669
-0.8757	0.2414	-0.4181
-0.4459	-0.7990	0.4035
-0.1685	0.5176	0.8389
-0.8791	0.3060	-0.3654
-0.4433	-0.8299	0.3388
-0.1355	0.4356	0.8899
-0.8861	0.3485	-0.3056
-0.4150	-0.8880	0.1981
-0.1431	0.2787	0.9497
-0.8985	0.3658	-0.2427
-0.3412	-0.9398	-0.0215
-0.1940	0.0480	0.9798
-0.9198	0.3385	-0.1986
-0.2691	-0.9161	-0.2972
-0.2431	-0.2340	0.9414
-0.9319	0.3256	-0.1598
-0.2757	-0.8548	-0.4396
-0.2618	-0.3733	0.8900
-0.9249	0.3605	-0.1209
-0.3415	-0.7329	-0.5884
-0.3096	-0.5034	0.8067
-0.8874	0.4577	-0.0550
-0.5271	-0.5573	-0.6416
-0.3776	-0.5228	0.7643
-0.7613	0.6451	0.0651
-0.6931	-0.4725	-0.5444
-0.3054	-0.4916	0.8155
-0.6529	0.7315	0.1964
-0.8502	-0.4882	-0.1970
0.0153	-0.3970	0.9177

-0.5262	0.7772	0.3450
-0.8951	-0.4453	-0.0215
0.1609	-0.3678	0.9159
-0.4158	0.8164	0.4009
-0.9199	-0.3621	0.1506
0.2848	-0.3528	0.8913
-0.2696	0.8628	0.4276
-0.9212	-0.2695	0.2805
0.3690	-0.3769	0.8496
-0.1232	0.8862	0.4467
-0.9109	-0.2038	0.3588
0.4105	-0.3589	0.8382
-0.0421	0.9108	0.4106
-0.9109	-0.1813	0.3706
0.4109	-0.3182	0.8544
-0.0370	0.9305	0.3643
-0.9345	-0.1817	0.3060
0.3440	-0.2414	0.9074
-0.0910	0.9533	0.2881
-0.9431	-0.1997	0.2659
0.3069	-0.2150	0.9271
-0.1280	0.9560	0.2640
-0.9451	-0.2159	0.2452
0.2876	-0.1933	0.9381
-0.1552	0.9571	0.2448
-0.9442	-0.2183	0.2468
0.2897	-0.1936	0.9373
-0.1569	0.9565	0.2460
-0.9430	-0.1824	0.2782
0.3129	-0.2026	0.9279
-0.1129	0.9621	0.2481
-0.9409	-0.1424	0.3072
0.3314	-0.2014	0.9217
-0.0694	0.9691	0.2367
-0.9320	-0.0646	0.3565
0.3621	-0.1996	0.9105
0.0123	0.9777	0.2095
-0.9041	0.0579	0.4234
0.4027	-0.2162	0.8894
0.1430	0.9746	0.1722
-0.8423	0.2121	0.4955
0.4485	-0.2341	0.8626
0.2990	0.9488	0.1020
-0.8149	0.2927	0.5003
0.4506	-0.2232	0.8644
0.3647	0.9298	0.0500
-0.8134	0.3399	0.4720
0.4471	-0.1538	0.8812

0.3722	0.9278	-0.0269
-0.8237	0.3787	0.4220
0.4278	-0.0733	0.9009
0.3721	0.9226	-0.1016
-0.8274	0.3844	0.4095
0.4238	-0.0510	0.9043
0.3684	0.9218	-0.1207
-0.8306	0.3871	0.4004
0.4190	-0.0394	0.9071
0.3669	0.9212	-0.1295
-0.8344	0.3856	0.3938
0.4148	-0.0311	0.9094
0.3629	0.9221	-0.1340
-0.8361	0.3907	0.3851
0.4128	-0.0143	0.9107
0.3613	0.9204	-0.1493
-0.8379	0.3975	0.3740
0.4104	0.0073	0.9119
0.3598	0.9176	-0.1693
-0.8392	0.3949	0.3739
0.4091	0.0055	0.9125
0.3583	0.9187	-0.1662
-0.8397	0.3954	0.3723
0.4084	0.0080	0.9127
0.3579	0.9185	-0.1682
-0.8388	0.3973	0.3722
0.4094	0.0097	0.9123
0.3589	0.9176	-0.1708
-0.8381	0.3955	0.3757
0.4099	0.0022	0.9121
0.3600	0.9184	-0.1640
-0.8344	0.3975	0.3819
0.4146	-0.0040	0.9100
0.3633	0.9176	-0.1614
-0.8331	0.4028	0.3790
0.4162	0.0053	0.9093
0.3643	0.9153	-0.1720
-0.8325	0.4035	0.3796
0.4178	0.0072	0.9085
0.3639	0.9149	-0.1745
-0.8312	0.4034	0.3826
0.4213	0.0079	0.9069
0.3628	0.9150	-0.1765
-0.8299	0.4037	0.3851
0.4228	0.0047	0.9062
0.3640	0.9149	-0.1746
-0.8276	0.3954	0.3985
0.4273	-0.0167	0.9040

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-0.8234	0.3715	0.4289
0.4343	-0.0737	0.8977
0.3651	0.9255	-0.1007
-0.8195	0.3434	0.4588
0.4379	-0.1413	0.8878
0.3697	0.9285	-0.0346
-0.8398	0.2479	0.4829
0.4111	-0.2903	0.8641
0.3544	0.9243	0.1419
-0.9136	0.0919	0.3961
0.3301	-0.4013	0.8544
0.2375	0.9113	0.3363
-0.9598	0.0551	0.2752
0.2324	-0.3933	0.8895
0.1573	0.9177	0.3647
-0.9825	0.0268	0.1844
0.1558	-0.4245	0.8919
0.1022	0.9050	0.4129
-0.9928	-0.0252	0.1174
0.1167	-0.4350	0.8929
0.0286	0.9001	0.4348
-0.9832	-0.1817	0.0148
0.0952	-0.4426	0.8917
-0.1554	0.8781	0.4525
-0.8548	-0.4759	-0.2070
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-0.6438	-0.6693	-0.3709
0.0300	-0.5065	0.8617
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-0.5418	-0.7296	-0.4173
0.0289	-0.5124	0.8583
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-0.0145	-0.5045	0.8633
-0.7403	0.5858	0.3299
-0.7851	-0.5057	-0.3577
-0.0737	-0.4972	0.8645
-0.6150	0.7051	0.3530
-0.9349	-0.2493	-0.2526
-0.1404	-0.3938	0.9084
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-0.9852	0.0694	-0.1570
-0.1697	-0.2549	0.9520
0.0261	0.9645	0.2629
-0.9212	0.3817	-0.0761
-0.1275	-0.1111	0.9856

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-0.0548	0.0542	0.9970
0.6662	0.7457	-0.0039
-0.6361	0.7503	-0.1800
-0.0978	0.1530	0.9834
0.7654	0.6431	-0.0239
-0.6404	0.7268	-0.2485
-0.1732	0.1785	0.9686
0.7483	0.6633	0.0116
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-0.2054	0.2503	0.9461
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-0.2276	0.2795	0.9328
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-0.2204	0.2649	0.9388
0.8094	0.5867	0.0244
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-0.2061	0.2466	0.9470
0.8138	0.5806	0.0259
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-0.1922	0.2365	0.9524
0.8202	0.5717	0.0235
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0.8193	0.5719	0.0413
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-0.1110	-0.0015	0.9938
0.7956	0.5992	0.0898
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-0.0356	-0.1881	0.9815
0.7609	0.6316	0.1486
-0.7090	0.6224	0.3316
0.1030	-0.3737	0.9218
0.6977	0.6877	0.2008
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0.1248	-0.4152	0.9011
0.6792	0.6978	0.2275
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0.7538	0.6392	0.1524
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-0.1119	-0.0864	0.9900

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-0.0971	-0.1214	0.9878
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-0.0609	-0.3343	0.9405
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0.2280	-0.4620	0.8571
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0.2266	-0.4183	0.8796
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-0.9520	0.1266	0.2786
0.2079	-0.4005	0.8924

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0.1640	-0.3368	0.9272
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0.0998	-0.3781	0.9204
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-0.9914	0.0882	0.0970
0.0602	-0.3508	0.9345
0.1164	0.9323	0.3425
-0.9913	0.0951	0.0915
0.0556	-0.3275	0.9432
0.1197	0.9401	0.3193
-0.9920	0.0626	0.1097
0.0829	-0.3324	0.9395
0.0953	0.9411	0.3246
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0.0971	-0.4331	0.8961
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0.0326	-0.3603	0.9323
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0.0364	-0.3208	0.9464
0.0400	0.9468	0.3194
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-0.1654	-0.2862	0.9438
0.1865	0.9306	0.3148
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0.3073	0.9083	0.2838
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0.4836	-0.0146	0.8752
0.8349	0.3080	-0.4562
0.0304	0.9797	0.1981
0.6218	-0.1737	0.7637
0.7826	0.1000	-0.6144
0.1848	0.9627	0.1979
0.6924	-0.2704	0.6689
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0.2592	0.9504	0.1718
0.7277	-0.3091	0.6123
0.6350	-0.0336	-0.7718
0.0170	0.9901	0.1395
0.6146	-0.1204	0.7796
0.7887	0.0724	-0.6105
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0.4274	-0.0132	0.9040
0.8458	0.3590	-0.3946
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0.1243	0.0184	0.9921
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0.0110	-0.0037	0.9999

0.6012	0.7991	-0.0037
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0.4364	0.8965	0.0770
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0.2719	0.9499	0.1544
-0.9409	0.3341	0.0555
-0.0079	-0.1853	0.9826
0.3386	0.9241	0.1770
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0.4785	0.8540	0.2042
-0.7680	0.6210	0.1565
-0.0326	-0.2820	0.9588
0.6396	0.7313	0.2369
-0.6639	0.7198	0.2028
-0.0648	-0.3256	0.9433
0.7450	0.6131	0.2628
-0.6503	0.7266	0.2218
-0.1044	-0.3747	0.9213
0.7525	0.5760	0.3195
-0.6101	0.7737	0.1710
-0.1839	-0.3482	0.9192
0.7707	0.5293	0.3547
-0.5885	0.8012	0.1082
-0.2647	-0.3174	0.9106
0.7639	0.5073	0.3989
-0.5846	0.8065	0.0884
-0.2955	-0.3132	0.9025
0.7556	0.5015	0.4214
-0.5796	0.8115	0.0753
-0.3136	-0.3073	0.8984
0.7522	0.4971	0.4326
-0.5711	0.8184	0.0635
-0.3326	-0.3015	0.8936
0.7505	0.4892	0.4444
-0.5656	0.8222	0.0631
-0.3399	-0.3021	0.8906
0.7513	0.4823	0.4504
-0.5613	0.8258	0.0539
-0.3442	-0.2922	0.8923
0.7526	0.4823	0.4483
-0.5532	0.8313	0.0543
-0.3320	-0.2798	0.9008

0.7640	0.4803	0.4308
-0.5600	0.8261	0.0636
-0.3218	-0.2876	0.9021
0.7635	0.4847	0.4268
-0.5653	0.8224	0.0641
-0.3173	-0.2885	0.9034
0.7614	0.4903	0.4240
-0.5734	0.8166	0.0660
-0.3137	-0.2932	0.9031
0.7569	0.4971	0.4243
-0.5819	0.8107	0.0650
-0.3087	-0.2941	0.9045
0.7524	0.5063	0.4214
-0.5873	0.8067	0.0654
-0.3065	-0.2964	0.9045
0.7491	0.5112	0.4214
-0.5916	0.8038	0.0628
-0.3064	-0.2963	0.9046
0.7457	0.5159	0.4216
-0.5932	0.8030	0.0572
-0.3079	-0.2919	0.9055
0.7439	0.5195	0.4204
-0.5958	0.8012	0.0552
-0.3059	-0.2899	0.9068
0.7426	0.5234	0.4179
-0.5973	0.8000	0.0568
-0.3006	-0.2890	0.9089
0.7435	0.5258	0.4131
-0.5974	0.7997	0.0596
-0.2920	-0.2862	0.9126
0.7469	0.5278	0.4045
-0.5973	0.7998	0.0604
-0.2802	-0.2786	0.9186
0.7515	0.5317	0.3905
-0.5957	0.8010	0.0603
-0.2686	-0.2694	0.9248
0.7570	0.5347	0.3756
-0.5963	0.8006	0.0593
-0.2565	-0.2600	0.9309
0.7607	0.5399	0.3604
-0.6078	0.7914	0.0651
-0.2350	-0.2576	0.9372
0.7585	0.5543	0.3426
-0.6345	0.7659	0.1039
-0.1894	-0.2843	0.9398
0.7494	0.5767	0.3255
-0.6426	0.7536	0.1385
-0.1633	-0.3113	0.9362

0.7486	0.5790	0.3231
-0.6222	0.7536	0.2119
-0.0196	-0.2856	0.9581
0.7826	0.5920	0.1925
-0.5102	0.7869	0.3471
0.2252	-0.2673	0.9369
0.8301	0.5562	-0.0408
-0.4321	0.8239	0.3668
0.3210	-0.2395	0.9163
0.8428	0.5136	-0.1610
-0.2136	0.9007	0.3782
0.4891	-0.2365	0.8395
0.8456	0.3644	-0.3900
0.1309	0.9104	0.3925
0.6952	-0.3665	0.6184
0.7068	0.1919	-0.6809
0.3518	0.6058	0.7137
0.8237	-0.5625	0.0715
0.4448	0.5627	-0.6968
0.4041	0.1841	0.8960
0.9045	-0.2266	-0.3613
0.1365	0.9564	-0.2581
0.3173	-0.0055	0.9483
0.9267	0.2141	-0.3088
-0.2014	0.9768	0.0730
0.2051	-0.0872	0.9748
0.7944	0.5967	-0.1138
-0.5718	0.7977	0.1917
0.0038	-0.1685	0.9857
0.5538	0.8211	0.1382
-0.8327	0.5453	0.0965
-0.2420	-0.2636	0.9338
0.2785	0.9030	0.3271
-0.9294	0.3392	-0.1451
-0.4989	-0.4141	0.7613
-0.0164	0.8828	0.4695
-0.8665	0.2218	-0.4472
-0.7329	-0.5400	0.4139
-0.1925	0.7481	0.6350
-0.6526	0.3857	-0.6522
-0.8482	-0.3966	0.3510
-0.0260	0.6932	0.7203
-0.5290	0.6018	-0.5983
-0.9872	-0.0749	0.1408
0.0905	0.4637	0.8813
-0.1314	0.8828	-0.4510
-0.8352	0.5252	0.1628
0.1614	-0.0488	0.9857

0.5256	0.8496	-0.0440
-0.5369	0.8251	0.1762
-0.0651	-0.2487	0.9664
0.8412	0.5074	0.1872
-0.5581	0.8174	0.1426
-0.1001	-0.2369	0.9664
0.8237	0.5251	0.2141
-0.5067	0.8529	0.1255
-0.1460	-0.2283	0.9626
0.8497	0.4694	0.2403
-0.4524	0.8901	-0.0547
-0.3789	-0.1363	0.9153
0.8073	0.4349	0.3989
-0.4633	0.8855	-0.0345
-0.4147	-0.1823	0.8915
0.7831	0.4273	0.4517
-0.5563	0.8300	0.0394
-0.3948	-0.3058	0.8664
0.7312	0.4664	0.4978
-0.5873	0.8044	0.0897
-0.3692	-0.3648	0.8548
0.7203	0.4688	0.5112
-0.5705	0.8161	0.0924
-0.3744	-0.3586	0.8551
0.7310	0.4532	0.5101
-0.5523	0.8284	0.0932
-0.3828	-0.3513	0.8544
0.7405	0.4363	0.5112
-0.5485	0.8309	0.0935
-0.3812	-0.3481	0.8565
0.7442	0.4342	0.5077
-0.5487	0.8304	0.0968
-0.3785	-0.3501	0.8568
0.7454	0.4335	0.5064
-0.5518	0.8288	0.0926
-0.3757	-0.3462	0.8597
0.7446	0.4396	0.5024
-0.5546	0.8271	0.0915
-0.3731	-0.3455	0.8611
0.7438	0.4434	0.5002
-0.5667	0.8171	0.1062
-0.3582	-0.3604	0.8613
0.7420	0.4500	0.4969
-0.5747	0.8107	0.1119
-0.3488	-0.3663	0.8627
0.7403	0.4567	0.4932
-0.5782	0.8080	0.1129
-0.3458	-0.3681	0.8631

0.7390	0.4600	0.4923
-0.5794	0.8061	0.1206
-0.3411	-0.3743	0.8623
0.7402	0.4584	0.4918
-0.5793	0.8059	0.1219
-0.3406	-0.3753	0.8620
0.7405	0.4579	0.4920
-0.5787	0.8062	0.1228
-0.3401	-0.3755	0.8621
0.7412	0.4572	0.4916
-0.5784	0.8061	0.1251
-0.3398	-0.3774	0.8614
0.7416	0.4558	0.4922
-0.5787	0.8052	0.1292
-0.3359	-0.3797	0.8620
0.7432	0.4554	0.4902
-0.5775	0.8054	0.1334
-0.3325	-0.3813	0.8626
0.7456	0.4537	0.4880
-0.5745	0.8072	0.1357
-0.3311	-0.3808	0.8634
0.7485	0.4511	0.4860
-0.5750	0.8073	0.1327
-0.3336	-0.3794	0.8630
0.7470	0.4520	0.4875
-0.5776	0.8077	0.1184
-0.3371	-0.3680	0.8665
0.7435	0.4606	0.4849
-0.5776	0.8093	0.1064
-0.3445	-0.3598	0.8671
0.7401	0.4642	0.4866
-0.5784	0.8114	0.0847
-0.3569	-0.3451	0.8681
0.7336	0.4718	0.4892
-0.5827	0.8088	0.0791
-0.3494	-0.3372	0.8742
0.7337	0.4818	0.4791
-0.5885	0.8065	0.0566
-0.3370	-0.3083	0.8896
0.7349	0.5045	0.4532
-0.5951	0.8013	0.0615
-0.3111	-0.3002	0.9017
0.7410	0.5175	0.4279
-0.5852	0.7999	0.1329
-0.2427	-0.3292	0.9126
0.7737	0.5018	0.3867
-0.5729	0.7947	0.2006
-0.1922	-0.3682	0.9097

0.7968	0.4826	0.3637
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-0.1145	-0.4305	0.8953
0.8286	0.4557	0.3252
-0.5306	0.7580	0.3794
-0.0571	-0.4785	0.8762
0.8457	0.4432	0.2971
-0.5100	0.7588	0.4052
-0.0524	-0.4976	0.8658
0.8586	0.4203	0.2935
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-0.0828	-0.5211	0.8495
0.8662	0.3838	0.3198
-0.4937	0.7590	0.4245
-0.0879	-0.5292	0.8439
0.8652	0.3793	0.3280
-0.5300	0.7431	0.4085
-0.0687	-0.5178	0.8527
0.8452	0.4239	0.3255
-0.5243	0.7217	0.4519
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0.8490	0.4021	0.3429
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-0.0589	-0.5646	0.8233
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0.8664	0.3841	0.3192
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0.8734	0.3754	0.3102
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-0.0663	-0.5303	0.8452
0.8744	0.3771	0.3052
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-0.0590	-0.5302	0.8458
0.8741	0.3818	0.3003
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0.8769	0.3765	0.2988
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0.8810	0.3649	0.3011
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0.8833	0.3586	0.3021
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0.0061	-0.2867	0.9580
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0.7915	0.5863	0.1724
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0.7902	0.5871	0.1761
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0.7842	0.5930	0.1825
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0.7758	0.6011	0.1917
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0.7762	0.5983	0.1989
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0.6956	0.6371	0.3320
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0.6759	0.6453	0.3561
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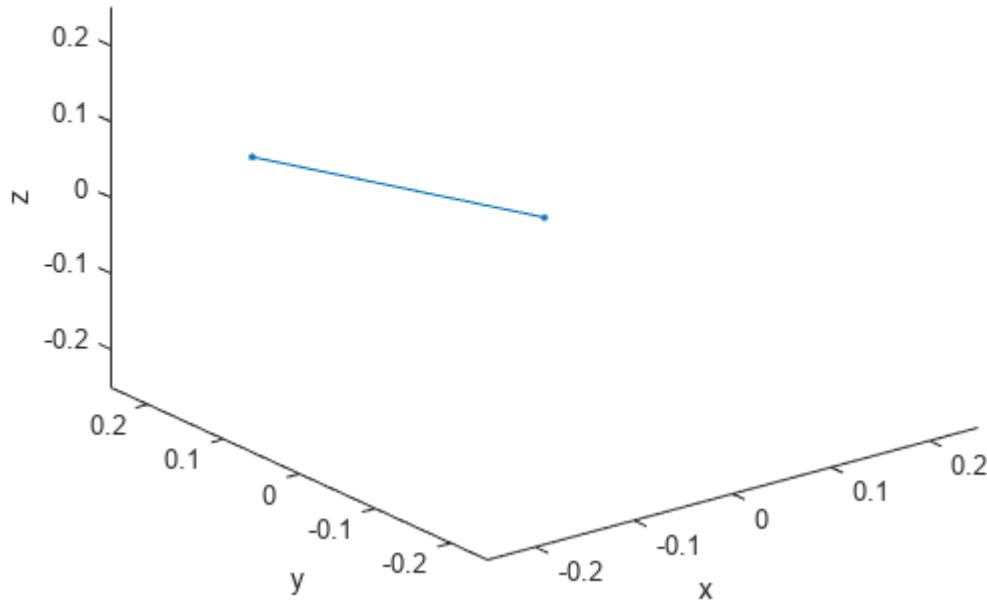
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-0.5125	0.8559	0.0692
-0.1658	-0.1777	0.9700
0.8425	0.4856	0.2330
-0.5193	0.8515	0.0727
-0.1605	-0.1808	0.9703
0.8394	0.4922	0.2306
-0.5179	0.8530	0.0642
-0.1591	-0.1698	0.9726
0.8405	0.4935	0.2236
-0.5147	0.8553	0.0593
-0.1565	-0.1617	0.9743
0.8430	0.4922	0.2171
-0.5137	0.8560	0.0587
-0.1563	-0.1607	0.9745
0.8436	0.4914	0.2164
-0.5133	0.8562	0.0591
-0.1566	-0.1612	0.9744
0.8438	0.4909	0.2168
-0.5172	0.8536	0.0615
-0.1513	-0.1619	0.9751
0.8424	0.4951	0.2129
-0.5325	0.8435	0.0707
-0.1467	-0.1742	0.9737
0.8336	0.5082	0.2165
-0.5495	0.8316	0.0798
-0.1318	-0.1805	0.9747
0.8250	0.5251	0.2088
-0.5605	0.8212	0.1075
-0.0996	-0.1957	0.9756
0.8221	0.5361	0.1915
-0.5686	0.8134	0.1228
-0.0857	-0.2071	0.9746
0.8181	0.5436	0.1875
-0.5719	0.8077	0.1432
-0.0616	-0.2163	0.9744
0.8180	0.5484	0.1735
-0.5668	0.8106	0.1468
-0.0533	-0.2139	0.9754
0.8221	0.5451	0.1645



`hMyo.close()`

```
[MyoUdp] Deleting Udp comms object  
[PnetClass.m] Closed pnet socket #0 at local port: 10001  
[PnetClass.m] Closed pnet socket #1 at local port: 10002
```

cleanup;

Part 2: Kinect

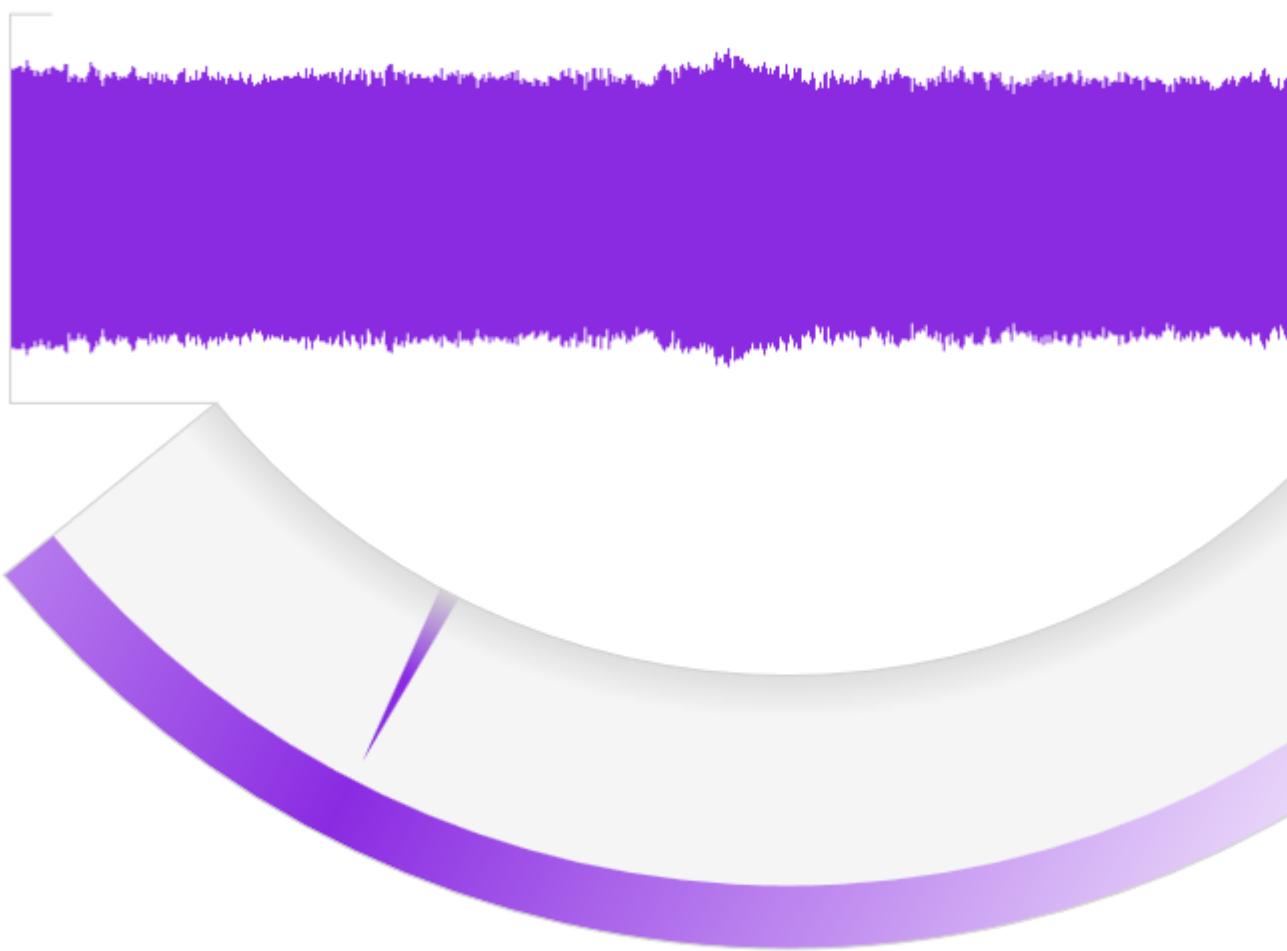
Open "SDK Browser for Kinect" (search in Windows Start Menu)

Run the following examples:

1. Audio Basics
2. Depth Basics
3. Face Tracking Basics
4. Skeletal Basics

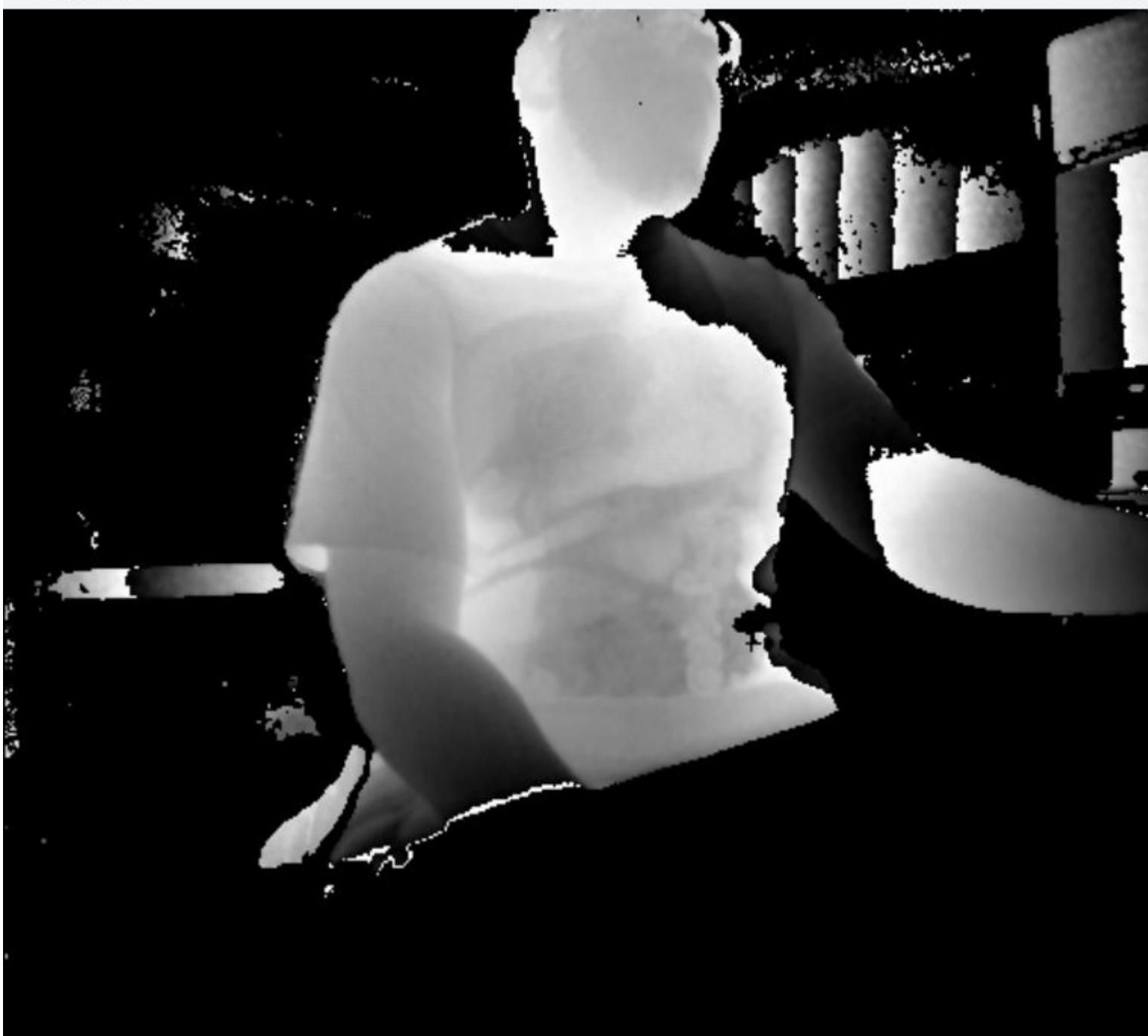
Copy and paste window screenshots from each:

1. **Audio Basic**

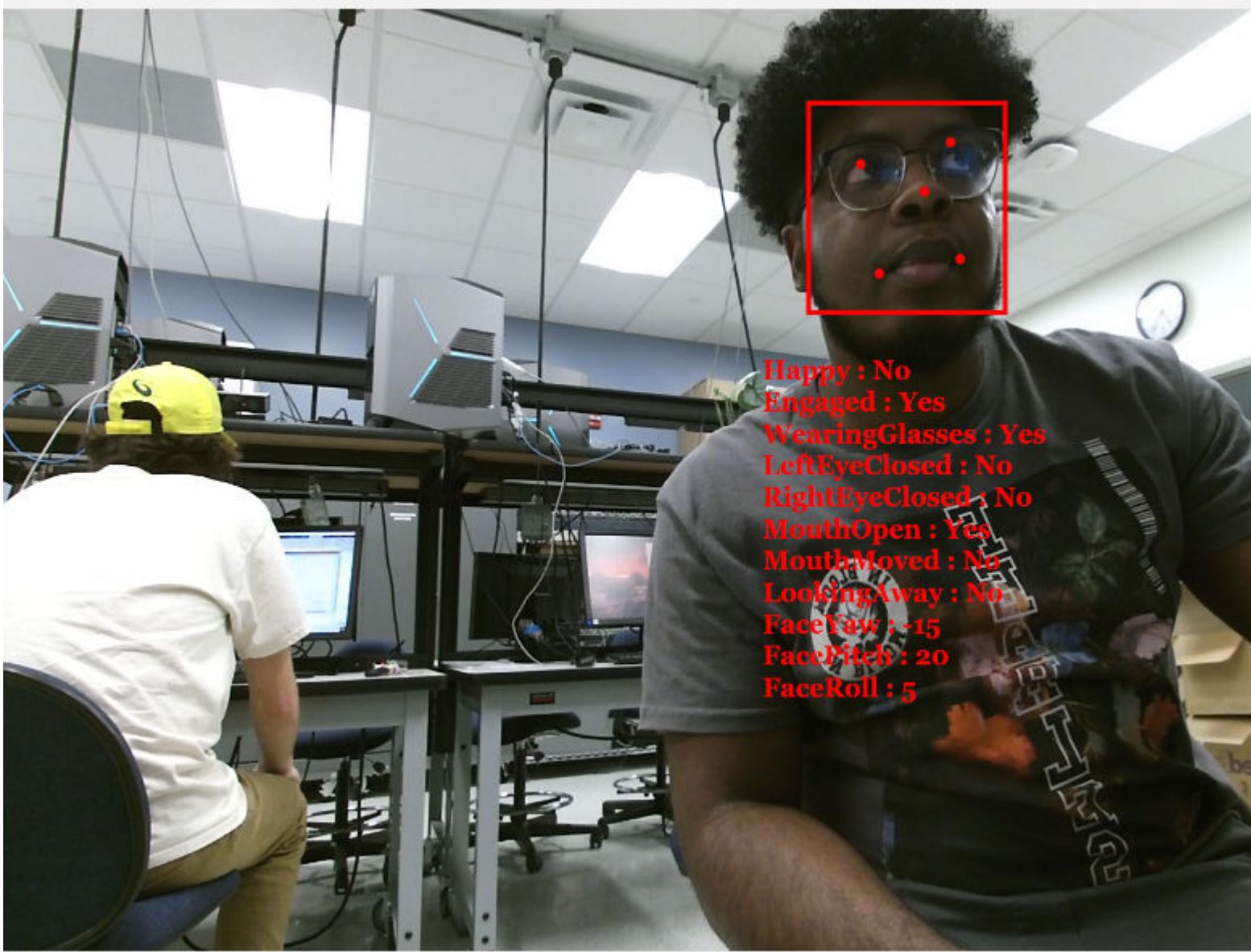


Beam Angle: -27 deg, Beam Angle Confidence: 0.00

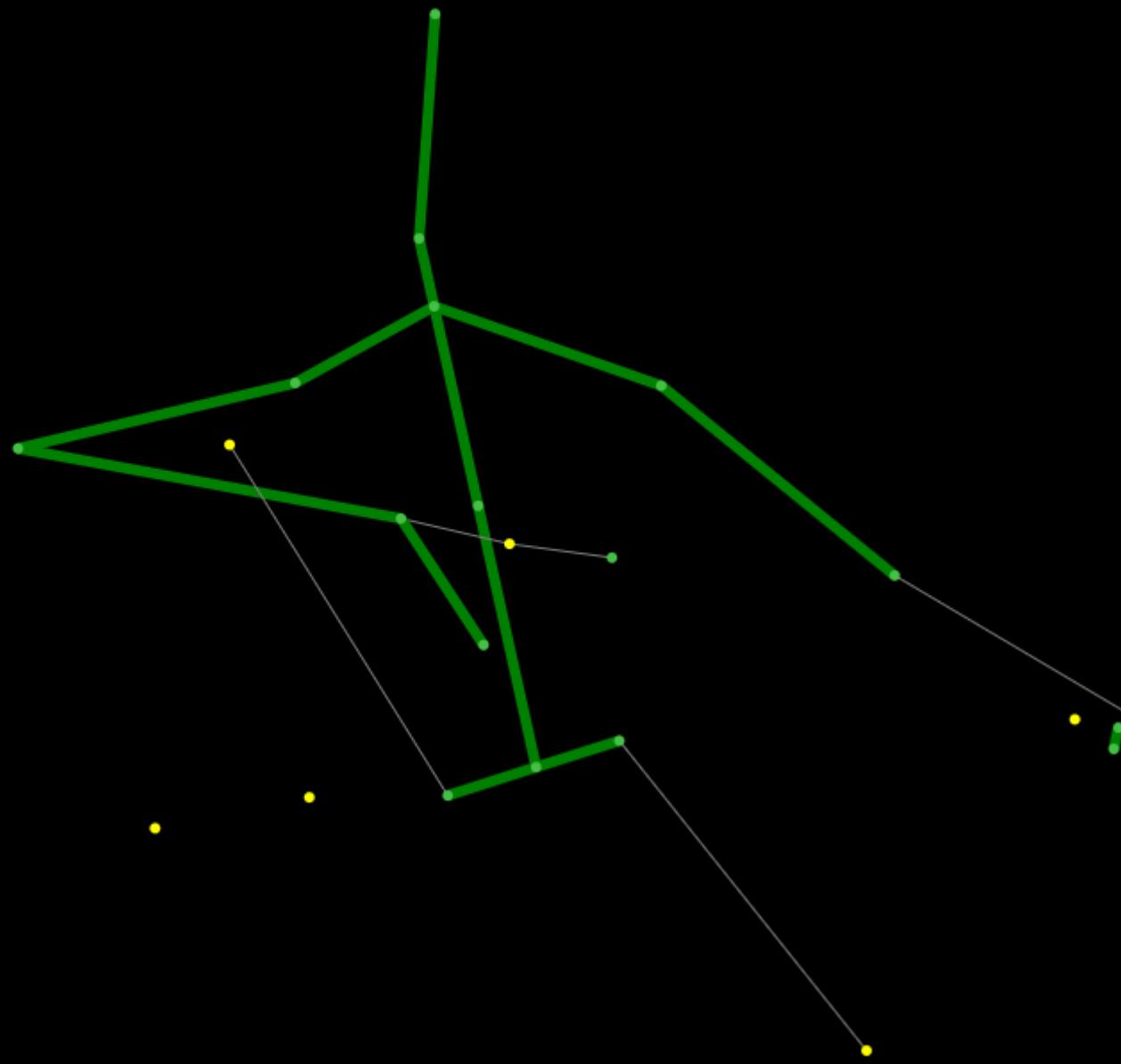
2. Depth Basic



3. Face Tracking Basic



4. Skeletal Basic



FPS = 30.00 Time = 170670768

Questions:

- What advantage do microphone arrays have over traditional microphones / speech input devices?
Arrays provide directionality and depth, while traditional mics and speech input devices do not.

- At what range is the face tracking effective? How might this be used as a robot controller? **Face tracking seems to be limited to between 1 and 15 feet. The further away the face, the harder more complex facial attributes (such as mood) are to detect. This can be used for close-range facial recognition for access. If a robot has a face, you can control its face.**
- What kind of motions and postures does the skeletal model capture? When does it break down? **The skeletal model captures the full body, mapping out major joints and links. It can break down based on variations in angles, based on the angle of the optical sensor, and has trouble with occluded body parts to this end. This also leads to inaccurate representations of joints.**

Kinect sampling from MATLAB

derived from: <https://www.mathworks.com/help/imaq/examples/using-the-kinect-r-for-windows-r-from-image-acquisition-toolbox-tm.html>

required MATLAB Support Package for Kinect: <https://www.mathworks.com/hardware-support/kinect-windows.html>

It might be more straightforward to run this in the Command Window (select, then hit F9)

```
utilpath =
'C:\ProgramData\MATLAB\SupportPackages\R2019b\toolbox\imaq\supportpackages\kinectruntime\kinectforwindowsruntimexamples';
addpath(utilpath);

% The Kinect for Windows Sensor shows up as two separate devices in IMAQHWINFO.
hwInfo = imaqhwinfo('kinect')

hwInfo = struct with fields:
    AdaptorDllName: 'C:\ProgramData\MATLAB\SupportPackages\R2023a\toolbox\imaq\supportpackages\kinectruntime\adap'
    AdaptorDllVersion: '6.7.1 (R2023a)'
        AdaptorName: 'kinect'
        DeviceIDs: {[1] [2]}
        DeviceInfo: [1x2 struct]

hwInfo.DeviceInfo(1)

ans = struct with fields:
    DefaultFormat: 'BGR_1920x1080'
    DeviceFileSupported: 0
        DeviceName: 'Kinect V2 Color Sensor'
        DeviceID: 1
    VideoInputConstructor: 'videoinput('kinect', 1)'
    VideoDeviceConstructor: 'imaq.VideoDevice('kinect', 1)'
        SupportedFormats: {'BGR_1920x1080'}

hwInfo.DeviceInfo(2)

ans = struct with fields:
    DefaultFormat: 'Depth_512x424'
    DeviceFileSupported: 0
        DeviceName: 'Kinect V2 Depth Sensor'
        DeviceID: 2
    VideoInputConstructor: 'videoinput('kinect', 2)'
```

```
VideoDeviceConstructor: 'imaq.VideoDevice('kinect', 2)'
SupportedFormats: {'Depth_512x424'}
```

```
% Create the VIDEOINPUT objects for the two streams
colorVid = videoinput('kinect',1)
```

Summary of Video Input Object Using 'Kinect V2 Color Sensor'.

Acquisition Source(s): Kinect V2 Color Source is available.

Acquisition Parameters: 'Kinect V2 Color Source' is the current selected source.
10 frames per trigger using the selected source.
'BGR_1920x1080' video data to be logged upon START.
Grabbing first of every 1 frame(s).
Log data to 'memory' on trigger.

Trigger Parameters: 1 'immediate' trigger(s) on START.

Status: Waiting for START.
0 frames acquired since starting.
0 frames available for GETDATA.

```
depthVid = videoinput('kinect',2)
```

Summary of Video Input Object Using 'Kinect V2 Depth Sensor'.

Acquisition Source(s): Kinect V2 Depth Source is available.

Acquisition Parameters: 'Kinect V2 Depth Source' is the current selected source.
10 frames per trigger using the selected source.
'Depth_512x424' video data to be logged upon START.
Grabbing first of every 1 frame(s).
Log data to 'memory' on trigger.

Trigger Parameters: 1 'immediate' trigger(s) on START.

Status: Waiting for START.
0 frames acquired since starting.
0 frames available for GETDATA.

```
% Set the triggering mode to 'manual'
triggerconfig([colorVid depthVid], 'manual');
colorVid.FramesPerTrigger = 100;
depthVid.FramesPerTrigger = 100;
```

```
% Start the color and depth device. This begins acquisition, but does not
% start logging of acquired data.
start([colorVid depthVid]);
```

```
% Trigger the devices to start logging of data.
trigger([colorVid depthVid]);
```

```
% Retrieve the acquired data
[colorFrameData,colorTimeData,colorMetaData] = getdata(colorVid);
```

ans =

ToolboxPreferencesManager with properties:

```
GetPrefListener: [1x1 handle.listener]  
SetPrefListener: [1x1 handle.listener]
```

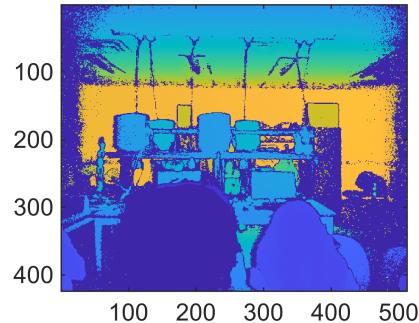
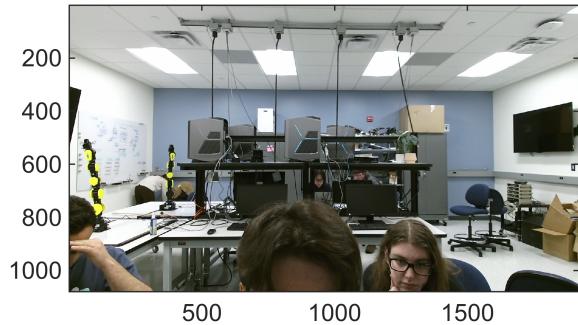
```
[depthFrameData, depthTimeData, depthMetaData] = getdata(depthVid);
```

```
% Stop the devices
```

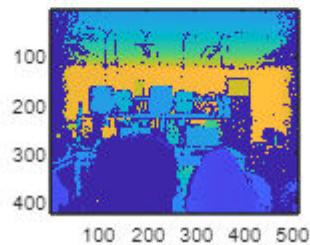
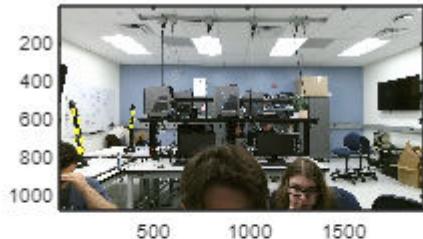
```
stop([colorVid depthVid]);
```

```
% display one of the frames
```

```
figure(1);  
subplot(2, 1, 1);  
imagesc(colorFrameData(:, :, :, 50)); axis equal tight;  
subplot(2, 1, 2);  
imagesc(depthFrameData(:, :, :, 50)); axis equal tight;
```



Copy and the screenshots of your RGB and depth maps:



Skeletal tracking

Grab a frame including a person's body (i.e., "skeleton" in Kinect terms)

```
depthSrc = getselectedsource(depthVid)
```

```
depthSrc =
Display Summary for Video Source Object:
```

```
General Settings:
```

```
Parent = [1x1 videoinput]
Selected = on
SourceName = Kinect V2 Depth Source
Tag = [0x0 string]
Type = videosource
```

```
Device Specific Properties:
```

```
EnableBodyTracking = on
```

```
% Turn on skeletal tracking.
```

```
depthSrc.EnableBodyTracking = 'on';
```

```
% Acquire 100 frames with tracking turned on.
```

```
% Remember to have a person in front of the
```

```
% Kinect for Windows to see valid tracking data.
```

```
colorVid.FramesPerTrigger = 100;
```

```
depthVid.FramesPerTrigger = 100;
```

```
start([colorVid depthVid]);
```

```
trigger([colorVid depthVid]);
```

```
% Retrieve the frames and check if any Skeletons are tracked
```

```
[frameDataColor] = getdata(colorVid);
```

```
[frameDataDepth, timeDataDepth, metaDataDepth] = getdata(depthVid);
```

```
% View skeletal data from depth metadata  
metaDataDepth
```

```
metaDataDepth = 100x1 struct
```

...

Fields	AbsTime	BodyIndexFrame	BodyTrackingID
1	[2025,4,1,19,35,30...]	424x512 double	[7205800000000000,720580000000...
2	[2025,4,1,19,35,30...]	424x512 double	[7205800000000000,720580000000...
3	[2025,4,1,19,35,30...]	424x512 double	[7205800000000000,720580000000...
4	[2025,4,1,19,35,30...]	424x512 double	[7205800000000000,720580000000...
5	[2025,4,1,19,35,30...]	424x512 double	[7205800000000000,720580000000...
6	[2025,4,1,19,35,30...]	424x512 double	[7205800000000000,720580000000...
7	[2025,4,1,19,35,30...]	424x512 double	[7205800000000000,720580000000...
8	[2025,4,1,19,35,30...]	424x512 double	[7205800000000000,720580000000...
9	[2025,4,1,19,35,30...]	424x512 double	[7205800000000000,720580000000...
10	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
11	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
12	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
13	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
14	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
15	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
16	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
17	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
18	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
19	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
20	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
21	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
22	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
23	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
24	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
25	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
26	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
27	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
28	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...
29	[2025,4,1,19,35,31...]	424x512 double	[7205800000000000,720580000000...

Fields	AbsTime	BodyIndexFrame	BodyTrackingID
96	[2025,4,1,19,35,33...]	424×512 double	[7205800000000000,720580000000...
97	[2025,4,1,19,35,33...]	424×512 double	[7205800000000000,720580000000...
98	[2025,4,1,19,35,33...]	424×512 double	[7205800000000000,720580000000...
99	[2025,4,1,19,35,33...]	424×512 double	[7205800000000000,720580000000...
100	[2025,4,1,19,35,34...]	424×512 double	[7205800000000000,720580000000...

```
% Check for tracked skeletons from depth metadata
anyBodiesTracked = any(metaDataDepth(95).IsBodyTracked ~= 0)
```

```
anyBodiesTracked = logical
1
```

```
% See which skeletons were tracked.
trackedBodies = find(metaDataDepth(95).IsBodyTracked)
```

```
trackedBodies = 1×3
1     2     3
```

```
jointCoordinates = metaDataDepth(95).JointPositions(:, :, trackedBodies)
```

```
jointCoordinates =
jointCoordinates(:, :, 1) =
```

```
0.0185   -0.5616   2.1072
0.0166   -0.2543   2.1349
0.0155    0.0455   2.1476
0.0194    0.1722   2.1557
-0.1466   -0.0499   2.1186
-0.1961   -0.2489   2.0356
-0.1483   -0.0969   1.8941
-0.1491   -0.0798   1.8880
0.1383   -0.0404   2.1069
0.2046   -0.2376   2.0219
0.1843   -0.0671   1.8969
0.1809   -0.0730   1.9006
-0.0496   -0.5533   2.0762
-0.0964   -0.9136   2.0587
-0.1010   -1.1802   2.1010
-0.0747   -1.2363   2.0194
0.0862   -0.5509   2.0679
0.1425   -0.9306   2.0598
0.1652   -1.1942   2.1008
0.0919   -1.1536   2.0149
0.0157   -0.0285   2.1469
-0.1365   -0.0379   1.8757
-0.1300   -0.0281   1.8860
0.1735   -0.0221   1.8848
0.1883   -0.0227   1.9017
```

```
jointCoordinates(:, :, 2) =
```

```

0.7351 -0.6069 1.9229
0.7615 -0.3108 1.9407
0.7819 -0.0214 1.9451
0.7619 0.1240 1.9347
0.5914 -0.1229 2.0198
0.4730 -0.3320 1.8846
0.3774 -0.4573 1.7555
0.3634 -0.5095 1.6673
0.9165 -0.1087 1.8375
0.9506 -0.2737 1.7186
0.8740 -0.4208 1.5499
0.8138 -0.4877 1.4687
0.6500 -0.6025 1.9304
0.6655 -0.9726 1.9534
0.6891 -1.3376 2.0012
0.6276 -1.3606 1.8804
0.7962 -0.5915 1.8527
0.8289 -0.9050 1.8307
0.8877 -1.3300 1.8381
0.8232 -1.3526 1.7188
0.7778 -0.0929 1.9462
0.3467 -0.5548 1.6098
0.3742 -0.4436 1.6199
0.7710 -0.5496 1.4145
0.8021 -0.5637 1.5224

```

```
jointCoordinates(:,:,3) =
```

```

-0.8195 -0.5064 1.9914
-0.8423 -0.2280 2.0238
-0.8590 0.0445 2.0420
-0.8728 0.1970 2.0615
-1.0165 -0.0688 1.9552
-1.0688 -0.2784 1.8945
-1.1795 -0.2259 1.7167
-1.1576 -0.1738 1.6790
-0.6689 -0.0692 2.0655
-0.6228 -0.3522 2.0484
-0.4461 -0.2195 1.9164
-0.3824 -0.1577 1.8828
-0.8849 -0.4978 1.9325
-1.1038 -0.6219 1.8626
-0.7543 -0.6205 1.8013
-0.7082 -0.6516 1.6599
-0.7259 -0.4975 1.9825
-0.6790 -0.7576 1.9752
-0.5892 -1.0600 2.1009
-0.6071 -0.9184 2.0140
-0.8558 -0.0226 2.0400
-1.1528 -0.1375 1.6211
-1.1507 -0.1668 1.7087
-0.3277 -0.0987 1.8602
-0.3414 -0.1505 1.9269

```

```
% Skeleton's joint indices with respect to the color image
jointIndices = metaDataDepth(95).ColorJointIndices(:, :, trackedBodies)
```

```

jointIndices =
jointIndices(:,:,1) =
1.0e+03 *

```

0.9950	0.8372
0.9928	0.6767
0.9912	0.5242
0.9927	0.4604
0.9087	0.5732
0.8808	0.6806
0.9020	0.6033
0.9013	0.5936
1.0556	0.5677
1.0961	0.6745
1.0930	0.5852
1.0908	0.5885
0.9599	0.8373
0.9360	1.0315
0.9347	1.1617
0.9481	1.2177
1.0314	0.8370
1.0626	1.0401
1.0730	1.1689
1.0381	1.1735
0.9915	0.5616
0.9082	0.5696
0.9122	0.5638
1.0875	0.5595
1.0948	0.5597

jointIndices(:,:,2) =

1.0e+03 *	
1.4064	0.8900
1.4162	0.7199
1.4258	0.5572
1.4165	0.4754
1.3052	0.6120
1.2621	0.7378
1.2254	0.8300
1.2306	0.8793
1.5344	0.6093
1.5972	0.7185
1.6135	0.8414
1.6050	0.9080
1.3562	0.8862
1.3615	1.0907
1.3660	1.2805
1.3566	1.3424
1.4597	0.8940
1.4868	1.0870
1.5218	1.3430
1.5201	1.4146
1.4234	0.5972
1.2293	0.9221
1.2457	0.8445
1.5969	0.9702
1.5739	0.9501

jointIndices(:,:,3) =

1.0e+03 *	
0.5391	0.8260
0.5328	0.6719

```
0.5269  0.5260
0.5232  0.4459
0.4203  0.5884
0.3735  0.7102
0.2420  0.6943
0.2400  0.6638
0.6324  0.5855
0.6549  0.7357
0.7340  0.6729
0.7667  0.6393
0.4894  0.8299
0.3437  0.9142
0.5345  0.9245
0.5287  0.9772
0.5886  0.8221
0.6136  0.9668
0.6813  1.0995
0.6594  1.0461
0.5284  0.5617
0.2173  0.6436
0.2569  0.6573
0.7961  0.6058
0.7941  0.6330
```

```
% Pull out the 95th color frame
image = frameDataColor(:, :, :, 95);

% Find number of Skeletons tracked
nBodies = length(trackedBodies);
```



Now plot the skeleton over the RGB image

```
% Create skeleton connection map to link the joints.
SkeletonConnectionMap = [ [4 3]; % Neck
                           [3 21]; % Head
                           [21 2]; % Right Leg
                           [2 1];
```

```

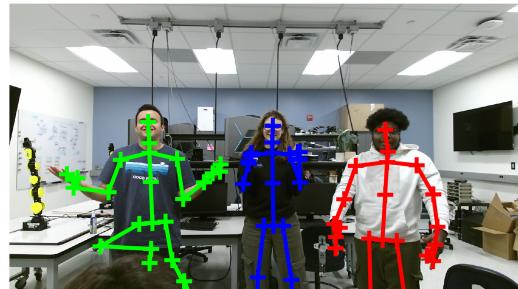
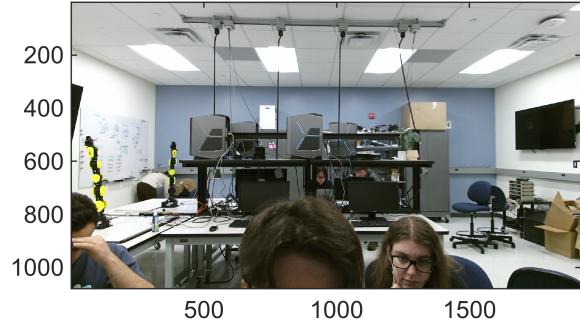
[21 9];
[9 10]; % Hip
[10 11];
[11 12]; % Left Leg
[12 24];
[12 25];
[21 5]; % Spine
[5 6];
[6 7]; % Left Hand
[7 8];
[8 22];
[8 23];
[1 17];
[17 18];
[18 19]; % Right Hand
[19 20];
[1 13];
[13 14];
[14 15];
[15 16];
];

% Marker colors for up to 6 bodies.
colors = ['b';'r';'g';'c';'y';'m'];

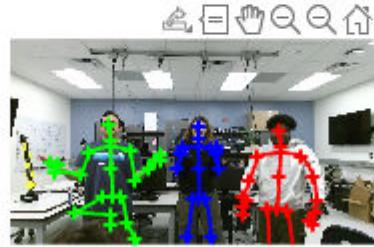
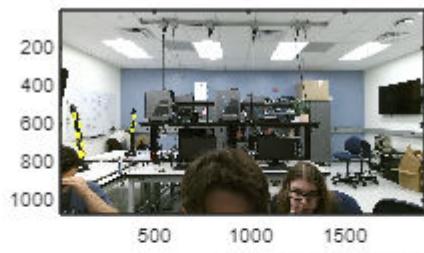
% Display the RGB image.
imshow(image);

% Overlay the skeleton on this RGB frame.
for i = 1:24
    for body = 1:nBodies
        X1 = [jointIndices(SkeletonConnectionMap(i,1),1,body)
jointIndices(SkeletonConnectionMap(i,2),1,body)];
        Y1 = [jointIndices(SkeletonConnectionMap(i,1),2,body)
jointIndices(SkeletonConnectionMap(i,2),2,body)];
        line(X1,Y1, 'LineWidth', 1.5, 'LineStyle', '-',
'Marker', '+', 'Color',
colors(body));
    end
    hold on;
end
hold off;

```



Copy and paste a screenshot overlaid with the extracted skeleton:



Tasks/Questions:

- Did the skeleton model accurately capture your body geometry? **Yes, the joints on each person are clearly noted in the image**
- How would you estimate the elbow angle from the skeletal model? **Use the angles between the upper and lower arms to calculate this.**

Submitting This Lab

Export this *.mlx file as Lab7_##_<LastName1>_<LastName2>_<LastName3>_<LastName4>.pdf (## should be your computer number) and email to Lauren.Diaz@jhuapl.edu