

## Author

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## github link

<https://github.com/KimInyeop-cpu/Robot-Automation/tree/main>

# 1. Background

## 1-1. Introduction

With the rapid growth of the electric vehicle (EV) market, the secondary battery industry has emerged as a key strategic sector. It is projected that by 2030, electric vehicles will account for more than 40% of the global automotive market, leading to a significant increase in battery production demand. However, conventional battery cell assembly and disassembly processes remain highly dependent on manual labor, resulting in limitations in productivity, process consistency, and quality control. In particular, as the importance of battery recycling and safe disassembly increases, there is a growing demand for intelligent automation systems capable of handling precise and complex operations beyond simple assembly tasks.

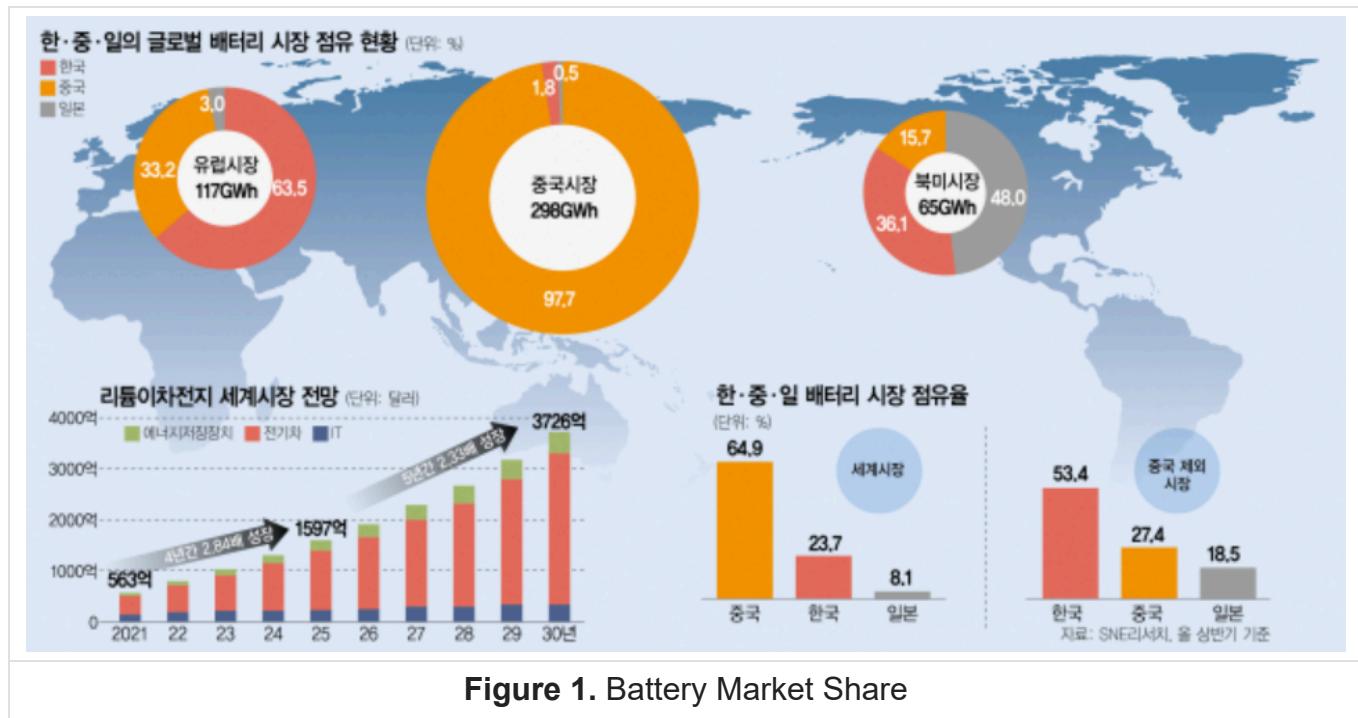


Figure 1. Battery Market Share

This project aims to address these challenges by developing an **automated battery cell winding process using industrial robots integrated with machine vision and artificial intelligence technologies**. By combining robotic manipulation, sensor-based detection nodes,

state diagram-based control logic, and camera-based recognition of battery cells and winding components, the project seeks to transform a labor-intensive process into a high-speed, high-precision automated system. Through this approach, the feasibility of improving productivity, reliability, and safety in battery manufacturing and recycling processes is investigated.

## 1-2. Problem Statement

### 1-2.1. Project Objectives

The main objectives of this project are as follows:

- 1. Implementation of Automated Assembly and Disassembly of Battery Cell Winding Processes**

To automate the assembly and disassembly of battery cells and winding components using industrial robots, thereby minimizing human error and improving repeatability.

- 2. Development of a Machine Vision-Based Recognition System**

To detect battery cell positions, orientations, and conditions (normal or defective) using camera-based vision systems and AI models, and to integrate the recognition results into the robot control system.

- 3. Design of Robot Control Logic and State Diagrams**

To design structured state diagrams that manage process flow and ensure stable coordination between sensor detection nodes and robotic actions.

- 4. Verification of Process Reliability and Performance**

To experimentally evaluate the success rate, accuracy, and operational stability of the automated system and assess its applicability to real industrial environments.

### 1-2.2. Expected Outcomes

The expected outcomes of this project are as follows:

- 1. Improved Productivity and Operational Efficiency**

By replacing manual labor with robotic automation, continuous operation beyond traditional working hours becomes possible, significantly increasing overall productivity.

- 2. Enhanced Accuracy and Quality Consistency**

The automated system is expected to achieve a high success rate in assembly and disassembly tasks, while the machine vision system enables reliable identification of normal and abnormal battery cells, excluding specific inclusion cases.

- 3. Reduced Labor Dependency and Improved Workplace Safety**

Automating repetitive and potentially hazardous battery handling processes reduces worker exposure to risk and lowers dependence on skilled manual labor.

- 4. Scalability for Battery Recycling and Future Smart Factory Applications**

The proposed system can be extended to battery disassembly and recycling processes,

providing a technological foundation for advanced smart factory and sustainable battery production systems.

## 1-3. Evaluation Index

Process	Target
<b>UR5 Robot Operation</b>	<ul style="list-style-type: none"><li>- Bracket detection success rate <math>\geq 98\%</math></li><li>- Cell box detection success rate = 100%</li><li>- Pick and Place success rate <math>\geq 95\%</math></li><li>- Stopper linkage success rate = 100%</li><li>- Assembly/Disassembly process completion time <math>\leq 1</math> minute</li></ul>
<b>Indy10 Robot Operation</b>	<ul style="list-style-type: none"><li>- Cell orientation detection success rate = 100%</li><li>- Foreign object detection success rate <math>\geq 95\%</math></li><li>- Defective cell detection success rate <math>\geq 95\%</math></li><li>- Stopper linkage success rate = 100%</li><li>- Winding assembly/disassembly process completion time <math>\leq 1</math> minute</li></ul>
<b>Defect Detection</b>	<ul style="list-style-type: none"><li>- Defect detection success rate (cylindrical surface) <math>\geq 95\%</math></li><li>- Defect detection success rate (flat surface) <math>\geq 80\%</math></li></ul>

## 2. Requirement

### Software (In Process Awareness-Based Pick and Place Automation Part, ur5e)

- OS: Linux Ubuntu 20.04
- ROS: ROS Noetic
- Additional Packages Required
  - OpenCV
  - rospy
  - numpy
  - moveit\_ros\_planning
- Additional Ubuntu Utility Programs
  - VS code
  - terminator

To build overall software setting, follow the [link](#) for extra guideline.

### Hardware

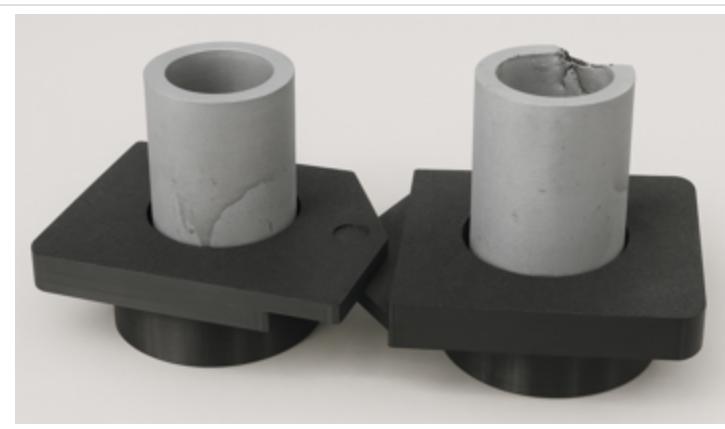
- Cell & Wind (Cell Radius: 57mm, Bracket Radius: 36mm)



**Figure 2A.** Cell

**Figure 2B.** Wind

- Bracket(Radius: 60mm)



**Figure 3.** Bracket

- Cell Box(Width & Length: 60mm)

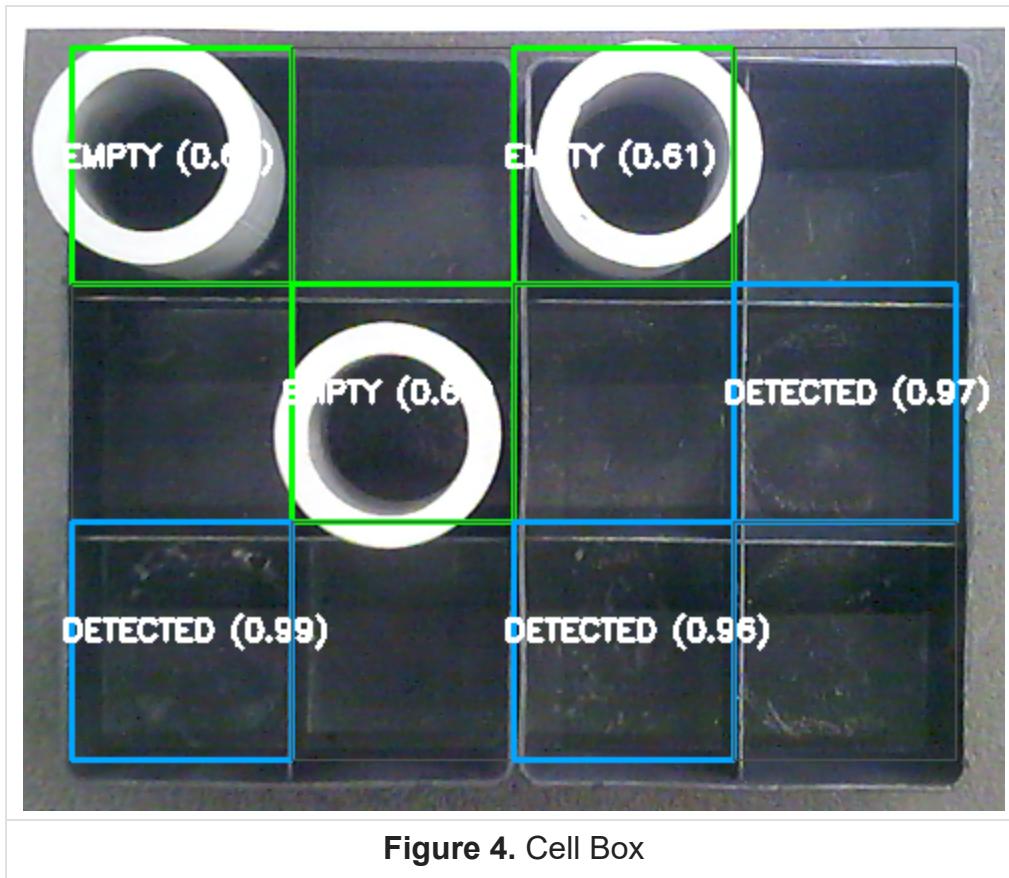


Figure 4. Cell Box

### 3. Tasks

#### 3-1. Assembly/Disassembly Process Recognition

- Recognizes whether a bracket contains a cell.
- Recognizes cells/composites in the cell box.
- Calculates coordinates for picking from the cell box and placing on the bracket.
- If a cell is missing from the cell box, the disassembly process switches. If a composite is missing, the assembly process switches.

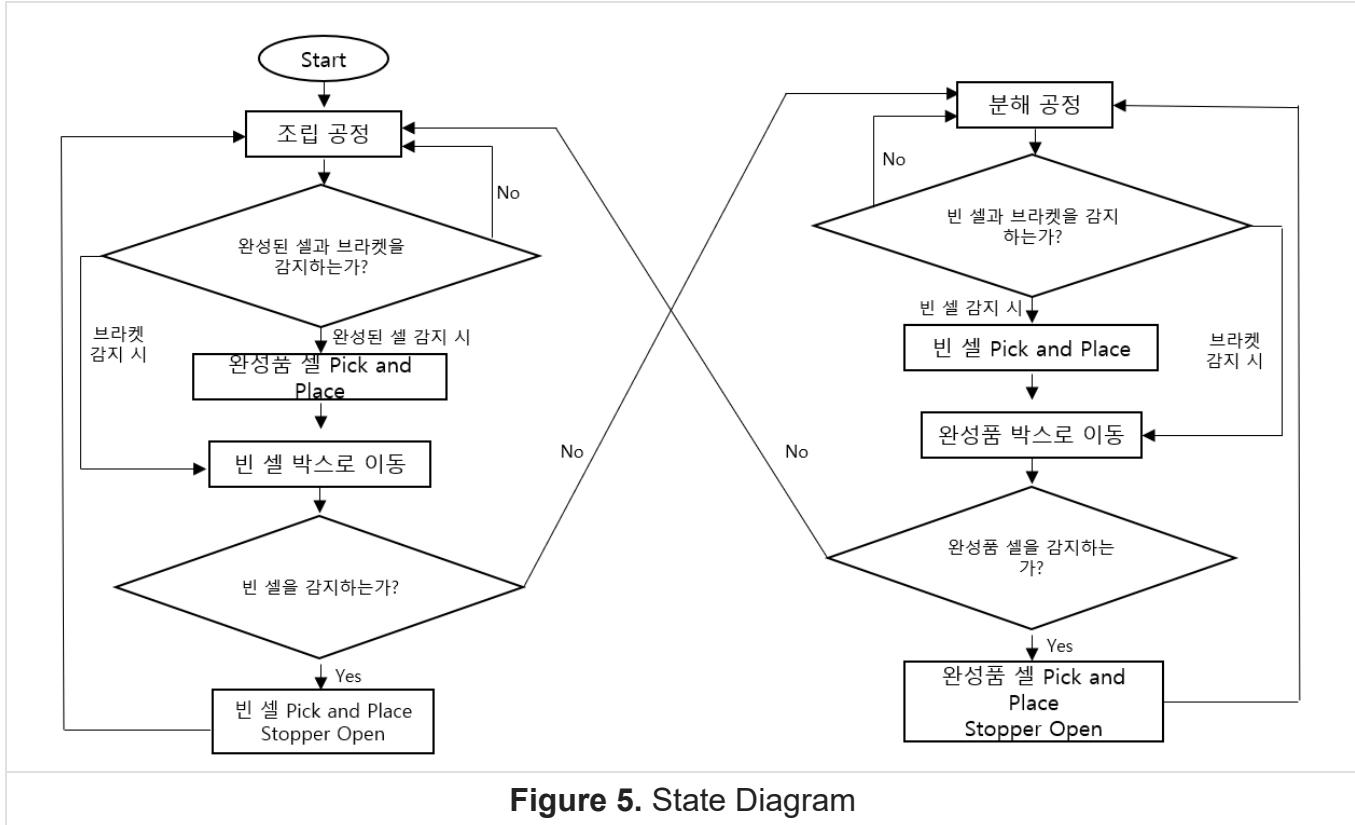
#### 3-2. Pick and Place Process Description

1. The ur5e robot approaches the bracket and checks for the presence of a cell.
2. If a cell is present, it places the cell in the appropriate cell box. If not, it picks the appropriate cell from the cell box.
3. During pick and place, the ur5e robot processes the image and calculates relative coordinates (pixel to millimeter) based on the camera, allowing the gripper to reach the correct location.
4. The robot automatically determines and switches between the assembly and disassembly processes based on the presence of a cell in the cell box.

# 4. Algorithm

## 4-1. Logic Design

Based on the tasks listed above, the system's flowchart is drawn as below:



### 4-1.1. Assembly Process

- **State 1:** First Bracket Detection (State 2 if Composite is detected, State 5 if Bracket is detected)
- **State 2:** Place Composite in Cell Box, then State 3
- **State 3:** Second Bracket Detection (State 4 if Composite is detected, State 6 if Bracket is detected)
- **State 4:** Place Composite in Cell Box, then State 5
- **State 5:** Pick a cell from the cell box, place it on the bracket, then State 6 (if no cell is in the cell box, then State 101 (Disassembly Process))
- **State 6:** Pick a cell from the cell box, place it on the bracket, then reset to State 1 (if no cell is in the cell box, then State 201 (Disassembly Preparation Process))

### 4-1.2. Disassembly Process

- **State 101:** First Bracket Recognition (State 102 for cell detection, State 105 for bracket detection)
- **State 102:** Place the cell in the cell box, then State 103
- **State 103:** Second bracket recognition (State 4 for cell detection, State 106 for bracket detection)
- **State 104:** Place the cell in the cell box, then State 5
- **State 105:** Pick the composite from the cell box, then place it on the bracket, then State 106 (if there is no composite in the cell box, then State 1 (assembly process))
- **State 106:** Pick the composite from the cell box, then place it on the bracket, then reset to State 101 (if there is no composite in the cell box, then State 301 (assembly preparation process))

#### 4-1.3. Disassembly Preparation Process

- **State 201:** First bracket recognition (if there is a composite, place it in the cell box, then State 101 (disassembly process) and State 202 for bracket detection)
- **State 202:** Detect a composite in the second bracket, place it in the cell box, and switch to State 101 (disassembly process).

#### 4-1.4. Assembly Preparation Process

- **State 301:** First bracket recognition (if a cell is detected, place it in the cell box, then switch to State 1 (assembly process). If a bracket is detected, switch to State 302.)
- **State 302:** Detect a cell in the second bracket, place it in the cell box, and switch to State 1 (assembly process).

### 4-2. Image Processing

The following image processing was used to identify the battery cell and assembly/disassembly process status.

#### 1. yellow\_bracket\_detection\_node.py

- This sensor node detects the bracket holes in the yellow bracket.  
**Bracket (yellow circle) detection**

```
mask = cv2.inRange(hsv, [20,120,120], [32,255,255])
circles = cv2.HoughCircles(mask, cv2.HOUGH_GRADIENT,
                           dp=1.2, minDist=190,
                           minRadius=210, maxRadius=430)
x, y, r = max(circles, key=lambda c: c[2])
```

- HSV-based yellow segmentation followed by Hough Circle circular bracket detection.
- Since the brackets are of constant size, false detections can be eliminated within the radius range.

### EMA Filter

```
x = (1-a)*x_prev + a*x  
y = (1-a)*y_prev + a*y
```

- Removing frame-to-frame positional blur with EMA filters

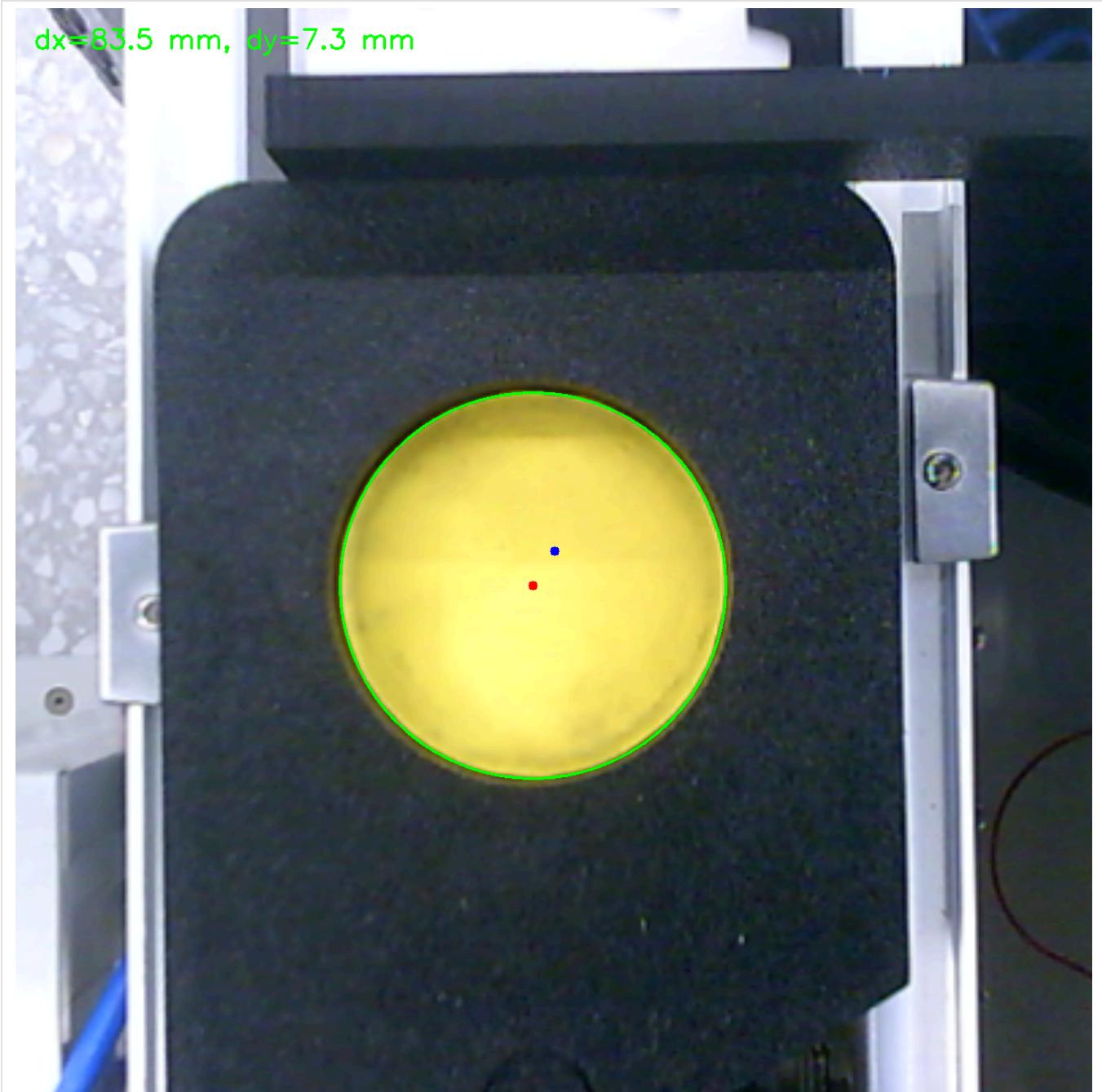


Figure 6. Bracket Detection

## 2. filled\_cellbox\_detection\_node.py

- This detection node detects cells in an empty cell box.

### Cell box brightness detection technique (classical image processing)

```
bright_mask = np.all(cell_roi >= 215, axis=2)
ratio = np.sum(bright_mask) / cell_area
```

- This detection technique is a classical computer vision method that uses RGB color space-based threshold brightness detection.
- Pixels within each cell region whose R, G, and B channel values all exceed a threshold are defined as bright pixels. If the area ratio of these pixels exceeds a threshold, the cell is determined to be detected.

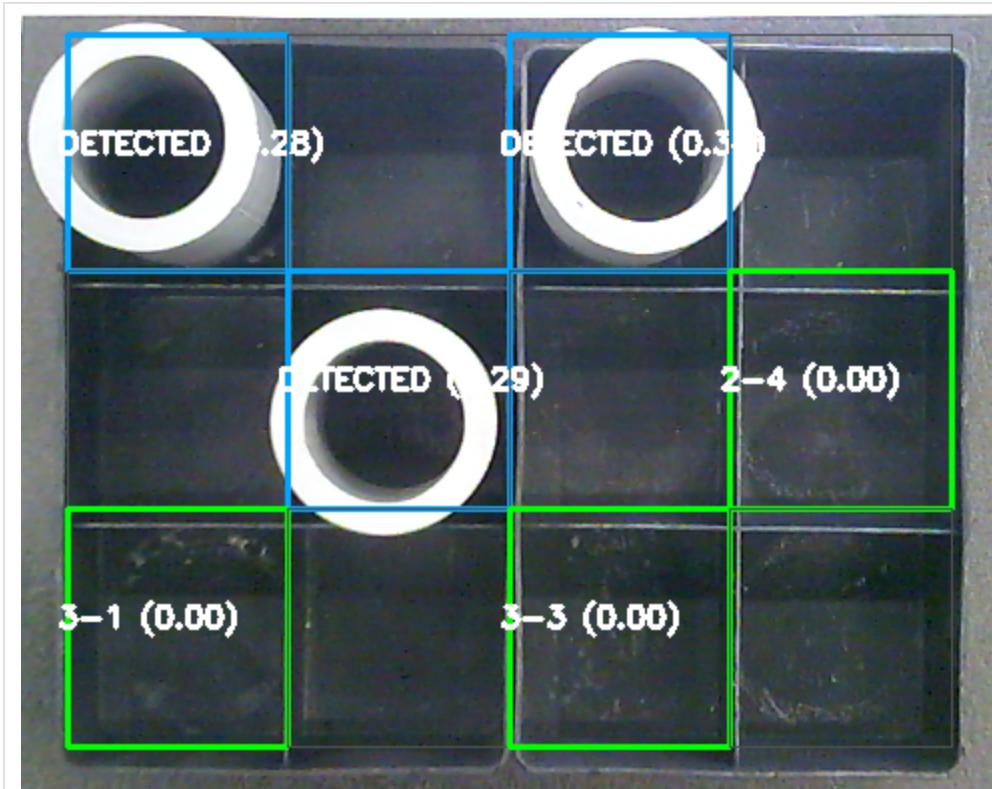


Figure 7. Cell Detection in Cellbox

## 3. empty\_composite\_cellbox\_detection\_node.py

- This detection node detects empty boxes in the composite cell boxes.

### Cell detection technique (classical image processing)

```
mean_intensity = np.mean(cell_region)
if mean_intensity < 90:
```

```
detected = True
```

- This technique is a classical computer vision method that uses grayscale average intensity-based threshold detection.
- If the mean intensity of each grid cell area falls below a threshold, the cell is considered dark and is then detected as a location for a composite cell.

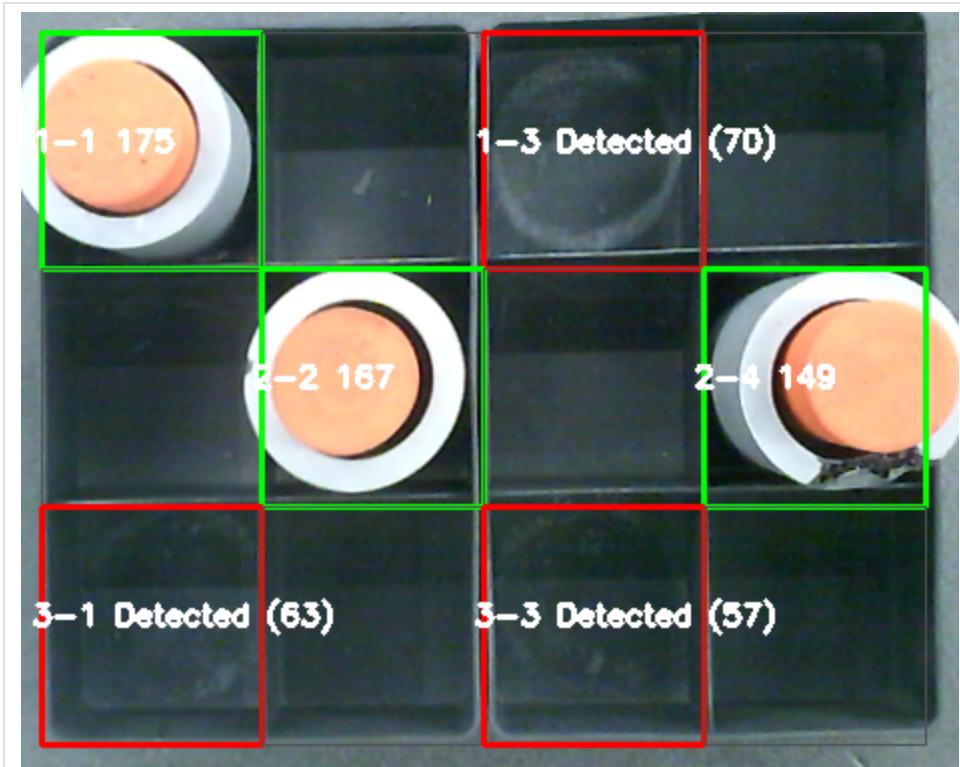


Figure 8. Empty Composite Cell in Cellbox

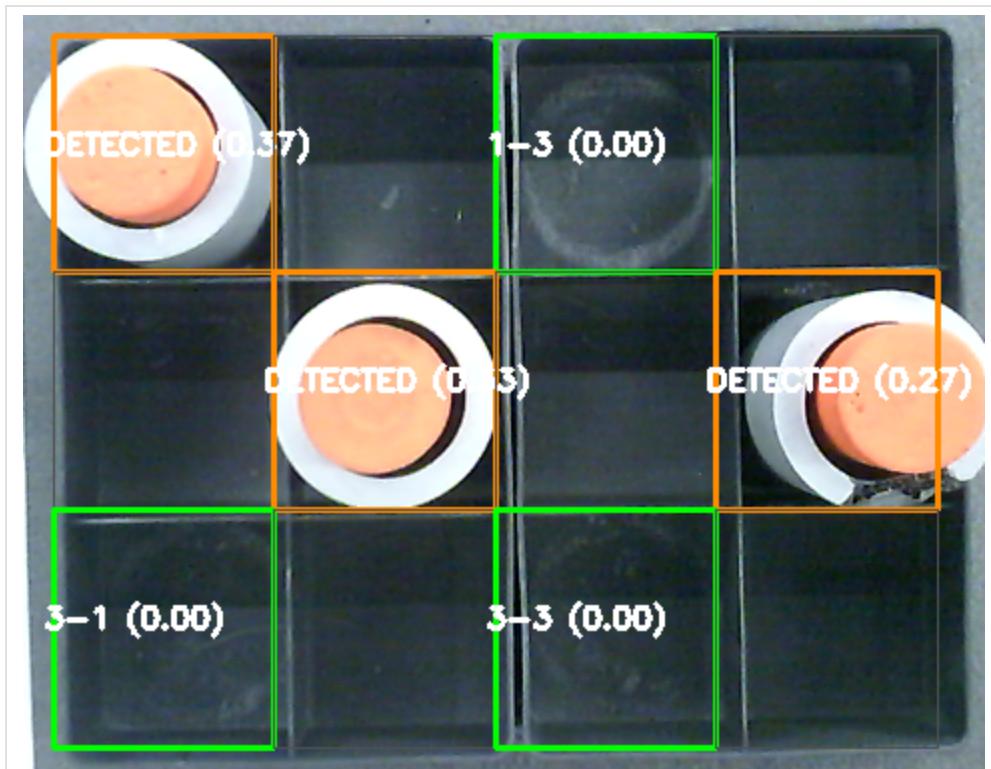
#### 4. filled\_composite\_cellbox\_detection\_node.py

- This detection node detects composite cells in the finished cell box.

##### Composite cell detection core logic

```
orange_mask = cv2.inRange(cell_roi,
                           (65, 110, 220), (185, 220, 255))
ratio = np.sum(orange_mask > 0) / cell_area
```

- This node is a classical computer vision technique that uses threshold color detection based on the RGB (BGR) color space.
- If the percentage of pixels within each cell that fall within the orange range exceeds a certain threshold ( $\geq 5\%$ ), then the cell is considered detected.



**Figure 9.** Filled Composite Cell in Cellbox

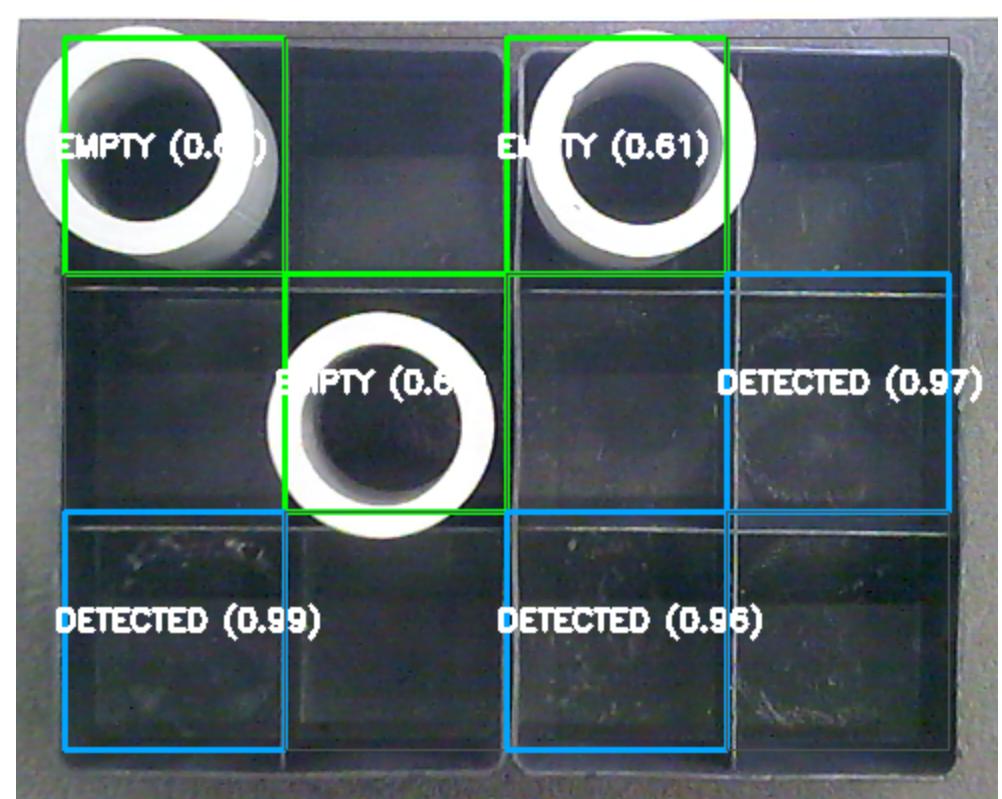
\*\*5. empty\_cell\_cellbox\_detection\_node.py

- This detection node detects empty spaces in empty cell boxes.

#### **Empty space detection core logic**

```
black_mask = cv2.inRange(hsv_roi, lower_black, upper_black)
```

- It is a threshold-based classical image processing technique that determines the presence of a black object based on the ratio of pixels with low brightness (V) in the HSV color space.



**Figure 10.** Empty Cell in Cellbox

## 6. winding\_decect\_node.py

- This sensor node detects the wind.

### Wind detection core logic

```
circles = cv2.HoughCircles(gray_blurred, cv2.HOUGH_GRADIENT, ...)  
orange_ratio = orange_pixels_inside_circle / circle_area
```

- It is a classical image processing technique that detects circular objects using grayscale-based Hough Circle Transform and determines them as valid objects only when the proportion of orange pixels inside the detected circle exceeds a threshold.

## 7. composite\_detection.py

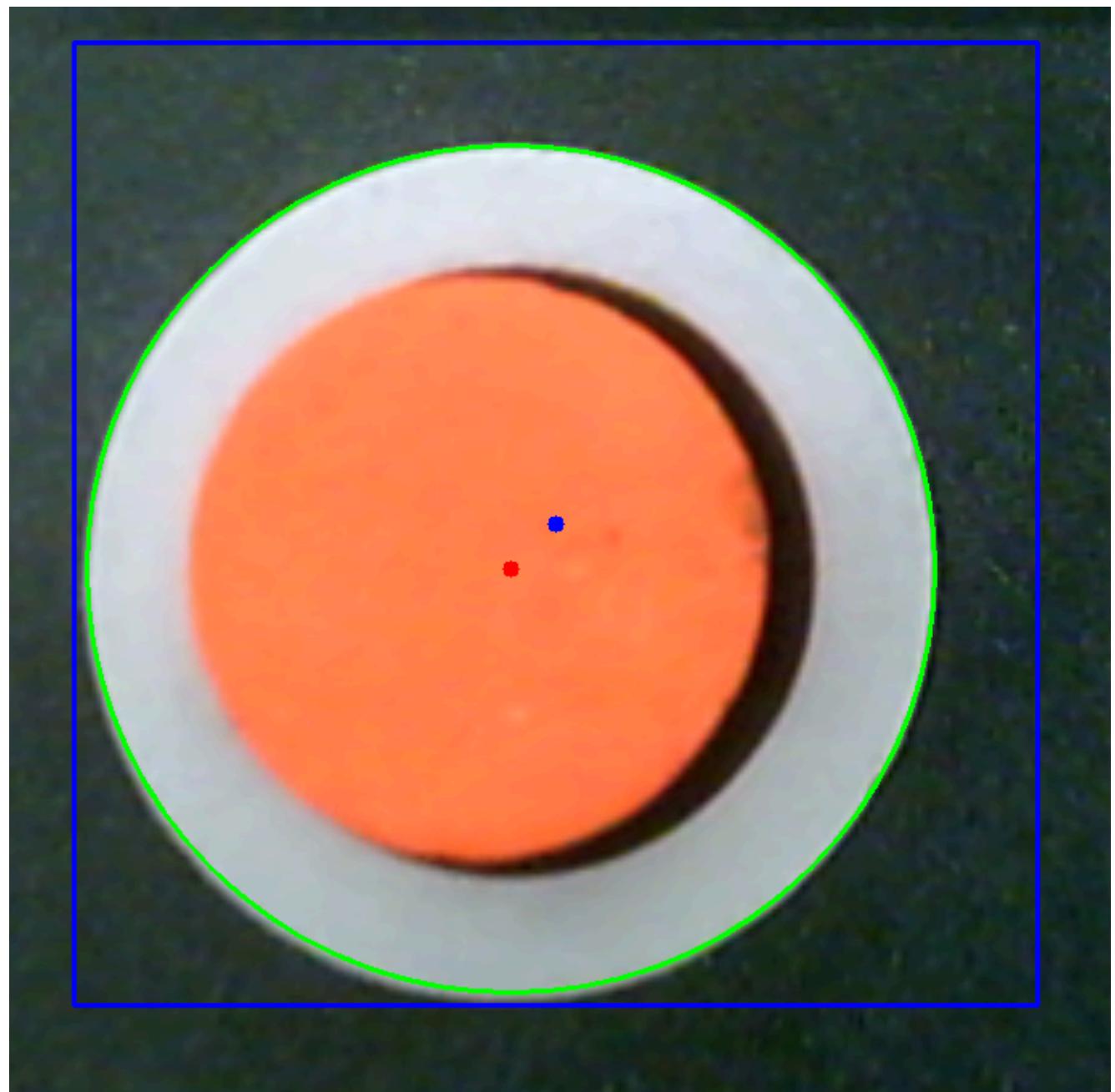
- This detection node detects the composite cell.

### Composite cell detection core logic

```
circles = cv2.HoughCircles(gray_blurred, cv2.HOUGH_GRADIENT, ...)
```

- It is a classical image processing technique that detects circular objects by applying Hough Circle Transform to a grayscale threshold image within the central ROI, and determines

them as valid locations only when the center distance condition is satisfied.



**Figure 11.** Composite Detection

## \*\*8. cell\_detection.py

- This detection node detects empty cells.

### **Empty cell detection core logic**

```
circles = cv2.HoughCircles(gray_blurred, cv2.HOUGH_GRADIENT, ...)
```

- It is a rule-based classical image processing technique that detects circular objects by applying Hough Circle Transform to grayscale threshold images, and judges them as pure

gray objects only when the orange/yellow ratio inside the circle is below the threshold.

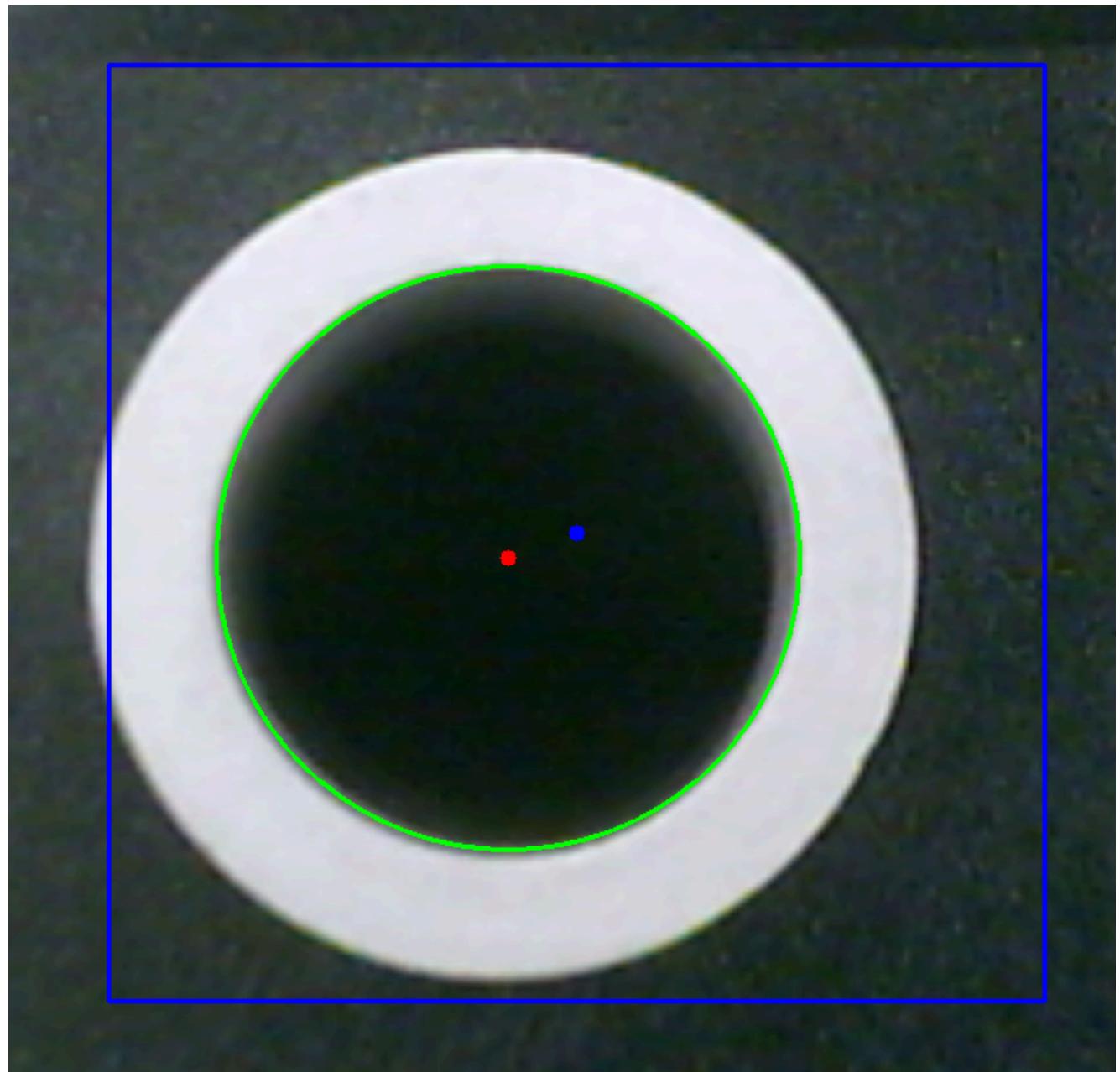


Figure 12. Cell Detection

## 4-3. Pick and Place Algorithm(Manipulation)

### 1. Joint-based locomotion (MoveJ)

```
def goJ(self, arr_deg, label=""):
    ok = self.ur5e.go_to_joint_abs(self.jdeg(arr_deg))
    rospy.sleep(1.5)
    return ok
```

- Meaning: Move the UR5e relative to absolute joint coordinates using a predefined array of joint angles.
- Usage: Stable pose transitions, such as observation poses, grid access, and return poses.

## 2. Cartesian movement based on relative coordinates (XY/Z separation)

```
self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
self.ur5e.go_to_pose_rel([0.0, 0.0, -0.07], [0, 0, 0])
```

- Meaning: Relative movement relative to the current TCP
- Features: After moving in the XY plane, only the Z axis is lowered/raised → Minimizes collisions
- Usage: Vision-based fine-position correction pick-and-place

## 3. Pick Basic Sequence

```
# XY 이동
self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
# Z 하강
self.ur5e.go_to_pose_rel([0.0, 0.0, -0.07], [0, 0, 0])
# 그립 ON
self.grip_on_6s()
# Z 상승
self.ur5e.go_to_pose_rel([0.0, 0.0, 0.115], [0, 0, 0])
```

- Meaning: Typical industrial robot pick sequence
- Feature: Reuse of the same structure for all pick operations

## 4. Grid-based Pick Cycle (Reusable Blocks)

```
def pick_cycle(self, pose_dict, cell_key, grip_mode="off"):
    self.goJ(p["start"])
    self.goJ(p["pick"])
    if grip_mode == "on": self.grip_on_6s()
    else: self.grip_off_6s()
    self.goJ(p["start"])
```

- Meaning: Cell name (e.g., "2-3") → Automatically execute the corresponding joint pose.
- Usage:
  - Move to the grid containing the cell.
  - Later, calculate the relative coordinates and execute Pick or Place.

## 5. State-based robot motion transition (FSM)

```
if self.state == 1: self.state_1()
elif self.state == 5: self.state_5()
elif self.state == 101: self.state_101()
```

- Meaning: Manage robot motion scenarios as states based on detection results.
- Features:
  - Assembly Process
  - Disassembly Process

This system consists of an industrial robot control logic that combines joint-based movement and Cartesian relative movement and performs pick-and-place operations through an FSM structure.

## 5. Results(Process Awareness-Based Pick and Place Automation Part, UR5e)

### 5-1 Results

The test was performed a total of 100 times, and the process time was measured from the moment the stopper contacted the bracket until the stopper opened after the process was completed. The results are as follows.

Process	Goal	Result
Detection	- Bracket detection success rate ≥98% - Cell box detection success rate =100%	- Bracket Detection Success Rate = 100% - Cell Box Detection Success Rate = 100%
Pick and Place	- Pick and Place Success Rate ≥95%	- Pick and Place Success Rate = 97%
Stopper linkage and process completion time	- Stopper Interlock Success Rate = 100% - Assembly/Disassembly Process Completion Time: Within 1 Minute	- Stopper Interlock Success Rate = 100% - Assembly/Disassembly Process Completion Time: 1 minute 35 seconds

### 5-2 Discussion

1. While the pick-and-place operation met the target performance indicator of a success rate of over 95%, the battery cell assembly and disassembly process requires precise analysis,

as even a single failure can impact the overall process quality. The reason is that the `go_to_joint_rel()` function used in relative coordinate-based control sets the positioning error tolerance to 0.003, allowing for a maximum error of approximately 3 mm. However, indiscriminately reducing this tolerance value improves positioning accuracy, but there is a trade-off: increased path calculation time and overall process delays. Therefore, more detailed adjustments to the tolerance value are necessary to simultaneously satisfy the required process accuracy and computational efficiency.

2. The target process time of less than one minute was not met, requiring further analysis in this area. The Cartesian technique, which directly specifies the spatial coordinates (X, Y, Z) of the robot and moves it, has no risk of sign inversion of the posture (yaw, pitch, roll) and can secure high precision because the path is calculated by dividing it into intervals of about 2 mm. However, it has the limitation of relatively slow process speed. On the other hand, the Euler technique, which directly controls the posture (yaw, pitch, roll) of the end-effector, has fast movement speed, but a serious problem has been observed in which the sign inversion of the posture occurs in certain situations and the robot posture suddenly becomes distorted, which acts as a clear trade-off. In addition, a delay of about 1.5 seconds occurred in the process of calling the detection node in a callback manner, which is believed to be caused by the ROS communication structure itself rather than the delay caused by `rospy.sleep()`.
3. Since the image processing was performed based on the lighting standard of NTH 115, detection and pick and place may become more inaccurate when exposed to other lighting environments.
4. If neither the Cell nor the Composite box contains a single cell, the ur5e robot will continue to switch between process states. Therefore, at least one cell must be present in each box.
5. The Cell box must have a Cell in its proper location, and the Composite box must have a Composite Cell in its proper location. Otherwise, the cell will not be recognized.

## 6. Conclusion

By introducing a process-aware pick and place automation system, operating hours can be significantly extended compared to existing human-driven processes, enabling continuous 24-hour operation. While the cycle time was somewhat long at 1 minute and 35 seconds, and only two cells were picked and placed per cycle, this project demonstrated the feasibility of fully unmanned pick and place, suggesting potential savings in labor and operating costs. Future research will focus on shortening the overall process execution time and enhancing the precision of image processing detection to ensure a near-zero pick and place failure rate.

## 7. Reference

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2. Attia, P. M., Moch, E., & Herring, P. K. (2025). Challenges and opportunities for high-quality battery production at scale. *Nature Communications*, 16, 611.  
<https://doi.org/10.1038/s41467-025-55861-7>
3. Jiang, X., Gramopadhye, A.K., Melloy, B.J. and Grimes, L.W. (2003), Evaluation of best system performance: Human, automated, and hybrid inspection systems. *Hum. Factors Man.*, 13: 137-152. <https://doi.org/10.1002/hfm.10031>
4. Jo, H., Park, H., Baek, S., & Kang, E. K. (2017). Low back pain in farmers: The association with agricultural work management, disability, and quality of life in Korean farmers. *Human Factors and Ergonomics in Manufacturing & Service Industries*, 27(3), 156–165.  
<https://doi.org/10.1002/hfm.20699>

## 8. Code

### 8-1. Structure

```

catkin_ws
|- build
|- devel
|- packages_from_git
|- src
|----|- CMakeLists.txt
|----|- 22000167_Kiminyeop_ur_python
|----|---|- msg
|----|---|---| grip_command.msg
|----|---|---| grip_state.msg
|----|---|---| object_info.msg
|----|---|---| pet_info.msg
|----|---|---| robot_state.msg
|----|---|- src
|----|---|---| camera.py
|----|---|---| cell_detection.py
|----|---|---| composite_detection.py
|----|---|---| empty_cell_box_detection_node.py
|----|---|---| empty_composite_cellbox_detection_node.py
|----|---|---| filled_cellbox_detection_node.py
|----|---|---| filled_composite_cellbox_detection_node.py
|----|---|---| main.py
|----|---|---| move_group_python_interface.py
|----|---|---| winding_detect_node.py
|----|---|---| yellow_bracket_detection_node.py

```

`my_robot_calibration.yaml` will add to the home

## 8-2. Command

1. If you saved my\_robot\_calibration.yaml to your home directory, run the following. If the path doesn't exist, you'll need to reset it to match your computer's path.

```
chmod+x ~/my_robot_calibration.yaml
```

2. Since the project is based on ROS environment, every command line is done under catkin workspace directory.

```
cd~/catkin_ws  
catkin_make  
roscore
```

3. To activate the system, the robot should be connected to a computer. Communication protocol is TCP/IP based therefore, IP should be set in proper manner

```
roslaunch ur_robot_driver ur5eBringup.launch robot_ip:=192.168.0.2  
roslaunch ur5e_rg2_moveit_config move_group.launch
```

4. Connect camera in UR5e

```
chmod +x ~/catkin_ws/src/ur_python/src/camera.py  
rosrun 22000167_Kiminyeop_ur_python camera.py
```

5. Follow the steps below

- Empty Bracket Detection: This detection node detects yellow bracket holes.

```
chmod +x ~/catkin_ws/src/ur_python/src/yellow_bracket_detection_node.py  
rosrun 22000167_Kiminyeop_ur_python yellow_bracket_detection_node.py
```

- Cell Box Cell Detection: This detection node detects cells in empty cell boxes.

```
chmod +x ~/catkin_ws/src/ur_python/src/filled_cellbox_detection_node.py  
rosrun 22000167_Kiminyeop_ur_python filled_cellbox_detection_node.py
```

- Empty Completed Box Detection: This detection node detects empty boxes in completed cell boxes.

```
chmod +x  
~/catkin_ws/src/ur_python/src/empty_composite_cellbox_detection_node.py  
rosrun 22000167_Kiminyeop_ur_python empty_composite_cellbox_detection_node.py
```

- Completed Cell Box Detection: This detection node detects cells in a completed cell box.

```
chmod +x  
~/catkin_ws/src/ur_python/src/filled_composite_cellbox_detection_node.py  
rosrun 22000167_Kiminyeop_ur_python filled_composite_cellbox_detection_node.py
```

- Empty Cell Box Detection: This detection node detects empty boxes in an empty cell box.

```
chmod +x ~/catkin_ws/src/ur_python/src/empty_cell_cellbox_detection_node.py  
rosrun 22000167_Kiminyeop_ur_python empty_cell_cellbox_detection_node.py
```

- Orange Winding Detection: This detection node detects orange windings.

```
chmod +x ~/catkin_ws/src/ur_python/src/winding_detect_node.py  
rosrun 22000167_Kiminyeop_ur_python winding_detect_node.py
```

- Completed Cell Detection: This detection node detects completed cells.

```
chmod +x ~/catkin_ws/src/ur_python/src/composite_detection.py  
rosrun 22000167_Kiminyeop_ur_python composite_detection.py
```

## 8. Cell Detection: This detection node detects empty cells.

```
chmod +x ~/catkin_ws/src/ur_python/src/cell_detection.py  
rosrun 22000167_Kiminyeop_ur_python cell_detection.py
```

- Run Arduino Stopper  
After installing Arduino 1.8.19, confirm that the board is Arduino Uno in the tool bar and that the port is dev/tty/ACM0. Confirm and upload, then close the Arduino window.

## 10. Enter VScode and run main.py.

## 8-3 Troubleshooting

- If the robot movement doesn't work, it's almost always due to a problem with

```
roslaunch ur_robot_driver ur5e_bringup.launch robot_ip:=192.168.0.2
```

Therefore, undoing and re-running this terminal should resolve the issue.

## 2. If you run the code

```
chmod +x ~/catkin_ws/src/ur_python/src/camera.py
rosrun 22000167_Kiminyeop_ur_python camera.py
```

the camera may not be connected to the ur5e robot but to the laptop. In this case, adjust the numeric value of `self.cap = cv2.VideoCapture(2)` from 0 to 5 and then run the program.

## 8-4 Code

```
my_robot_calibration.yaml
```

```
kinematics:
  shoulder:
    x: 0
    y: 0
    z: 0.1627122445743823
    roll: -0
    pitch: 0
    yaw: 5.707382499074709e-08
  upper_arm:
    x: 0.0001820110310317555
    y: 0
    z: 0
    roll: 1.571314866107557
    pitch: 0
    yaw: 1.12157791523139e-06
  forearm:
    x: -0.425170344631444
    y: 0
    z: 0
    roll: 0.001444320579376547
    pitch: -0.0004261037597356073
    yaw: 4.642343028998144e-06
  wrist_1:
    x: -0.392646598028507
    y: -0.0004030322688786401
    z: 0.1331063119537431
    roll: 0.003027888244224887
```

```
pitch: -0.001185722601572754
yaw: -2.569771029137183e-06
wrist_2:
x: -7.071306960874342e-06
y: -0.09960359635829828
z: -3.198591184007791e-07
roll: 1.570799538115874
pitch: 0
yaw: 1.304820282092834e-06
wrist_3:
x: 1.369362273278849e-05
y: 0.09958483828527664
z: 9.521789789182917e-05
roll: 1.571752475045119
pitch: 3.141592653589793
yaw: 3.141592510837143
hash: calib_14698139022496758595
```

#### CMakeLists.txt

```
cmake_minimum_required(VERSION 3.0.2)
project(ur_python)

## Compile as C++11, supported in ROS Kinetic and newer
# add_compile_options(-std=c++11)

## Find catkin macros and libraries
## if COMPONENTS list like find_package(catkin REQUIRED COMPONENTS xyz)
## is used, also find other catkin packages
find_package(catkin REQUIRED COMPONENTS
  rospy
  message_generation
  std_msgs
  message_runtime
  moveit_ros_planning
  moveit_ros_planning_interface
  moveit_visual_tools
  geometry_msgs
  image_transport
  cv_bridge
  sensor_msgs
)
find_package (OpenCV REQUIRED)
add_message_files(
```

```

FILES
object_info.msg
robot_state.msg
grip_command.msg
grip_state.msg
pet_info.msg
)

generate_messages(
DEPENDENCIES
std_msgs
geometry_msgs
)

## System dependencies are found with CMake's conventions
# find_package(Boost REQUIRED COMPONENTS system)

## Uncomment this if the package has a setup.py. This macro ensures
## modules and global scripts declared therein get installed
## See http://ros.org/doc/api/catkin/html/user_guide/setup_dot_py.html
# catkin_python_setup()

#####
## Declare ROS messages, services and actions ##
#####

## To declare and build messages, services or actions from within this
## package, follow these steps:
## * Let MSG_DEPENDENCIES be the set of packages whose message types you use in
##   your messages/services/actions (e.g. std_msgs, actionlib_msgs, ...).
## * In the file package.xml:
##   * add a build_depend tag for "message_generation"
##   * add a build_depend and a exec_depend tag for each package in
MSG_DEPENDENCIES
##   * If MSG_DEPENDENCIES isn't empty the following dependency has been pulled in
##     but can be declared for certainty nonetheless:
##       * add a exec_depend tag for "message_runtime"
## * In this file (CMakeLists.txt):
##   * add "message_generation" and every package in MSG_DEPENDENCIES to
##     find_package(catkin REQUIRED COMPONENTS ...)
##   * add "message_runtime" and every package in MSG_DEPENDENCIES to
##     catkin_package(CATKIN_DEPENDS ...)
##   * uncomment the add_*_files sections below as needed
##     and list every .msg/.srv/.action file to be processed
##   * uncomment the generate_messages entry below

```

```

## * add every package in MSG_DEP_SET to generate_messages(DEPENDENCIES ...)

## Generate messages in the 'msg' folder
# add_message_files(
#   FILES
#   Message1.msg
#   Message2.msg
# )

## Generate services in the 'srv' folder
# add_service_files(
#   FILES
#   Service1.srv
#   Service2.srv
# )

## Generate actions in the 'action' folder
# add_action_files(
#   FILES
#   Action1.action
#   Action2.action
# )

## Generate added messages and services with any dependencies listed here
# generate_messages(
#   DEPENDENCIES
#   std_msgs
# )

#####
## Declare ROS dynamic reconfigure parameters ##
#####

## To declare and build dynamic reconfigure parameters within this
## package, follow these steps:
## * In the file package.xml:
##   * add a build_depend and a exec_depend tag for "dynamic_reconfigure"
## * In this file (CMakeLists.txt):
##   * add "dynamic_reconfigure" to
##     find_package(catkin REQUIRED COMPONENTS ...)
##   * uncomment the "generate_dynamic_reconfigure_options" section below
##     and list every .cfg file to be processed

## Generate dynamic reconfigure parameters in the 'cfg' folder
# generate_dynamic_reconfigure_options(
#   cfg/DynReconf1.cfg

```

```

#    cfg/DynReconf2.cfg
# )

#####
## catkin specific configuration ##
#####

## The catkin_package macro generates cmake config files for your package
## Declare things to be passed to dependent projects
## INCLUDE_DIRS: uncomment this if your package contains header files
## LIBRARIES: libraries you create in this project that dependent projects
## also need
## CATKIN_DEPENDS: catkin_packages dependent projects also need
## DEPENDS: system dependencies of this project that dependent projects also
## need
catkin_package(
#  INCLUDE_DIRS include
#  LIBRARIES ur_python
#  CATKIN_DEPENDS rospy std_msgs
#  DEPENDS system_lib
    LIBRARIES opencv
    CATKIN_DEPENDS
        cv_bridge
        image_transport
        sensor_msgs
        std_msgs
)
######
## Build ##
#####

## Specify additional locations of header files
## Your package locations should be listed before other locations
include_directories(
# include
    ${catkin_INCLUDE_DIRS}
    ${OpenCV_INCLUDE_DIRS}
)
## Declare a C++ library
# add_library(${PROJECT_NAME}
#   src/${PROJECT_NAME}/ur_python.cpp
# )
## Add cmake target dependencies of the library
## as an example, code may need to be generated before libraries

```

```

## either from message generation or dynamic reconfigure
# add_dependencies(${PROJECT_NAME} ${${PROJECT_NAME}_EXPORTED_TARGETS}
#${catkin_EXPORTED_TARGETS})

## Declare a C++ executable
## With catkin_make all packages are built within a single CMake context
## The recommended prefix ensures that target names across packages don't
## collide
# add_executable(${PROJECT_NAME}_node src/ur_python_node.cpp)

## Rename C++ executable without prefix
## The above recommended prefix causes long target names, the following
## renames the
## target back to the shorter version for ease of user use
## e.g. "rosrun someones_pkg node" instead of "rosrun someones_pkg
## someones_pkg_node"
# set_target_properties(${PROJECT_NAME}_node PROPERTIES OUTPUT_NAME node
PREFIX "")

## Add cmake target dependencies of the executable
## same as for the library above
# add_dependencies(${PROJECT_NAME}_node ${${PROJECT_NAME}_EXPORTED_TARGETS}
#${catkin_EXPORTED_TARGETS})

## Specify libraries to link a library or executable target against
# target_link_libraries(${PROJECT_NAME}_node
#   ${catkin_LIBRARIES}
# )

#####
## Install ##
#####

# all install targets should use catkin DESTINATION variables
# See http://ros.org/doc/api/catkin/html/adv\_user\_guide/variables.html

## Mark executable scripts (Python etc.) for installation
## in contrast to setup.py, you can choose the destination
# catkin_install_python(PROGRAMS
#   scripts/my_python_script
#   DESTINATION ${CATKIN_PACKAGE_BIN_DESTINATION}
# )

## Mark executables for installation
## See
http://docs.ros.org/melodic/api/catkin/html/howto/format1/building\_executables

```

```

.html
# install(TARGETS ${PROJECT_NAME}_node
#   RUNTIME DESTINATION ${CATKIN_PACKAGE_BIN_DESTINATION}
# )

## Mark libraries for installation
## See
http://docs.ros.org/melodic/api/catkin/html/howto/format1/building\_libraries.html
# install(TARGETS ${PROJECT_NAME}
#   ARCHIVE DESTINATION ${CATKIN_PACKAGE_LIB_DESTINATION}
#   LIBRARY DESTINATION ${CATKIN_PACKAGE_LIB_DESTINATION}
#   RUNTIME DESTINATION ${CATKIN_GLOBAL_BIN_DESTINATION}
# )

## Mark cpp header files for installation
# install(DIRECTORY include/${PROJECT_NAME}/
#   DESTINATION ${CATKIN_PACKAGE_INCLUDE_DESTINATION}
#   FILES_MATCHING PATTERN "*.h"
#   PATTERN ".svn" EXCLUDE
# )

## Mark other files for installation (e.g. launch and bag files, etc.)
# install(FILES
#   # myfile1
#   # myfile2
#   DESTINATION ${CATKIN_PACKAGE_SHARE_DESTINATION}
# )

#####
## Testing ##
#####

## Add gtest based cpp test target and link libraries
# catkin_add_gtest(${PROJECT_NAME}-test test/test_ur_python.cpp)
# if(TARGET ${PROJECT_NAME}-test)
#   target_link_libraries(${PROJECT_NAME}-test ${PROJECT_NAME})
# endif()

## Add folders to be run by python nosetests
# catkin_add_nosetests(test)

```

camera.py

```

#!/usr/bin/env python3
#-- coding:utf-8 --

```

```

import rospy
import cv2
from sensor_msgs.msg import Image          # sensor_msg 패키지로부터 Image
type을 import함
from cv_bridge import CvBridge, CvBridgeError # cv_bridge 라이브러리 : OpenCV
이미지와 ROS 메시지 간의 변환 가능

class CameraNode:

    def __init__(self):
        self.bridge = CvBridge()           # cv_bridge 객체 생성
        self.image_pub =
rospy.Publisher("camera/image_raw", Image, queue_size=1)      #
"camera/image_raw"라는 토픽으로 메시지를 publish할 publisher 객체 생성
        self.cap = cv2.VideoCapture(2)       # 카메라 연결을 위한 VideoCapture
객체 생성

    def run(self):
        rospy.init_node('camera_node', anonymous=True) # 노드 이름
"camera_node"로 초기화
        rate = rospy.Rate(30)                 # 루프 실행 주기 : 30hz
        while not rospy.is_shutdown():        # ROS가 종료되지 않은 동
안
            ret, frame = self.cap.read()       # 카메라로부터 이미지를
읽음
            if ret:                          # 이미지가 정상적으로 읽
현진 경우
                try:
                    # 읽어들인 이미지를 ROS Image 메시지로 변환하여 토픽으로 publish
                    self.image_pub.publish(self.bridge.cv2_to_imgmsg(frame,
"bgr8"))

                except CvBridgeError as e:
                    print(e)                  # CvBridge 변환 예외 처리
리
                rate.sleep()               # 지정된 루프 실행 주기에
따라 대기

if __name__ == '__main__':
    try:
        camera = CameraNode()          # CameraNode 객체 생성
        camera.run()                  # run 메서드 실행
    except rospy.ROSInterruptException:
        pass

```

## cell\_detection.py

```
#!/usr/bin/env python3
# -*- coding:utf-8 -*-

import rospy, cv2, numpy as np, os, math
from sensor_msgs.msg import Image
from cv_bridge import CvBridge
from geometry_msgs.msg import Point

class StableGrayDetectionNode:
    def __init__(self):
        rospy.init_node('stable_gray_detection_node', anonymous=True)
        self.bridge = CvBridge()
        self.detection_pub = rospy.Publisher('/grid1_fallback/result', Point,
queue_size=1)
        self.image_sub = rospy.Subscriber("/camera/image_raw", Image,
self.image_callback)

        # =====
        # ✎ 사용자 조정 파라미터
        # =====
        self.ROI_WIDTH = 400
        self.ROI_HEIGHT = 400
        self.TARGET_SIZE = (1200, 1200)
        self.CENTER_PX = (600, 600)
        self.DETECTION_OFFSET = 300

        # 픽셀 → mm 변환
        self.scale_x = 0.13
        self.scale_y = 0.13

        # 카메라 오프셋
        self.CAMERA_OFFSET_X_MM = 88.0
        self.CAMERA_OFFSET_Y_MM = 3.0

        # 반지름 필터
        self.MIN_RADIUS = 170
        self.MAX_RADIUS = 250
        self.CENTER_TOL_MM = 10.0

        # Gray 톤 필터
        self.LOWER_GRAY = 140
        self.UPPER_GRAY = 255

        # Hough 파라미터
```

```

        self.HOUGH_DP = 1
        self.HOUGH_MIN_DIST = 100
        self.HOUGH_PARAM1 = 50
        self.HOUGH_PARAM2 = 20

        # EMA 필터
        self.prev_center = None
        self.prev_radius = None
        self.alpha = 0.35

        # 🔴 주황색 감지 파라미터 (반대 조건)
        self.ORANGE_RATIO_THRESH = 0.03 # 3% 이상이면 무시
        self.ORANGE_MIN = (50, 80, 240)
        self.ORANGE_MAX = (120, 150, 255)

        # 🟡 노란색 감지 파라미터 (너가 지정한 EXACT 값)
        self.YELLOW_RATIO_THRESH = 0.03

        self.lower_yellow1 = np.array([20, 120, 120])
        self.upper_yellow1 = np.array([32, 255, 255])

        self.lower_yellow2 = np.array([0, 0, 0])
        self.upper_yellow2 = np.array([0, 0, 0])

# =====
# 📁 카메라 캘리브레이션
# =====

calib_path =
"/home/kiminyeop/catkin_ws/src/ur_python/src/dataset_bra2_checkboard3/circlegrid_calibration_results_8x6_20mm.npz"
if os.path.exists(calib_path):
    data = np.load(calib_path)
    self.camera_matrix = data["camera_matrix"]
    self.dist_coeffs = data["dist_coeffs"]
    rospy.loginfo("📷 Loaded camera calibration from: {}").format(calib_path)
else:
    rospy.logwarn("⚠ Calibration file not found - skipping undistortion.")
    self.camera_matrix, self.dist_coeffs = None, None

    rospy.loginfo("🔴 Stable Gray Detection Node initialized (Gray only, ignore Orange+Yellow)")

# -----
def image_callback(self, msg):
    try:

```

```

        frame = self.bridge.imgmsg_to_cv2(msg, "bgr8")
        if self.camera_matrix is not None:
            frame = cv2.undistort(frame, self.camera_matrix,
self.dist_coeffs)

        H, W = frame.shape[:2]
        x1 = int(W/2 - self.ROI_WIDTH/2)
        y1 = int(H/2 - self.ROI_HEIGHT/2)
        cropped = frame[y1:y1+self.ROI_HEIGHT, x1:x1+self.ROI_HEIGHT]
        resized = cv2.resize(cropped, self.TARGET_SIZE,
interpolation=cv2.INTER_LINEAR)

        self.detect_gray_circle(resized)

    except Exception as e:
        rospy.logerr(f"Gray Detection Error: {e}")

# -----
def detect_gray_circle(self, frame):
    output = frame.copy()
    gray = cv2.cvtColor(frame, cv2.COLOR_BGR2GRAY)
    gray_filtered = cv2.inRange(gray, self.LOWER_GRAY, self.UPPER_GRAY)
    gray_blurred = cv2.GaussianBlur(gray_filtered, (9, 9), 2)

    # === HSV 변환 (노란색 검출을 위해 추가)
    hsv = cv2.cvtColor(frame, cv2.COLOR_BGR2HSV)

    OFFSET = self.DETECTION_OFFSET
    HOUGH_SIZE = 600
    HOUGH_INPUT = gray_blurred[OFFSET:OFFSET + HOUGH_SIZE, OFFSET:OFFSET +
HOUGH_SIZE]

    circles = cv2.HoughCircles(
        HOUGH_INPUT, cv2.HOUGH_GRADIENT,
        self.HOUGH_DP, self.HOUGH_MIN_DIST,
        param1=self.HOUGH_PARAM1, param2=self.HOUGH_PARAM2,
        minRadius=self.MIN_RADIUS, maxRadius=self.MAX_RADIUS
    )

    best_circle_data = None
    min_dist_to_center = float('inf')

    # ◆ 가장 중앙에 가까운 원 선택
    if circles is not None:
        circles = np.uint16(np.around(circles))
        for i in circles[0, :]:

```

```

        x_rel, y_rel, r = i[0], i[1], i[2]
        x = x_rel + OFFSET
        y = y_rel + OFFSET
        dx_px = float(x - self.CENTER_PX[0])
        dy_px = float(y - self.CENTER_PX[1])
        dist_px = math.sqrt(dx_px**2 + dy_px**2)
        if dist_px < min_dist_to_center:
            min_dist_to_center = dist_px
            best_circle_data = (x, y, r, 1.0)

    # ◆ 결과 처리
    if best_circle_data is not None:
        x, y, r, _ = best_circle_data

    # EMA 안정화
    if self.prev_center is None:
        self.prev_center = np.array([x, y], dtype=float)
        self.prev_radius = r
    else:
        self.prev_center = (1 - self.alpha) * self.prev_center +
self.alpha * np.array([x, y])
        self.prev_radius = (1 - self.alpha) * self.prev_radius +
self.alpha * r

    x, y = self.prev_center
    r = self.prev_radius

    # === 🍊 원 내부 오렌지 비율 계산 ===
    mask = np.zeros(frame.shape[:2], dtype=np.uint8)
    cv2.circle(mask, (int(x), int(y)), int(r), 255, -1)
    orange_mask = cv2.inRange(frame, self.ORANGE_MIN, self.ORANGE_MAX)
    orange_inside = cv2.bitwise_and(orange_mask, orange_mask,
mask=mask)
    orange_ratio = np.sum(orange_inside > 0) / np.sum(mask > 0)
    rospy.loginfo_throttle(1.0, f"🍊 Orange ratio inside circle:
{orange_ratio*100:.2f}%")


    # === 🟡 원 내부 노란색 비율 계산 (너가 지정한 HSV 기준 사용) ===
    yellow_mask1 = cv2.inRange(hsv, self.lower_yellow1,
self.upper_yellow1)
    yellow_mask2 = cv2.inRange(hsv, self.lower_yellow2,
self.upper_yellow2)
    yellow_mask = cv2.bitwise_or(yellow_mask1, yellow_mask2)

    yellow_inside = cv2.bitwise_and(yellow_mask, yellow_mask,
mask=mask)

```

```

yellow_ratio = np.sum(yellow_inside > 0) / np.sum(mask > 0)
rospy.loginfo_throttle(1.0, f"🟡 Yellow ratio inside circle: {yellow_ratio*100:.2f}%")


# === 픽셀 → mm 변환 ===
dx_px = float(x - self.CENTER_PX[0])
dy_px = float(y - self.CENTER_PX[1])
dx_mm = dx_px * self.scale_x
dy_mm = dy_px * self.scale_y
dist_mm = math.sqrt(dx_mm**2 + dy_mm**2)

# === 카메라 오프셋 보정 ===
dx_mm_total = -dy_mm + self.CAMERA_OFFSET_X_MM
dy_mm_total = -dx_mm + self.CAMERA_OFFSET_Y_MM

# ✅ 회색 원은 감지 + 주황색 OR 노란색 > threshold 이면 무시
if (
    dist_mm <= self.CENTER_TOL_MM and
    orange_ratio <= self.ORANGE_RATIO_THRESH and
    yellow_ratio <= self.YELLOW_RATIO_THRESH
):
    cv2.circle(output, (int(x), int(y)), int(r), (0, 255, 0), 2)
    cv2.circle(output, (int(x), int(y)), 5, (0, 0, 255), -1)
    cv2.circle(output, self.CENTER_PX, 5, (255, 0, 0), -1)

    cv2.putText(output, f"dx={dx_mm:.1f} dy={dy_mm:.1f} (OK gray only)",
               (25, 45), cv2.FONT_HERSHEY_SIMPLEX, 0.8, (0, 255, 0),
               2)
    cv2.putText(output, f"XOFF -> dx={dx_mm_total:.1f} dy={dy_mm_total:.1f}",
               (25, 85), cv2.FONT_HERSHEY_SIMPLEX, 0.8,
               (255, 255, 0), 2)

    self.detection_pub.publish(Point(x=float(dx_mm_total),
                                     y=float(dy_mm_total), z=float(r)))
    rospy.loginfo_throttle(1.0, f"✅ Valid Gray (no orange/yellow): dx={dx_mm_total:.1f}, dy={dy_mm_total:.1f}")

else:
    rospy.logwarn_throttle(1.0,
                           f"⚠️ Ignored (dist={dist_mm:.1f}mm, "
                           f"orange={orange_ratio*100:.1f}%, yellow={yellow_ratio*100:.1f}%)")
    self._publish_fail()

```

```

        else:
            rospy.logwarn_throttle(1.0, "X No circle found.")
            self._publish_fail()

        # 시각화
        cv2.rectangle(output, (OFFSET, OFFSET), (OFFSET + HOUGH_SIZE, OFFSET +
HOUGH_SIZE), (255, 0, 0), 2)
        cv2.imshow("Stable Gray Detection (Gray only, Ignore Orange +
Yellow)", output)
        cv2.imshow("Hough Filtered Input", gray_blurred)
        cv2.imshow("Orange Mask Inside Circle", orange_inside)
        cv2.imshow("Yellow Mask Inside Circle", yellow_inside)
        cv2.waitKey(1)

# -----
def _publish_fail(self):
    self.detection_pub.publish(Point(x=0.0, y=0.0, z=0.0))

# -----
if __name__ == '__main__':
    try:
        StableGrayDetectionNode()
        rospy.spin()
    except rospy.ROSInterruptException:
        cv2.destroyAllWindows()

```

composite\_detection.py

```

#!/usr/bin/env python3
# -*- coding:utf-8 -*-

import rospy, cv2, numpy as np, os, math
from sensor_msgs.msg import Image
from cv_bridge import CvBridge
from geometry_msgs.msg import Point

class StableGrayDetectionNode:
    def __init__(self):
        rospy.init_node('stable_gray2_detection_node', anonymous=True)
        self.bridge = CvBridge()
        self.detection_pub = rospy.Publisher('/grid2_fallback/result', Point,
queue_size=1)
        self.image_sub = rospy.Subscriber("/camera/image_raw", Image,
self.image_callback)

# =====

```

```

# ❀ 사용자 조정 파라미터 (Hough에 맞게 조정)
# =====
self.ROI_WIDTH = 400
self.ROI_HEIGHT = 400
self.TARGET_SIZE = (1200, 1200)
self.CENTER_PX = (600, 600)
self.DETECTION_OFFSET = 300

# 픽셀 → mm 변환
self.scale_x = 0.13
self.scale_y = 0.13

# 카메라 오프셋
self.CAMERA_OFFSET_X_MM = 88.0
self.CAMERA_OFFSET_Y_MM = 3.0

# 반지름 필터 (픽셀)
self.MIN_RADIUS = 170
self.MAX_RADIUS = 250

# 중심 허용 거리 (mm)
self.CENTER_TOL_MM = 20.0

# Gray 톤 필터링 범위
self.LOWER_GRAY = 140
self.UPPER_GRAY = 255

# Hough 파라미터
self.HOUGH_DP = 1
self.HOUGH_MIN_DIST = 100
self.HOUGH_PARAM1 = 50
self.HOUGH_PARAM2 = 20

# EMA 필터
self.prev_center = None
self.prev_radius = None
self.alpha = 0.35

# =====
# 📁 카메라 캘리브레이션
# =====
calib_path =
"/home/kiminyeop/catkin_ws/src/ur_python/src/dataset_bra2_checkboard3/circlegrid_calibration_results_8x6_20mm.npz"
if os.path.exists(calib_path):
    data = np.load(calib_path)

```

```

        self.camera_matrix = data["camera_matrix"]
        self.dist_coeffs = data["dist_coeffs"]
        rospy.loginfo(f"📸 Loaded camera calibration from: {calib_path}")
    else:
        rospy.logwarn("⚠️ Calibration file not found - skipping undistortion.")
        self.camera_matrix, self.dist_coeffs = None, None

    rospy.loginfo("🌐 Stable Gray Detection Node initialized (Hough Transform, Limited ROI)")

# -----
def image_callback(self, msg):
    try:
        frame = self.bridge.imgmsg_to_cv2(msg, "bgr8")
        if self.camera_matrix is not None:
            frame = cv2.undistort(frame, self.camera_matrix,
self.dist_coeffs)

            H, W = frame.shape[:2]
            x1 = int(W/2 - self.ROI_WIDTH/2)
            y1 = int(H/2 - self.ROI_HEIGHT/2)
            cropped = frame[y1:y1+self.ROI_HEIGHT, x1:x1+self.ROI_HEIGHT]
            resized = cv2.resize(cropped, self.TARGET_SIZE,
interpolation=cv2.INTER_LINEAR)

            self.detect_gray_circle(resized)

    except Exception as e:
        rospy.logerr(f"Gray Detection Error: {e}")

# -----
def detect_gray_circle(self, frame):
    output = frame.copy()
    gray = cv2.cvtColor(frame, cv2.COLOR_BGR2GRAY)
    gray_filtered = cv2.inRange(gray, self.LOWER_GRAY, self.UPPER_GRAY)
    gray_blurred = cv2.GaussianBlur(gray_filtered, (9, 9), 2)

    OFFSET = self.DETECTION_OFFSET
    HOUGH_SIZE = 600
    HOUGH_INPUT = gray_blurred[OFFSET:OFFSET + HOUGH_SIZE, OFFSET:OFFSET + HOUGH_SIZE]

    circles = cv2.HoughCircles(
        HOUGH_INPUT, cv2.HOUGH_GRADIENT,
        self.HOUGH_DP, self.HOUGH_MIN_DIST,

```

```

        param1=self.HOUGH_PARAM1, param2=self.HOUGH_PARAM2,
        minRadius=self.MIN_RADIUS, maxRadius=self.MAX_RADIUS
    )

    best_circle_data = None
    min_dist_to_center = float('inf')

    if circles is not None:
        circles = np.uint16(np.around(circles))
        for i in circles[0, :]:
            x_rel, y_rel, r = i[0], i[1], i[2]
            x = x_rel + OFFSET
            y = y_rel + OFFSET
            dx_px = float(x - self.CENTER_PX[0])
            dy_px = float(y - self.CENTER_PX[1])
            dist_px = math.sqrt(dx_px**2 + dy_px**2)
            if dist_px < min_dist_to_center:
                min_dist_to_center = dist_px
                best_circle_data = (x, y, r)

    if best_circle_data is not None:
        x, y, r = best_circle_data

    # EMA 안정화
    if self.prev_center is None:
        self.prev_center = np.array([x, y], dtype=float)
        self.prev_radius = r
    else:
        self.prev_center = (1 - self.alpha) * self.prev_center +
self.alpha * np.array([x, y])
        self.prev_radius = (1 - self.alpha) * self.prev_radius +
self.alpha * r

    x, y = self.prev_center
    r = self.prev_radius

    # 픽셀 → mm 변환
    dx_px = float(x - self.CENTER_PX[0])
    dy_px = float(y - self.CENTER_PX[1])
    dx_mm = dx_px * self.scale_x
    dy_mm = dy_px * self.scale_y
    dist_mm = math.sqrt(dx_mm**2 + dy_mm**2)

    # 오프셋 적용
    dx_mm_total = -dy_mm + self.CAMERA_OFFSET_X_MM
    dy_mm_total = -dx_mm + self.CAMERA_OFFSET_Y_MM

```

```

if dist_mm <= self.CENTER_TOL_MM:
    # 시각화
    cv2.circle(output, (int(x), int(y)), int(r), (0,255,0), 2)
    cv2.circle(output, (int(x), int(y)), 5, (0,0,255), -1)
    cv2.circle(output, self.CENTER_PX, 5, (255,0,0), -1)

    # --- ✅ 텍스트 출력 (raw + XOFFSET 적용)
    cv2.putText(output, f"dx={dx_mm:.1f} dy={dy_mm:.1f}",
                (25,45), cv2.FONT_HERSHEY_SIMPLEX, 0.8, (0,255,0),
2)
    cv2.putText(output, f"XOFF -> dx={dx_mm_total:.1f} dy=
{dy_mm_total:.1f}",
                (25,85), cv2.FONT_HERSHEY_SIMPLEX, 0.8,
(255,255,0), 2)

    # 퍼블리시
    self.detection_pub.publish(Point(x=float(dx_mm_total),
y=float(dy_mm_total), z=float(r)))
    rospy.loginfo_throttle(1.0, f"🔴 Valid Circle: dx=
{dx_mm_total:.1f}, dy={dy_mm_total:.1f}")
    else:
        rospy.logwarn_throttle(1.0, f"⚠️ Circle ignored (dist=
{dist_mm:.1f}mm > {self.CENTER_TOL_MM}mm)")
        self._publish_fail()
    else:
        rospy.logwarn_throttle(1.0, "✖️ No circle found in Hough area.")
        self._publish_fail()

    # 시각화
    cv2.rectangle(output, (OFFSET, OFFSET), (OFFSET + HOUGH_SIZE, OFFSET +
HOUGH_SIZE), (255, 0, 0), 2)
    cv2.imshow("Stable Gray2 Detection (Hough Transform, Limited ROI)",
output)
    cv2.imshow("Gray2 Hough Filtered Input", gray_blurred)
    cv2.waitKey(1)

# -----
def _publish_fail(self):
    self.detection_pub.publish(Point(x=0.0, y=0.0, z=0.0))

# -----
if __name__ == '__main__':
    try:
        StableGrayDetectionNode()
        rospy.spin()

```

```
    except rospy.ROSInterruptException:  
        cv2.destroyAllWindows()
```

## empty\_cell\_cellbox\_detection\_node.py

```
#!/usr/bin/env python3  
# -*- coding:utf-8 -*-  
  
import rospy, cv2, numpy as np  
from sensor_msgs.msg import Image  
from cv_bridge import CvBridge  
from std_msgs.msg import String # 발행할 메시지 타입  
  
class InverseGrayDetectionNode:  
    def __init__(self):  
        rospy.init_node('gray_detection_node', anonymous=True)  
        self.bridge = CvBridge()  
        self.detection_pub = rospy.Publisher('/inverse_gray_detection_result',  
String, queue_size=1)  
        self.image_sub = rospy.Subscriber("/camera/image_raw", Image,  
self.image_callback)  
  
        # === 그리드 설정 ===  
        self.P1, self.P2, self.P3 = (105, 77), (547, 73), (105, 433)  
        self.cols, self.rows = 4, 3  
        self.active_cells = {(1,1),(1,3),(2,2),(2,4),(3,1),(3,3)}  
        self.gray_history = [] # 안정화용  
  
        # === 🚨 [수정] 검정색 픽셀 감지 임계값 (HSV 사용) ===  
        # 검정색: V(명도)가 낮음 (V <= 60)  
        self.lower_black, self.upper_black = np.array([0, 0, 0]),  
np.array([150, 150, 150])  
  
        # 🚨 [수정] 검정색 픽셀의 최소 면적 비율 (물체가 있다고 판단하는 기준)  
        self.BLACK_PIXEL_RATIO = 0.77 # 감지 최소 면적 비율 (90% 이상일 때  
DETECTED)  
  
        # ✅ 우선순위 리스트 (문자열 정렬 순서로 가장 높은 우선순위 결정)  
        self.priority_list = sorted([f'{r}-{c}' for r, c in  
self.active_cells])  
  
    def image_callback(self, msg):  
        try:  
            frame = self.bridge.imgmsg_to_cv2(msg, "bgr8")  
            result_frame = self.black_area_detect(frame) # 함수 이름  
'black_area_detect'로 변경
```

```

        cv2.imshow("Black Area Grid Cell Detection", result_frame)
        cv2.waitKey(1)
    except Exception as e:
        rospy.logerr(f"Detection Error: {e}")

def black_area_detect(self, frame):
    display_frame = frame.copy()
    hsv = cv2.cvtColor(frame, cv2.COLOR_BGR2HSV) # HSV 변환

    xs = np.linspace(self.P1[0], self.P2[0], self.cols+1)
    ys = np.linspace(self.P1[1], self.P3[1], self.rows+1)
    detected_black = set() # 감지된 '검정색 물체' 셀 목록

    for i in range(self.rows):
        for j in range(self.cols):
            r, c = i+1, j+1
            x1, x2 = int(xs[j]), int(xs[j+1])
            y1, y2 = int(ys[i]), int(ys[i+1])

            # 영역 유효성 검사
            if y2 <= y1 or x2 <= x1:
                continue

            cell_roi = hsv[y1:y2, x1:x2]
            cell_area = cell_roi.shape[0] * cell_roi.shape[1]

            # 1. HSV 임계값을 사용하여 검정색 픽셀 마스크 생성
            black_mask = cv2.inRange(cell_roi, self.lower_black,
self.upper_black)

            # 2. 검정색 픽셀의 개수 및 비율 계산
            black_pixel_count = np.sum(black_mask == 255)
            current_ratio = black_pixel_count / cell_area if cell_area > 0
            else 0

            cell_name = f"{r}-{c}"
            color = (80,80,80) # 기본 회색 (비활성)
            text = f'{cell_name} ({current_ratio:.2f})'

            # ↗️ 시각화는 원본 BGR 프레임 복사본(display_frame)에 수행
            if (r,c) in self.active_cells:

                # 🚨 [감지 조건] 검정색 픽셀 비율이 BLACK_PIXEL_RATIO 이상일 때
                if current_ratio >= self.BLACK_PIXEL_RATIO:
                    detected_black.add(cell_name)

```

```

        color = (255, 165, 0) # 주황색 (물체 감지)
        text = f"DETECTED ({current_ratio:.2f})"
    else:
        # 🚨 [미감지] 검정색 물체가 없다고 판단 (NOT DETECTED / EMPTY)
        color = (0, 255, 0) # 녹색 (물체 없음)
        text = f"EMPTY ({current_ratio:.2f})"

        # ✨ 활성 셀 테두리 및 텍스트 표시
        cv2.rectangle(display_frame, (x1, y1), (x2, y2), color, 2)
        cx, cy = int((x1+x2)/2), int((y1+y2)/2)
        cv2.putText(display_frame, text, (cx - 60, cy),
                    cv2.FONT_HERSHEY_SIMPLEX, 0.5, (255, 255, 255),
2)
else:
    # ✨ 비활성 셀 테두리 표시
    cv2.rectangle(display_frame, (x1, y1), (x2, y2), color, 1)

# ✨ 5프레임 안정화 및 우선순위가 가장 높은 셀 하나만 발행하는 로직
# 감지된 '검정색 물체' 셀들의 목록을 우선순위에 따라 정렬
detected_list = sorted(list(detected_black), key=lambda x:
self.priority_list.index(x) if x in self.priority_list else
len(self.priority_list))

is_published = False

# '검정색 물체'가 감지된 경우
if detected_list:
    highest_priority_cell = detected_list[0]
    # 히스토리에 (최우선 순위 셀) 문자열을 포함하는 frozenset을 저장
    self.gray_history.append(frozenset({highest_priority_cell}))
else:
    self.gray_history.append(frozenset()) # 감지된 셀이 없으면 빈 세트 추가

if len(self.gray_history) > 5: self.gray_history.pop(0)

# 5프레임 동안 감지된 셀이 존재하고, 그 셀이 모두 동일한 최우선 순위 셀일 경우
if (len(self.gray_history) == 5 and
    all(h == self.gray_history[0] for h in self.gray_history) and
    len(self.gray_history[0]) == 1):

    # 최우선 순위 셀의 문자열을 추출하여 발행
    result_str = list(self.gray_history[0])[0]
    self.detection_pub.publish(String(result_str))

```

```

        rospy.loginfo(f"⭐ Black Object Stable Detection Published  

(Highest Priority): {result_str}")
        self.gray_history.clear()
        is_published = True

        # 🚨 [추가] 안정화된 감지에 실패했을 경우 터미널에 로그 출력
        if not is_published:
            rospy.logwarn(f"🚧 Black Object NOT DETECTED (History len:  

{len(self.gray_history)}).")

    return display_frame

if __name__ == '__main__':
    try:
        node = InverseGrayDetectionNode()
        rospy.spin()
    except rospy.ROSInterruptException:
        pass
    finally:
        cv2.destroyAllWindows()

```

empty\_composite\_cellbox\_detection\_node.py

```

#!/usr/bin/env python3
# -*- coding:utf-8 -*-

import rospy, cv2, numpy as np
from sensor_msgs.msg import Image
from cv_bridge import CvBridge
from std_msgs.msg import String

class DarkGridDetectionNode:
    def __init__(self):
        rospy.init_node('dark_grid_detection_node', anonymous=True)
        self.bridge = CvBridge()

        self.detection_pub = rospy.Publisher('/darkgrid_detection_result',
String, queue_size=1)
        self.image_sub = rospy.Subscriber("/camera/image_raw", Image,
self.image_callback)

        # ❌❌❌ 왜곡 보정 파라미터 (Camera Calibration 결과) ❌❌❌
        # !!! 경고: 이 값들은 예시입니다. 실제 카메라 캘리브레이션 값으로 반드시 변경해
야 합니다. !!!
        # Camera Matrix (K)
        self.camera_matrix = np.array([

```

```

[600.0, 0.0, 640.0],      # fx, 0, cx
[0.0, 600.0, 360.0],      # 0, fy, cy
[0.0, 0.0, 1.0]
], dtype=np.float64)

# Distortion Coefficients (D): k1, k2, p1, p2, k3...
self.dist_coeffs = np.array([
    0.1, -0.05, 0.001, 0.001, 0.0
], dtype=np.float64)

# === 감지 파라미터 ===
self.dark_intensity_thresh = 90
# 🚨 경고: 이 좌표들은 왜곡 보정된 이미지에 맞춰 다시 측정하고 변경해야 합니다.

⚠️
self.P1, self.P2, self.P3 = (105, 77), (547, 73), (105, 433)
self.cols, self.rows = 4, 3
# 로봇이 Place 가능한 셀만 활성화 셀로 정의하는 것이 좋습니다.
self.active_cells = {(1,1),(1,3),(2,2),(2,4),(3,1),(3,3)}
self.gray_history = []
rospy.loginfo("--- ❤️ Dark Grid Detection Node 초기화 완료. ---")

def image_callback(self, msg):
    try:
        frame = self.bridge.imgmsg_to_cv2(msg, "bgr8")

        # 1. 🚨 왜곡 보정 (Undistortion) 🚨
        processed_frame = frame

        # 파라미터가 유효한지 확인하고 왜곡 보정 수행
        if self.camera_matrix is not None and self.dist_coeffs is not
None:
            h, w = frame.shape[:2]

            # 최적의 새 카메라 행렬 계산
            new_camera_matrix, roi = cv2.getOptimalNewCameraMatrix(
                self.camera_matrix, self.dist_coeffs, (w, h), 1, (w, h)
            )

            # 왜곡 보정 적용
            undistorted_frame = cv2.undistort(frame, self.camera_matrix,
                                              self.dist_coeffs, None,
            new_camera_matrix)

            # 왜곡 보정 후 ROI(관심 영역) 자르기
            x, y, w_roi, h_roi = roi
            if w_roi > 0 and h_roi > 0:

```

```

        processed_frame = undistorted_frame[y:y+h_roi, x:x+w_roi]
    else:
        processed_frame = undistorted_frame

    # 2. Dark Grid 감지 실행 (보정된 이미지 사용)
    result_frame = self.dark_detect(processed_frame)
    cv2.imshow("Dark Grid Cell Detection", result_frame)
    cv2.waitKey(1)
except Exception as e:
    rospy.logerr(f"Dark Grid Detection Error: {e}")

def dark_detect(self, frame):
    # 왜곡 보정 후 이미지의 크기가 원본과 다를 수 있으므로 그레이 변환
    gray = cv2.cvtColor(frame, cv2.COLOR_BGR2GRAY)

    # --- 그리드 좌표 계산 로직 ---
    xs = np.linspace(self.P1[0], self.P2[0], self.cols+1)
    ys = np.linspace(self.P1[1], self.P3[1], self.rows+1)
    detected = set()

    for i in range(self.rows):
        for j in range(self.cols):
            r, c = i+1, j+1
            x1, x2 = int(xs[j]), int(xs[j+1])
            y1, y2 = int(ys[i]), int(ys[i+1])

            # 범위 체크
            if x1 < x2 and y1 < y2 and x1 >= 0 and y1 >= 0 and x2 <=
frame.shape[1] and y2 <= frame.shape[0]:
                cell_region = gray[y1:y2, x1:x2]

                if cell_region.size > 0:
                    # ↘ 핵심: 평균 밝기 계산
                    mean_intensity = np.mean(cell_region)
                else:
                    mean_intensity = 255 # 영역이 비었으면 밝은 것으로 간주

                if (r,c) in self.active_cells:
                    color = (0,255,0)
                    text = f"{mean_intensity:.0f}"

                    # ↘ 감지 로직: 평균 밝기가 임계값 이하일 때 (Dark Grid)
                    if mean_intensity < self.dark_intensity_thresh:
                        detected.add(f"{r}-{c}")
                        color = (0,0,255)
                        text = f"Detected ({mean_intensity:.0f})"

```

```

        cv2.rectangle(frame, (x1, y1), (x2, y2), color, 2)
        cx, cy = int((x1+x2)/2), int((y1+y2)/2)
        cv2.putText(frame, f"{r}-{c} {text}", (cx-60, cy),
                    cv2.FONT_HERSHEY_SIMPLEX, 0.5,
                    (255, 255, 255), 2)

    else:
        cv2.rectangle(frame, (x1, y1), (x2, y2), (80, 80, 80),
1)

# --- 안정화 로직 ---
self.gray_history.append(frozenset(detected))
if len(self.gray_history) > 3:
    self.gray_history.pop(0)

if (len(self.gray_history) == 3 and
    all(h == self.gray_history[0] for h in self.gray_history) and
    len(detected) > 0):

    # 🚨🚨🚨 수정된 핵심 로직: 감지된 셀 중 첫 번째 셀만 선택하여 발행 🚨🚨🚨
    stable_detected_set = self.gray_history[0]

if stable_detected_set:
    # 감지된 유효한 셀들(예: {"1-1", "2-2"})을 사전순으로 정렬하여 첫 번
째 셀만 선택
    # 이렇게 하면 컨트롤러가 예상하는 단일 키 형식(예: "1-1")이 발행됩니
다.
    result_str = sorted(list(stable_detected_set))[0]

    self.detection_pub.publish(String(result_str))
    rospy.loginfo(f"♥ Dark Grid Stable Detection Published:
{result_str}")

    self.gray_history.clear()
    # 🚨🚨🚨 수정 끝 🚨🚨🚨

return frame

def run(self):
    rospy.spin()

if __name__ == '__main__':
    try:
        node = DarkGridDetectionNode()
        node.run()
    except rospy.ROSInterruptException:

```

```
    pass
finally:
    cv2.destroyAllWindows()
```

filled\_cellbox\_detection\_node.py

```
#!/usr/bin/env python3
# -*- coding:utf-8 -*-

import rospy, cv2, numpy as np
from sensor_msgs.msg import Image
from cv_bridge import CvBridge
from std_msgs.msg import String # 실행할 메시지 타입

class GrayDetectionNode:
    def __init__(self):
        rospy.init_node('gray_detection_node', anonymous=True)
        self.bridge = CvBridge()
        # =====#
        # 🔔 토픽 이름
        # =====#
        self.detection_pub = rospy.Publisher('/gray_detection_result', String,
queue_size=1)
        self.image_sub = rospy.Subscriber("/camera/image_raw", Image,
self.image_callback)

        # === 그리드 설정 ===
        self.P1, self.P2, self.P3 = (105, 77), (547, 73), (105, 433)
        self.cols, self.rows = 4, 3
        # 🔔 활성 셀 정의 (순서는 우선순위와 동일): 1-1이 가장 높고, 3-3이 가장 낮습니다.
        self.active_cell_priority = ["1-1", "1-3", "2-2", "2-4", "3-1", "3-3"]
        self.active_cells = set((int(c.split('-')[0]), int(c.split('-')[1])))
for c in self.active_cell_priority)
        self.gray_history = [] # 안정화용

        # === 새로운 밝은 픽셀 감지 임계값 ===
        self.bright_intensity_thresh = 215 # RGB 채널의 최소값
        self.bright_pixel_ratio = 0.10      # 감지 최소 면적 비율 (10%)

    def image_callback(self, msg):
        try:
            frame = self.bridge.imgmsg_to_cv2(msg, "bgr8")
            result_frame = self.bright_area_detect(frame)
            cv2.imshow("Bright Area Grid Cell Detection", result_frame)
            cv2.waitKey(1)
```

```

        except Exception as e:
            rospy.logerr(f"Detection Error: {e}")

def bright_area_detect(self, frame):
    display_frame = frame.copy()

    xs = np.linspace(self.P1[0], self.P2[0], self.cols+1)
    ys = np.linspace(self.P1[1], self.P3[1], self.rows+1)
    detected_cell_names = set() # 감지된 셀 이름 (예: "1-1")

    # 1. 셀 별 밝은 영역 감지
    for i in range(self.rows):
        for j in range(self.cols):
            r, c = i+1, j+1
            cell_name = f"{r}-{c}"
            x1, x2 = int(xs[j]), int(xs[j+1])
            y1, y2 = int(ys[i]), int(ys[i+1])

            if y2 <= y1 or x2 <= x1: continue

            cell_roi = frame[y1:y2, x1:x2]
            cell_area = cell_roi.shape[0] * cell_roi.shape[1]

            # B, G, R 채널 값이 모두 215 이상인 픽셀 찾기
            bright_mask = np.all(cell_roi >= self.bright_intensity_thresh,
axis=2)
            bright_pixel_count = np.sum(bright_mask)
            current_ratio = bright_pixel_count / cell_area if cell_area >
0 else 0

            color = (80,80,80) # 기본 회색 (비활성)
            text = f"{r}-{c} ({current_ratio:.2f})"

            if (r,c) in self.active_cells:
                color = (0,255,0) # 초록색 (활성 대기)

            if current_ratio >= self.bright_pixel_ratio:
                detected_cell_names.add(cell_name) # 감지된 셀 이름 저장
                color = (255,165,0) # 주황색 (감지됨)
                text = f"DETECTED ({current_ratio:.2f})"

            # 활성 셀 테두리 및 텍스트 표시
            cv2.rectangle(display_frame, (x1, y1), (x2, y2), color, 2)
            cx, cy = int((x1+x2)/2), int((y1+y2)/2)
            cv2.putText(display_frame, text, (cx - 60, cy),
cv2.FONT_HERSHEY_SIMPLEX, 0.5, (255,255,255),

```

2)

```
        else:
            # 비활성 셀 태두리 표시
            cv2.rectangle(display_frame, (x1, y1), (x2, y2), color, 1)

    # 2. 5프레임 안정화 로직
    self.gray_history.append(frozenset(detected_cell_names))
    if len(self.gray_history) > 5: self.gray_history.pop(0)

    # 5프레임이 채워지고, 모든 프레임에서 같은 결과가 나왔을 때
    if len(self.gray_history) == 5 and all(h == self.gray_history[0] for h
in self.gray_history):

        stable_detected_set = self.gray_history[0]
        result_str = ""

        if len(stable_detected_set) > 0:
            # ↗ 3. 감지된 셀 목록에서 우선순위가 가장 높은 셀 하나를 선택
            highest_priority_cell = ""
            for cell_name in self.active_cell_priority:
                if cell_name in stable_detected_set:
                    highest_priority_cell = cell_name
                    break

            if highest_priority_cell:
                #💡 우선순위가 높은 셀 하나만 발행
                result_str = highest_priority_cell
                self.detection_pub.publish(String(result_str))
                rospy.loginfo(f"🌟 Bright Area STABLE PRIORITY Detection
Published: {result_str}")

            else:
                # (이 경우는 이론상 발생하기 어려움: stable_detected_set이 비어
                있지 않은데 우선순위 목록에 없음)
                result_str = ""
                self.detection_pub.publish(String(result_str))
                rospy.logwarn(f"--- ⚠ Bright Area STABLE: No active
priority cell found ({result_str}) ---")

        else:
            # 🚨 아무것도 감지되지 않았을 경우: 빈 문자열 발행
            result_str = ""
            self.detection_pub.publish(String(result_str))
            rospy.loginfo(f"--- ⚠ Bright Area STABLE Nothing Detected
({result_str}) ---")
```

```

        # 발행 후, 히스토리를 초기화하여 다음 새로운 감지를 대기 (중복 발행 방지)
        self.gray_history.clear()

    return display_frame # 플롯된 프레임을 반환

if __name__ == '__main__':
    try:
        node = GrayDetectionNode()
        rospy.spin()
    except rospy.ROSInterruptException:
        pass
    finally:
        cv2.destroyAllWindows()

```

`filled_composite_detection_node.py`

```

#!/usr/bin/env python3
# -*- coding:utf-8 -*-

import rospy, cv2, numpy as np
from sensor_msgs.msg import Image
from cv_bridge import CvBridge
from std_msgs.msg import String

class AssemblyGridDetectionNode:
    def __init__(self):
        rospy.init_node('assembly_grid_detection_node', anonymous=True)
        self.bridge = CvBridge()

        # =====#
        # 🔔 퍼블리셔 및 서브스크라이버
        # =====#
        self.detection_pub = rospy.Publisher('/inverse_grid_detection_result',
String, queue_size=1)
        self.image_sub = rospy.Subscriber("/camera/image_raw", Image,
self.image_callback)

        # === 그리드 설정 ===
        self.P1, self.P2, self.P3 = (105, 77), (547, 73), (105, 433)
        self.cols, self.rows = 4, 3
        self.active_cell_priority = ["1-1", "1-3", "2-2", "2-4", "3-1", "3-3"]
        self.active_cells = set((int(c.split('-')[0]), int(c.split('-')[1])))
for c in self.active_cell_priority:
    self.gray_history = []

        # === 주황색 감지 파라미터 ===

```

```

# B, G, R 채널 기준 (0~255)
self.ORANGE_B_MIN, self.ORANGE_B_MAX = 65, 185
self.ORANGE_G_MIN, self.ORANGE_G_MAX = 110, 220
self.ORANGE_R_MIN, self.ORANGE_R_MAX = 220, 255
self.orange_pixel_ratio = 0.05 # 셀 내 주황색이 5% 이상일 때 감지

# -----
def image_callback(self, msg):
    try:
        frame = self.bridge.imgmsg_to_cv2(msg, "bgr8")
        result_frame = self.orange_area_detect(frame)
        cv2.imshow("Assembly Grid Detection (Orange Area)", result_frame)
        cv2.waitKey(1)
    except Exception as e:
        rospy.logerr(f"Detection Error: {e}")

# -----
def orange_area_detect(self, frame):
    display_frame = frame.copy()

    xs = np.linspace(self.P1[0], self.P2[0], self.cols+1)
    ys = np.linspace(self.P1[1], self.P3[1], self.rows+1)
    detected_cell_names = set()

    # ❶ 셀별 주황색 영역 감지
    for i in range(self.rows):
        for j in range(self.cols):
            r, c = i+1, j+1
            cell_name = f"{r}-{c}"
            x1, x2 = int(xs[j]), int(xs[j+1])
            y1, y2 = int(ys[i]), int(ys[i+1])

            if y2 <= y1 or x2 <= x1:
                continue

            cell_roi = frame[y1:y2, x1:x2]
            cell_area = cell_roi.shape[0] * cell_roi.shape[1]

            # 주황색 범위 마스크 (BGR)
            b_min, b_max = self.ORANGE_B_MIN, self.ORANGE_B_MAX
            g_min, g_max = self.ORANGE_G_MIN, self.ORANGE_G_MAX
            r_min, r_max = self.ORANGE_R_MIN, self.ORANGE_R_MAX

            orange_mask = cv2.inRange(cell_roi, (b_min, g_min, r_min),
(b_max, g_max, r_max))
            orange_count = np.sum(orange_mask > 0)


```

```

        current_ratio = orange_count / cell_area if cell_area > 0 else
0

        color = (80,80,80)
        text = f"{r}-{c} ({current_ratio:.2f})"

        if (r, c) in self.active_cells:
            color = (0,255,0)

        if current_ratio >= self.orange_pixel_ratio:
            detected_cell_names.add(cell_name)
            color = (0,140,255) # ● 주황색 감지시 색상 강조
            text = f"DETECTED ({current_ratio:.2f})"

            cv2.rectangle(display_frame, (x1, y1), (x2, y2), color, 2)
            cx, cy = int((x1+x2)/2), int((y1+y2)/2)
            cv2.putText(display_frame, text, (cx - 60, cy),
                        cv2.FONT_HERSHEY_SIMPLEX, 0.5, (255,255,255),
2)
        else:
            cv2.rectangle(display_frame, (x1, y1), (x2, y2), color, 1)

# ❷ 3프레임 안정화 로직 (EMA처럼 프레임별 안정화)
self.gray_history.append(frozenset(detected_cell_names))
if len(self.gray_history) > 3:
    self.gray_history.pop(0)

if len(self.gray_history) == 3 and all(h == self.gray_history[0] for h
in self.gray_history):
    stable_detected_set = self.gray_history[0]
    result_str = ""

    if len(stable_detected_set) > 0:
        highest_priority_cell = ""
        for cell_name in self.active_cell_priority:
            if cell_name in stable_detected_set:
                highest_priority_cell = cell_name
                break

        if highest_priority_cell:
            result_str = highest_priority_cell
            self.detection_pub.publish(String(result_str))
            rospy.loginfo(f"⭐ Assembly Grid STABLE PRIORITY Detection
Published: {result_str}")
        else:
            result_str = ""

```

```

        self.detection_pub.publish(String(result_str))
        rospy.logwarn(f"⚠️ No active priority cell found
({result_str})")
    else:
        result_str = ""
        self.detection_pub.publish(String(result_str))
        rospy.loginfo(f"⚠️ Nothing Detected ({result_str})")

    self.gray_history.clear()

    return display_frame

# -----
if __name__ == '__main__':
    try:
        node = AssemblyGridDetectionNode()
        rospy.spin()
    except rospy.ROSInterruptException:
        pass
    finally:
        cv2.destroyAllWindows()

```

move\_group\_python\_interface.py

```

#!/usr/bin/env python3

import sys
import rospy
import moveit_commander
import moveit_msgs
import geometry_msgs

import tf
import copy
import math

from tf.transformations import *
from geometry_msgs.msg import Quaternion
from moveit_commander.conversions import pose_to_list
from math import pi, tau, dist, fabs, cos

from ur_msgs.srv import SetIO, SetIOPRequest
from ur_python.msg import robot_state

```

```

def all_close(goal, actual, tolerance):
    """Compare poses or lists within a tolerance."""
    if type(goal) is list:
        for index in range(len(goal)):
            if abs(actual[index] - goal[index]) > tolerance:
                return False

    elif type(goal) is geometry_msgs.msg.PoseStamped:
        return all_close(goal.pose, actual.pose, tolerance)

    elif type(goal) is geometry_msgs.msg.Pose:
        x0, y0, z0, qx0, qy0, qz0, qw0 = pose_to_list(actual)
        x1, y1, z1, qx1, qy1, qz1, qw1 = pose_to_list(goal)
        d = dist((x1, y1, z1), (x0, y0, z0))
        cos_phi_half = fabs(qx0*qx1 + qy0*qy1 + qz0*qz1 + qw0*qw1)
        return d <= tolerance and cos_phi_half >= cos(tolerance / 2.0)

    return True


class MoveGroupPythonInterface(object):
    """MoveGroupPythonInterface"""

    def ensure_minimal_rotation(self, current_quat, target_quat):
        """Quaternion 부호 반전으로 인한 180° jump 방지"""
        dot = sum(c * t for c, t in zip(current_quat, target_quat))
        if dot < 0.0:
            target_quat = [-t for t in target_quat]
        return target_quat

    def __init__(self, real="real", gripper="gripper"):
        super(MoveGroupPythonInterface, self).__init__()

        moveit_commander.roscpp_initialize(sys.argv)
        rospy.init_node("move_group_python_interface", anonymous=True)

        self.msg_robot_state = robot_state()
        self.pub_robot_state = rospy.Publisher("robot_state", robot_state,
                                              queue_size=10)

        self.robot = moveit_commander.RobotCommander()
        self.group_name = "manipulator"
        self.manipulator =
moveit_commander.move_group.MoveGroupCommander(self.group_name)

        if real == "real":

```

```

        self.io_handler =
rospy.ServiceProxy('/ur_hardware_interface/set_io', SetIO)
        self.gripper = SetIOResponse()
        self.gripper_init()

        self.planning_frame = self.manipulator.get_planning_frame()
print("===== Planning frame: %s" % self.planning_frame)
self.eef_link = self.manipulator.get_end_effector_link()
print("===== End effector link: %s" % self.eef_link)
self.group_names = self.robot.get_group_names()
print("===== Available Planning Groups:",
self.robot.get_group_names())
print("===== Printing robot state")
print(self.robot.get_current_state())
print("")
rospy.sleep(1)

def move_to_standby(self):
    print("===== Go to 'stand_by' pose")
    self.go_to_joint_abs([tau/4, -tau/4, tau/4, -tau/4, -tau/4, 0.0])
    self.manipulator.go(wait=True)
    self.manipulator.stop()
    print("===== Printing robot state")
    print(self.robot.get_current_state())

def gripper_init(self):
    self.gripper.fun = 1
    self.gripper.pin = 1
    self.grip_off()

def grip_on(self):
    self.msg_robot_state.move = 1
    self.pub_robot_state.publish(self.msg_robot_state)
    self.gripper.state = 1
    self.io_handler.call(self.gripper)
    rospy.sleep(1.5)
    self.msg_robot_state.move = 0
    self.pub_robot_state.publish(self.msg_robot_state)

def grip_off(self):
    self.msg_robot_state.move = 1
    self.pub_robot_state.publish(self.msg_robot_state)
    self.gripper.state = 0
    self.io_handler.call(self.gripper)
    rospy.sleep(1.5)
    self.msg_robot_state.move = 0

```

```

        self.pub_robot_state.publish(self.msg_robot_state)

    def go_to_joint_abs(self, target_joints):
        current_joint = self.manipulator.get_current_joint_values()
        target_joint = copy.deepcopy(current_joint)
        for i in range(6):
            target_joint[i] = target_joints[i]

        self.msg_robot_state.move = 1
        self.pub_robot_state.publish(self.msg_robot_state)
        self.manipulator.go(target_joint, wait=True)
        self.manipulator.stop()
        self.msg_robot_state.move = 0
        self.pub_robot_state.publish(self.msg_robot_state)
        return all_close(target_joint,
self.manipulator.get_current_joint_values(), 0.005)

    def go_to_joint_rel(self, relative_pos):
        current_joint = self.manipulator.get_current_joint_values()
        target_joint = [cj + r for cj, r in zip(current_joint, relative_pos)]
        self.msg_robot_state.move = 1
        self.pub_robot_state.publish(self.msg_robot_state)
        self.manipulator.go(target_joint, wait=True)
        self.manipulator.stop()
        self.msg_robot_state.move = 0
        self.pub_robot_state.publish(self.msg_robot_state)
        return all_close(target_joint,
self.manipulator.get_current_joint_values(), 0.005)

    def go_to_pose_abs(self, absolute_xyz, absolute_rpy):
        current_pose = self.manipulator.get_current_pose().pose
        target_pose = copy.deepcopy(current_pose)
        target_pose.position.x = absolute_xyz[0]
        target_pose.position.y = absolute_xyz[1]
        target_pose.position.z = absolute_xyz[2]
        target_quat = quaternion_from_euler(*absolute_rpy)
        target_pose.orientation = Quaternion(*target_quat)
        self.manipulator.set_pose_target(target_pose)
        self.msg_robot_state.move = 1
        self.pub_robot_state.publish(self.msg_robot_state)
        self.manipulator.go(wait=True)
        self.manipulator.stop()
        self.manipulator.clear_pose_targets()
        self.msg_robot_state.move = 0
        self.pub_robot_state.publish(self.msg_robot_state)
        return all_close(target_pose,

```

```

self.manipulator.get_current_pose().pose, 0.005)

def go_to_pose_rel(self, relative_xyz, relative_rpy, max_retry=3):
    """
    Move the manipulator to a relative pose (position + orientation)
    with retry and stability.
    relative_xyz: [dx, dy, dz] in meters
    relative_rpy: [dR, dP, dY] in radians
    """

    # ① 현재 pose 읽기
    current_pose = self.manipulator.get_current_pose().pose
    target_pose = copy.deepcopy(current_pose)

    # ② 상대 이동 적용
    target_pose.position.x += relative_xyz[0]
    target_pose.position.y += relative_xyz[1]
    target_pose.position.z += relative_xyz[2]

    # ③ 회전 (쿼터니언 누적 방식)
    current_quat = [
        current_pose.orientation.x,
        current_pose.orientation.y,
        current_pose.orientation.z,
        current_pose.orientation.w,
    ]
    rel_quat = quaternion_from_euler(*relative_rpy)

    # 누적 회전 (상대 회전 * 현재 회전)
    target_quat = quaternion_multiply(rel_quat, current_quat)

    # minimal rotation 보정
    dot = sum(c * t for c, t in zip(current_quat, target_quat))
    if dot < 0.0:
        target_quat = [-q for q in target_quat]
        rospy.logwarn("🌀 Quaternion flipped for minimal rotation")

    target_pose.orientation = Quaternion(*target_quat)

    # 로그 출력
    rospy.loginfo(f"👉 Δxyz = {relative_xyz}, Δrpy(deg) = "
{[round(x*180/pi,3) for x in relative_rpy]}")
    rospy.loginfo(f"📍 From z={current_pose.position.z:.3f} → To z={target_pose.position.z:.3f}")

    # ④ Cartesian Path 기반 경로 계획 및 실행 (재시도)

```

```

waypoints = [target_pose]
success = False

for attempt in range(1, max_retry + 1):
    (plan, fraction) = self.manipulator.compute_cartesian_path(
        waypoints,
        0.002,      # eef_step (단위: m)
        True         # jump_threshold
    )
    rospy.loginfo(f"⌚ Attempt {attempt}: Cartesian path fraction={fraction:.3f}")

    if fraction > 0.9:
        rospy.loginfo(f"✅ Cartesian path success on attempt {attempt}")
        self.msg_robot_state.move = 1
        self.pub_robot_state.publish(self.msg_robot_state)

        self.manipulator.execute(plan, wait=True)
        self.manipulator.stop()

        self.msg_robot_state.move = 0
        self.pub_robot_state.publish(self.msg_robot_state)
        success = True
        break
    else:
        rospy.logwarn(f"⚠️ Path incomplete (fraction={fraction:.3f}), retrying...")
        rospy.sleep(0.5)

# ⑤ 실패 시 안전 중단
if not success:
    rospy.logerr("✖️ Cartesian path failed after retries - skipping safely.")
    return False

# ⑥ 최종 자세 비교
current_pose = self.manipulator.get_current_pose().pose
if not all_close(target_pose, current_pose, 0.003):
    rospy.logwarn("⚠️ Final pose deviation detected, check accuracy.")

return True

```

main.py

```

#!/usr/bin/env python3
# -*- coding:utf-8 -*-

import sys
import rospy
import math
import numpy as np
from math import pi
import time as pytime
from time import time
import serial

from move_group_python_interface import MoveGroupPythonInterface
from geometry_msgs.msg import Point
from std_msgs.msg import String
from tf.transformations import euler_from_quaternion, quaternion_from_euler
from geometry_msgs.msg import Pose, Quaternion

# -----
# 간단 토픽 래치
# -----

class TopicLatch:
    def __init__(self, ttl=3.0):
        self.ttl = ttl
        self.data = None
        self.stamp = 0.0
    def update(self, msg):
        self.data = msg
        self.stamp = time()
    def alive(self):
        return (time() - self.stamp) <= self.ttl
    def get(self, default=None):
        return self.data if self.alive() else default


class AsmFsmNode:
    def __init__(self):
        # rospy.init_node("asm_fsm_node", anonymous=True)
        self.ur5e = MoveGroupPythonInterface(real="real", gripper="gripper")

        # ✅ 초기 RPY 부호 교정 불필요
        rospy.loginfo("MoveGroupPythonInterface initialized with stabilized
RPY logic ( $\pm 0.1^\circ$  limit + minimal rotation).")

# ----- 아두이노 시리얼 연결 -----

```

```

try:
    self.arduino = serial.Serial()
    self.arduino.port = '/dev/ttyACM0'
    self.arduino.baudrate = 9600
    self.arduino.timeout = 1

    # ★★★ reset 방지 (포트 오픈 전에 해야 함)
    self.arduino.dtr = False
    self.arduino.rts = False

    self.arduino.open()      # 이제 UNO Reset 절대 안 됨

    rospy.loginfo("🔌 Arduino Serial Connected (/dev/ttyACM) without
reset")
except Exception as e:
    rospy.logwarn(f"⚠️ Arduino Serial Connection Failed: {e}")
    self.arduino = None


# 이하 원래 코드
self.GRIP_HOLD = 2
self.D2R = pi/180.0
self.prev_orange = None
self.ema_alpha = 0.35
self.ema_stable_thresh_mm = 10.0 # 1mm 이하 변화 시 안정화 간주
self.ema_min_frames = 2          # 최소 4프레임 유지 필요
self.ema_stable_count = 0


# ---- 토픽 래치 ----
self.red_result      = TopicLatch(ttl=2.0)    # /red_detection/result
(Point)
    self.orange_result = TopicLatch(ttl=2.0)    #
/orange_detection/result (Point)
    self.darkgrid_result = TopicLatch(ttl=2.0)   #
/darkgrid_detection_result (String)
    self.gray_result    = TopicLatch(ttl=2.0)    #
/gray_detection_result (String)
    self.inv_gray_result = TopicLatch(ttl=2.0)   #
/inverse_gray_detection_result (String)
    self.inv_grid_result = TopicLatch(ttl=2.0)   #
/inverse_grid_detection_result (String)
    self.fallback_circle = TopicLatch(ttl=2.0)   #
/fallback_circle/result (Point)
    self.grid1_fallback = TopicLatch(ttl=2.0)   #
/grid1_fallback/result (Point)

```

```

        self.grid2Fallback = TopicLatch(ttl=2.0) #
/grid2Fallback/result (Point)

# ---- 구독 ----
rospy.Subscriber("/red_detection/result", Point, self.cb_red)
rospy.Subscriber("/orange_detection/result", Point, self.cb_orange)
rospy.Subscriber("/darkgrid_detection_result", String,
self.cb_darkgrid)
rospy.Subscriber("/gray_detection_result", String, self.cb_gray)
rospy.Subscriber("/inverse_gray_detection_result", String,
self.cb_inv_gray)
rospy.Subscriber("/inverse_grid_detection_result", String,
self.cb_inv_grid)
rospy.Subscriber("/fallback_circle/result", Point,
self.cb_fallback_circle)
rospy.Subscriber("/grid1Fallback/result", Point,
self.cb_grid1Fallback)
rospy.Subscriber("/grid2Fallback/result", Point,
self.cb_grid2Fallback)

# ---- 조인트 (deg) ----
self.ASM_OBS_START_JOINTS      = [298.62, -102.48, 119.54,
-106.94, -89.63, -61.17]
self.RED_PLACE_POSE_1_JOINTS   = [308.07, -92.37, 110.96,
-108.60, -89.66, -51.81]
self.ASM_OBS_GRID_JOINTS       = [243.53, -74.39, 66.28,
-82.02, -90.00, -116.50]
self.ASM_RED_DETECT_TRIGGER_JOINTS = [272.92, -118.99, 129.53,
-100.31, -89.71, -86.91]
self.OBS_GRID_JOINTS          = [267.86, -74.47, 66.36,
-81.72, -90.07, -92.25]
self.RED_PLACE_POSE_2_JOINTS   = [287.35, -103.92, 128.08,
-108.26, -88.37, -67.33]

# === 새로 지정된 Grip-OFF 경유 좌표들 ===
# A 경로 (state 1/101/201/301에서 사용)
self.OFF_A1 = [308.44, -89.11, 116.87, -117.93, -89.93, -51.93]
self.OFF_A2 = [308.44, -90.27, 115.27, -115.26, -89.92, -51.96]
# B 경로 (state 3/103에서 사용)
self.OFF_B1 = [288.55, -106.54, 133.50, -116.53, -89.89, -71.82]
self.OFF_B2 = [288.58, -108.29, 130.91, -112.21, -89.95, -71.79]
# state 6/106 이후 Grip OFF 위치 동일 (B2)
self.GRIP_OFF_B2 = self.OFF_B2
# state 5/105 이후 Grip OFF 위치 (A2)

```

```

    self.GRIP_OFF_A2 = self.OFF_A2

    # ---- 토픽별 포즈 딕셔너리 (새 좌표 반영) ----
    # /gray_detection_result → 조립용 픽 (그레이드 셀)
    self.ASM_GRID_POSES = {
        "1-1": {"start": [273.89, -84.60, 93.19, -98.45, -90.06, -86.15]}, 
        "1-3": {"start": [273.15, -67.90, 72.17, -94.09, -90.09, -86.80]}, 
        "2-2": {"start": [266.95, -78.48, 86.06, -97.27, -90.08, -93.06]}, 
        "2-4": {"start": [267.49, -60.76, 61.65, -90.54, -90.09, -92.57]}, 
        "3-1": {"start": [259.17, -88.10, 96.91, -98.58, -90.15, -100.80]}, 
        "3-3": {"start": [261.31, -70.86, 76.25, -95.19, -90.08, -98.61]}, 
    }

    self.DIS_GRID_POSES = {
        "1-1": {"start": [245.12, -87.75, 96.56, -98.68, -90.19, -114.91]}, 
        "1-3": {"start": [249.95, -70.67, 76.04, -95.30, -90.18, -110.01]}, 
        "2-2": {"start": [241.81, -77.35, 84.69, -97.10, -90.22, -118.16]}, 
        "2-4": {"start": [246.63, -59.80, 60.15, -90.00, -90.18, -113.43]}, 
        "3-1": {"start": [232.74, -82.41, 90.72, -98.17, -90.27, -127.19]}, 
        "3-3": {"start": [239.69, -65.02, 68.04, -92.84, -90.11, -120.19]}, 
    }

    # /darkgrid_detection_result → 빈 그리드 픽(조립 전)
    self.DARKGRID_POSES = {
        "1-1": {"start": [254.13, -89.30, 97.65, -98.06, -90.11, -107.77], "pick": [254.10, -86.06, 107.90, -111.54, -90.01, -107.82]}, 
        "1-3": {"start": [257.45, -71.90, 77.20, -95.00, -89.84, -102.30], "pick": [257.44, -69.45, 87.32, -107.60, -89.84, -102.31]}, 
        "2-2": {"start": [249.57, -80.41, 85.10, -94.64, -89.90, -110.18], "pick": [249.40, -77.17, 98.43, -111.19, -89.92, -110.35]}, 
        "2-4": {"start": [253.53, -62.42, 60.22, -87.84, -89.81, -106.28], "pick": [253.18, -60.95, 74.89, -103.90, -89.83, -106.34]}, 
        "3-1": {"start": [240.32, -86.43, 93.50, -96.67, -89.95, -119.46], "pick": [240.31, -83.03, 104.88, -111.49, -89.94, -119.43]}, 
        "3-3": {"start": [246.35, -69.47, 70.17, -90.42, -89.79, -114.60], "pick": [245.97, -67.14, 83.81, -106.32, -89.81, -113.90]}, 
    }

    # /inverse_gray_detection_result → fallback 상황의 회색 셀 픽
    self._FALLBACK_POSES = {
        "1-1": {"start": [282.64, -80.76, 88.80, -97.86, -89.85, -77.24], "pick": 
    }

```

```

[282.38,-78.32,97.93,-109.45,-89.81,-77.47}],  

    "1-3": {"start": [280.40,-65.60,69.21,-94.72,-90.02,-79.52], "pick":  

[280.11,-63.99,78.71,-105.82,-90.02,-79.77]},  

    "2-2": {"start": [275.13,-77.00,84.56,-98.48,-89.79,-84.87], "pick":  

[275.01,-74.55,94.24,-110.57,-89.77,-84.99]},  

    "2-4": {"start": [274.12,-59.33,59.69,-91.05,-89.66,-85.73], "pick":  

[273.92,-58.49,70.86,-103.01,-89.54,-85.82]},  

    "3-1": {"start": [268.33,-87.22,96.27,-99.81,-89.82,-91.56], "pick":  

[268.05,-84.59,106.33,-112.47,-89.92,-91.80]},  

    "3-3": {"start": [268.64,-70.52,76.07,-96.50,-89.75,-91.21], "pick":  

[268.18,-68.58,86.08,-108.45,-89.77,-91.65]},  

}  

# /inverse_grid_detection_result → 분해공정 픽  

self.INVERSE_POSES = {  

    "1-1": {"start":  

[253.74,-89.33,99.87,-100.37,-89.86,-108.12], "pick":  

[253.73,-84.97,110.70,-115.54,-89.85,-108.10]},  

    "1-3": {"start": [257.34,-71.88,79.42,-97.27,-89.95,-102.36], "pick":  

[257.34,-68.50,89.85,-111.02,-89.93,-102.33]},  

    "2-2": {"start":  

[249.35,-79.85,90.38,-100.50,-90.06,-110.40], "pick":  

[249.33,-75.75,100.63,-114.85,-89.97,-110.45]},  

    "2-4": {"start": [253.09,-62.55,66.25,-93.71,-89.88,-106.70], "pick":  

[253.09,-59.97,77.20,-107.24,-89.83,-106.77]},  

    "3-1": {"start":  

[240.19,-85.99,96.76,-100.47,-89.94,-119.65], "pick":  

[240.22,-81.69,107.36,-115.48,-90.01,-119.60]},  

    "3-3": {"start": [245.91,-69.16,75.62,-96.42,-89.90,-114.03], "pick":  

[245.91,-65.99,86.15,-110.08,-89.90,-113.99]},  

}  

# ---- fallback 안정화 파라미터 ----  

self.fallback_stable = {"x": None, "y": None, "t": 0.0}  

self.FALLBACK_STABLE_TIME = 2.0          # 2초 유지  

self.FALLBACK_TOLERANCE = 20.0           # ±20 px  

self.FALLBACK_MATCH_TOLERANCE = 25.0     # red/orange와 ±25 px  

# ---- 초기 상태 ----  

self.state = 1  

rospy.loginfo("💬 ASM FSM Node Ready. Start at state 1.")

def open_stopper(self):  

    rospy.logerr(">>> open_stopper() CALLED NOW <<<")
```

```

if not self.arduino:
    rospy.logwarn("Arduino not connected")
    return

# 1) Arduino auto-reset 방지 (UNO)
try:
    self.arduino.setDTR(False)
    self.arduino.setRTS(False)
except:
    pass

# 2) 입력 버퍼 비우기
self.arduino.reset_input_buffer()

# 3) 명령 즉시 보내기
self.arduino.write(b'c\n')
self.arduino.flush()

rospy.loginfo("[WRITE] c")

# 4) Arduino 응답 빠르게 읽기 (0.3초) → pytime 사용! (충돌 방지)
end = pytime.time() + 0.3
while pytime.time() < end:
    if self.arduino.in_waiting:
        line = self.arduino.readline().decode(errors='ignore').strip()
        rospy.loginfo(f"[ARDUINO] {line}")

# ----- 콜백 -----
def cb_red(self, msg: Point): self.red_result.update(msg)
def cb_orange(self, msg: Point): self.orange_result.update(msg)
def cb_darkgrid(self, msg: String): self.darkgrid_result.update(msg)
def cb_gray(self, msg: String): self.gray_result.update(msg)
def cb_inv_gray(self, msg: String): self.inv_gray_result.update(msg)
def cb_inv_grid(self, msg: String): self.inv_grid_result.update(msg)
def cb_fallback_circle(self, msg: Point): self.fallback_circle.update(msg)
def cb_grid1_fallback(self, msg: Point): self.grid1_fallback.update(msg)
def cb_grid2_fallback(self, msg: Point): self.grid2_fallback.update(msg)

# ----- 헬퍼 -----
def jdeg(self, arr_deg):
    return [x*self.D2R for x in arr_deg]

```

```

def goJ(self, arr_deg, label=""):
    if label: rospy.loginfo(f"➡ MoveJ: {label}")
    ok = self.ur5e.go_to_joint_abs(self.jdeg(arr_deg))
    rospy.sleep(1.5)
    return ok

def wait_until_rpy_sign_ok(self, tol_check_rate=0.5):
    while not rospy.is_shutdown():
        try:
            # 현재 pose 읽기
            pose = self.ur5e.manipulator.get_current_pose().pose
            q = pose.orientation
            roll, pitch, yaw = np.degrees(euler_from_quaternion([q.x, q.y,
q.z, q.w]))

            # 부호 확인
            roll_ok = roll < 0
            pitch_ok = pitch > 0
            yaw_ok = yaw > 0

            if roll_ok and pitch_ok and yaw_ok:
                rospy.loginfo(f"✅ RPY OK: [R={roll:.3f}, P={pitch:.3f},"
Y={yaw:.3f}]")
                break
            else:
                rospy.logwarn(
                    f"⚠️ RPY sign mismatch! [R={roll:.3f}, P={pitch:.3f},"
Y={yaw:.3f}] → waiting...")
        except Exception as e:
            rospy.logwarn(f"⚠️ Failed to read RPY: {e}")

        rospy.sleep(tol_check_rate)

# ✅ 감지 유효 자세 확인 (OBS1 or OBS2)
def valid_pose_for_detection(self, tol_deg=1.0):
    """
    현재 UR5e 조인트가 감지 가능한 관찰 자세(OBS1/OBS2)인지 확인.
    tol_deg: 허용 오차 (deg)
    """
    try:
        # 현재 UR5e 조인트 읽기 (deg 변환)
        current_joints = [x / self.D2R for x in
self.ur5e.manipulator.get_current_joint_values()]

```

```

        except Exception as e:
            rospy.logwarn(f"⚠️ Cannot read current joint state: {e}")
            return False

    def is_close(target):
        return all(abs(a - b) <= tol_deg for a, b in zip(current_joints,
target))

        # ✅ OBS1 또는 OBS2 근처에 있을 때만 감지 허용
    valid = (
        is_close(self.ASM_OBS_START_JOINTS) or
        is_close(self.ASM_RED_DETECT_TRIGGER_JOINTS)
    )

    if not valid:
        rospy.loginfo("🚫 Detection ignored (not in OBS1 or OBS2 pose)")
    else:
        rospy.loginfo("✅ Valid detection pose confirmed.")
    return valid

def grip_on_6s(self):
    self.ur5e.grip_on()
    rospy.sleep(max(0.0, self.GRIP_HOLD - 1.5))

def grip_off_6s(self):
    self.ur5e.grip_off()
    rospy.sleep(max(0.0, self.GRIP_HOLD - 1.5))

def point_detected(self, latch: TopicLatch):
    # ✅ OBS1 또는 OBS2에서만 감지 유효
    if not self.valid_pose_for_detection():
        return False
    msg = latch.get()
    return (msg is not None) and (getattr(msg, "x", 0.0) != 0.0)

def choose_cell_from_string(self, s):
    if not s: return None
    txt = s.strip()
    if "," in txt: txt = txt.split(",")[0].strip()
    if " " in txt: txt = txt.split()[0].strip()
    return txt

def pick_cycle(self, pose_dict, cell_key, grip_mode="off"):
    if not cell_key or cell_key not in pose_dict:

```

```

        rospy.logwarn("⚠️ invalid grid key: {cell_key}")
        return False
    p = pose_dict[cell_key]
    ok = self.goJ(p["start"], f"{cell_key} start")
    ok &= self.goJ(p["pick"], f"{cell_key} pick")
    if grip_mode == "on": self.grip_on_6s()
    else: self.grip_off_6s()
    ok &= self.goJ(p["start"], f"{cell_key} back")
    return ok

# ----- fallback 안정 감지 (±20px/2s + red/orange 매칭 ±25px) -----
# ----- fallback 안정 감지 (±20px/2s + red/orange 매칭 ±25px) -----
def fallback_stable_detected(self):
    if not self.fallback_circle.alive():
        rospy.loginfo("⚠️ No active /fallback_circle/result messages.")
        self.fallback_stable["x"] = None
        return False

    msg_fb = self.fallback_circle.get()
    msg_red = self.red_result.get()
    msg_orange = self.orange_result.get()
    if msg_fb is None:
        rospy.loginfo("⚠️ fallback_circle message is None.")
        return False

    # ✅ (0, 0, 0) 퍼블리시 필터링
    if msg_fb.x == 0.0 and msg_fb.y == 0.0 and msg_fb.z == 0.0:
        rospy.logdebug("⚠️ fallback_circle published (0,0,0) → skip.")
        self.fallback_stable["x"] = None
        return False

    x, y = msg_fb.x, msg_fb.y
    now = time()
    ...

    # ◆ ③ 첫 감지 → 기준 좌표 등록
    if self.fallback_stable["x"] is None:
        self.fallback_stable = {"x": x, "y": y, "t": now}
        return False

    dx = abs(x - self.fallback_stable["x"])
    dy = abs(y - self.fallback_stable["y"])

    # ◆ ④ ±20px 이내 이동 유지 확인
    stable_ok = (dx <= self.FALLBACK_TOLERANCE and dy <=

```

```

self.FALLBACK_TOLERANCE)
    time_ok = (now - self.fallback_stable["t"] >=
self.FALLBACK_STABLE_TIME)

        # ◆ 5 좌표가 새로 벗어났으면 기준 갱신
        if not stable_ok:
            self.fallback_stable = {"x": x, "y": y, "t": now}
            return False

        # ◆ 6 red/orange 감지와 ±25px 매칭 여부 확인
        def close_enough(msg_ref):
            if msg_ref is None: return False
            return (abs(x - msg_ref.x) <= self.FALLBACK_MATCH_TOLERANCE and
                    abs(y - msg_ref.y) <= self.FALLBACK_MATCH_TOLERANCE)

        match_ok = close_enough(msg_red) or close_enough(msg_orange)

        # ◆ 7 모든 조건 충족 시 감지 성공
        if stable_ok and time_ok and match_ok:
            rospy.loginfo(f"✓ Fallback stabilized & matched (x={x:.1f}, y=
{y:.1f})")
            return True

        return False

# ----- 메인 루프 -----
def spin(self):
    rate = rospy.Rate(10)
    while not rospy.is_shutdown():
        try:
            if self.state == 1: self.state_1()
            elif self.state == 2: self.state_2()
            elif self.state == 3: self.state_3()
            elif self.state == 4: self.state_4()
            elif self.state == 5: self.state_5()
            elif self.state == 6: self.state_6()
            elif self.state == 101: self.state_101()
            elif self.state == 102: self.state_102()
            elif self.state == 103: self.state_103()
            elif self.state == 104: self.state_104()
            elif self.state == 105: self.state_105()
            elif self.state == 106: self.state_106()
            elif self.state == 201: self.state_201()
            elif self.state == 202: self.state_202()
            elif self.state == 301: self.state_301()

```

```

        elif self.state == 302: self.state_302()
    else:
        rospy.logwarn(f" ? Unknown state {self.state} -> 1")
        self.state = 1
    except Exception as e:
        rospy.logerr(f" ✨ Exception in state {self.state}: {e}")
    rate.sleep()

def state_1(self):
    try:
        # ① 관찰 자세로 이동
        self.goJ(self.ASM_OBS_START_JOINTS, "ASM_OBS_START_JOINTS")
        rospy.sleep(1.0)

        # ② 감지 결과 확인
        has_red = self.point_detected(self.red_result)
        has_orange = self.point_detected(self.orange_result)
        msg_orange = self.orange_result.get()

        # =====
        # 🍊 오렌지 감지 시 – 좌표 기반 핑업 절차 실행
        # =====
        if has_orange and msg_orange:
            dx = msg_orange.x
            dy = msg_orange.y

            # 비정상 토픽 값 (픽셀 좌표 등) 필터링
            if abs(dx) > 200 or abs(dy) > 200:
                rospy.logwarn(f"⚠ Ignored abnormal orange detection: x={dx:.1f}, y={dy:.1f}")
            return

        # -----
        # EMA 적용 (좌표 안정화 필터)
        # -----
        if self.prev_orange is None:
            self.prev_orange = np.array([dx, dy], dtype=float)
            self.ema_stable_count = 0
            rospy.loginfo("📊 EMA 초기화 중...")
            return

        curr = np.array([dx, dy], dtype=float)
        self.prev_orange = (1 - self.ema_alpha) * self.prev_orange +
self.ema_alpha * curr
        diff = np.linalg.norm(curr - self.prev_orange)

```

```

        if diff < self.ema_stable_thresh_mm:
            self.ema_stable_count += 2
        else:
            self.ema_stable_count = 0 # 다시 초기화

        rospy.loginfo_throttle(1.0, f" ✅ EMA 안정도: diff={diff:.2f}mm,
count={self.ema_stable_count}")

        # 충분히 안정화되었을 때만 핑업 시작
        if self.ema_stable_count < self.ema_min_frames:
            rospy.loginfo(" ✅ EMA 안정화 대기 중...")
            return

        rospy.loginfo(" ✅ EMA 안정화 완료 → 핑업 시작")

        dx_m = self.prev_orange[0] / 1000.0
        dy_m = self.prev_orange[1] / 1000.0

        # 1 XY 평면 이동
        rospy.loginfo(f" ➔ Move to target: dx={dx_m:.4f} m, dy=
{dy_m:.4f} m")
        self.ur5e.go_to_pose_rel([dx_m, dy_m, 0.0], [0,0,0])
        rospy.sleep(0.3)

        # 2 Z 하강
        rospy.loginfo(" ⬇ Descend 70 mm (Z only)")
        self.ur5e.go_to_pose_rel([0.0, 0.0, -0.07], [0,0,0])

        # 3 Grip ON
        self.grip_on_6s()

        # 4 Lift
        self.ur5e.go_to_pose_rel([0.0, 0.0, 0.115], [0,0,0])

        # 5 관찰 자세 복귀
        self.goJ(self.ASM_OBS_GRID_JOINTS, "ASM_OBS_GRID_JOINTS")

        # 6 다음 상태 전환
        self.state = 2
        rospy.loginfo(" ➔ state 2")

    elif has_red and not has_orange:
        self.state = 3
        rospy.loginfo(" ➔ state 3")

    else:

```

```

        rospy.loginfo("|| state1 hold")

    except Exception as e:
        rospy.logerr(f"✖ Exception in state 1: {e}")

def state_2(self):
    msg = self.darkgrid_result.get()
    cell = self.choose_cell_from_string(msg.data if msg else "")
    if cell:
        self.pick_cycle(self.DARKGRID_POSES, cell, grip_mode="off")
    else:
        rospy.loginfo("|| state2 no grid")
    self.state = 3
    rospy.loginfo("➡ back to state 3")

def state_3(self):
    try:
        # ① 관찰 자세로 이동
        self.goJ(self.ASM_RED_DETECT_TRIGGER_JOINTS,
        "ASM_RED_DETECT_TRIGGER_JOINTS")
        rospy.sleep(0.5) # 관찰 자세 안정화

        # 감지 결과 읽기
        has_red = self.point_detected(self.red_result)
        has_orange = self.point_detected(self.orange_result)
        msg_orange = self.orange_result.get()

        # =====
        # 🍊 오렌지 감지 시 - state 1과 동일한 좌표 기반 핵업 절차
        # =====

        if has_orange and msg_orange:
            dx = msg_orange.x / 1000.0 # mm → m 변환
            dy = msg_orange.y / 1000.0

            # 비정상 좌표 필터링
            if abs(msg_orange.x) > 200 or abs(msg_orange.y) > 200:
                rospy.logwarn(f"⚠ Ignored abnormal orange detection: x={msg_orange.x:.1f}, y={msg_orange.y:.1f}")
            return

        rospy.loginfo(f"🍊 Orange detected (state3): dx={dx:.4f} m,
dy={dy:.4f} m")

    # 1 XY 평면 이동

```

```

        rospy.loginfo("➡ Moving in XY plane first...")
        self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0.0, 0.0, 0.0])
        rospy.sleep(0.3)

        # 2 Z 하강 -0.07 m
        rospy.loginfo("⬇ Descend 70 mm (Z only)")
        self.ur5e.go_to_pose_rel([0.0, 0.0, -0.07], [0.0, 0.0, 0.0])

        # 3 Grip ON
        rospy.loginfo("🔥 Gripper ON")
        self.grip_on_6s()

        # 4 Z 상승 +0.115 m
        rospy.loginfo("⬆ Lift up 115 mm (Z only)")
        self.ur5e.go_to_pose_rel([0.0, 0.0, 0.115], [0.0, 0.0, 0.0])

        # 5 관찰 자세 복귀
        self.goJ(self.ASM_OBS_GRID_JOINTS, "ASM_OBS_GRID_JOINTS")

        # 6 다음 상태로
        self.state = 4
        rospy.loginfo("➡ state 4")

# =====
# ● 오렌지 감지 X, 빨간 원만 감지됨 → state 5로 전환
# =====
elif has_red and not has_orange:
    self.state = 5
    rospy.loginfo("➡ state 5")

# =====
# ✗ 감지 안됐을 때
# =====
else:
    rospy.loginfo("|| state3 hold")

except Exception as e:
    rospy.logerr(f"❗ Exception in state 3: {e}")

def state_4(self):
    msg = self.darkgrid_result.get()
    cell = self.choose_cell_from_string(msg.data if msg else "")
    if cell:
        self.pick_cycle(self.DARKGRID_POSES, cell, grip_mode="off")
    else:

```

```

        rospy.loginfo("|| state4 no grid")
        self.state = 5
        rospy.loginfo("➡️ state 5")

def state_5(self):
    rospy.loginfo("➡️ Enter state_5()")

    # ① 관찰자세로 이동 (그리드 전체 관찰)
    self.goJ(self.OBS_GRID_JOINTS, "ASM_OBS_GRID_JOINTS")
    rospy.sleep(0.5)

    # ② /gray_detection/result 감지 시도
    rospy.loginfo("⌚ Waiting for /gray_detection/result ...")
    gray_msg = None
    t0 = rospy.Time.now().to_sec()
    while (rospy.Time.now().to_sec() - t0) < 2.5 and not
rospy.is_shutdown():
        msg = self.gray_result.get()
        if msg and msg.data and msg.data.lower() != "none":
            gray_msg = msg
            break
        rospy.sleep(0.1)

        if not gray_msg:
            rospy.logwarn("❌ No gray cell detected → return to
OBS_START_JOINTS → state101")
            self.goJ(self.ASM_OBS_START_JOINTS, "ASM_OBS_START_JOINTS (after
gray fail)")
            self.state = 101
            return

    # ✅ 감지 성공 시 셀 이름 결정
    cell = self.choose_cell_from_string(gray_msg.data if gray_msg else "")
    if not cell or cell not in self.ASM_GRID_POSES:
        rospy.logwarn("⚠️ Invalid or unknown gray cell: {gray_msg.data}")
        self.goJ(self.ASM_OBS_START_JOINTS, "OBS_START_JOINTS (invalid
gray)")
        self.state = 101
        return

    rospy.loginfo(f"✅ Gray cell detected: {cell}")

    # ③ 해당 셀의 START 자세로 이동
    start_pose = self.ASM_GRID_POSES[cell]["start"]
    self.goJ(start_pose, f"{cell} start (state5)")

```

```

        rospy.sleep(0.3)

        # ④ /grid1Fallback/result 감지 시도
        rospy.loginfo("⌚ Waiting for /grid1Fallback/result ...")
        fb_msg = None
        t0 = rospy.Time.now().to_sec()
        while (rospy.Time.now().to_sec() - t0) < 2.5 and not
rospy.is_shutdown():

            msg = self.grid1Fallback.get()
            if msg and (msg.x != 0.0 or msg.y != 0.0):
                fb_msg = msg
                break
            rospy.sleep(0.05)

        if fb_msg:
            dx = fb_msg.x / 1000.0 # mm → m
            dy = fb_msg.y / 1000.0
            rospy.loginfo(f"📍 grid1Fallback offset: dx={dx:.3f} m, dy={dy:.3f} m")

            self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
            rospy.sleep(0.3)
            self.ur5e.go_to_pose_rel([0, 0, -0.115], [0, 0, 0])
            self.grip_on_6s()
            self.ur5e.go_to_pose_rel([0, 0, 0.115], [0, 0, 0])
        else:
            rospy.logwarn("⚠️ No /grid1Fallback/result → skipping pre-pick")

        # ⑤ RED DETECTION으로 미세 조정
        self.goJ(self.ASM_OBS_START_JOINTS, "ASM_OBS_START_JOINTS (red
detection)")
        rospy.loginfo("⌚ Waiting 1.5s for camera stabilization...")
        rospy.sleep(0.5)

        rospy.loginfo("⌚ Waiting for /redDetection/result ...")
        red_msg = None
        t0 = rospy.Time.now().to_sec()
        while (rospy.Time.now().to_sec() - t0) < 3.0 and not
rospy.is_shutdown():

            msg = self.redResult.get()
            if msg and msg.x != 0.0 and msg.y != 0.0:
                red_msg = msg
                rospy.loginfo("⌚ Red detected - waiting 1.5s for EMA
stabilization...")
                rospy.sleep(0.5)    # ✅ EMA가 평균값으로 안정화될 시간을 확보
                break

```

```

        rospy.sleep(0.1)

    if not red_msg:
        rospy.logwarn("✖ No /red_detection/result → state101")
        self.state = 101
        return

    dx = red_msg.x / 1000.0
    dy = red_msg.y / 1000.0
    rospy.loginfo(f"🔴 Red offset: dx={dx:.3f} m, dy={dy:.3f} m")

    try:
        rospy.loginfo("🚀 RELATIVE MOVE START: X={dx:.4f}m, Y={dy:.4f}m, Z=0.0m")
        self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
        rospy.sleep(0.3)
    except Exception as e:
        rospy.logwarn("⚠ XY offset move failed: {e}")

    # ⑥ 배치 및 복귀
    self.ur5e.go_to_pose_rel([0, 0, -0.04], [0, 0, 0])
    self.grip_off_6s()
    self.ur5e.go_to_pose_rel([0, 0, 0.04], [0, 0, 0])

    # ⑦ 복귀 및 다음 단계
    self.goJ(start_pose, f"{cell} return (state5)")
    self.state = 6
    rospy.loginfo("➡ Next: state 6")

# -----
def state_6(self):
    rospy.loginfo("➡ Enter state_6()")

    # ① 관찰자세 이동 (그리드 전체 관찰)
    self.goJ(self.OBS_GRID_JOINTS, "ASM_OBS_GRID_JOINTS")
    rospy.sleep(0.5)

    # ② /gray_detection/result 감지 시도
    rospy.loginfo("⌚ Waiting for /gray_detection/result ...")
    gray_msg = None
    t0 = rospy.Time.now().to_sec()
    while (rospy.Time.now().to_sec() - t0) < 2.5 and not
rospy.is_shutdown():
        msg = self.gray_result.get()
        if msg and msg.data and msg.data.lower() != "none":

```

```

        gray_msg = msg
        break
    rospy.sleep(0.1)

    # 🔞 감지 실패 시 → state 201
    if not gray_msg:
        rospy.logwarn("✖ No gray cell detected → return to
OBS_START_JOINTS → state201")
        self.goJ(self.ASM_OBS_START_JOINTS, "ASM_OBS_START_JOINTS (after
gray fail)")

        ##### ☆ 여기 추가 #####
        rospy.sleep(1.0)
        self.open_stopper()
        rospy.sleep(1.0)
        ##### ☆ 여기까지 #####
        self.state = 201
        return

    # ✅ 감지 성공 시 셀 이름 결정
    cell = self.choose_cell_from_string(gray_msg.data if gray_msg else "")
    if not cell or cell not in self.ASM_GRID_POSES:
        rospy.logwarn(f"⚠ Invalid or unknown gray cell: {gray_msg.data}")
        self.goJ(self.ASM_OBS_START_JOINTS, "OBS_START_JOINTS (invalid
gray)")
        ##### ☆ 여기 추가 #####
        rospy.sleep(1.0)
        self.open_stopper()
        rospy.sleep(1.0)
        ##### ☆ 여기까지 #####
        self.state = 201
        return

    rospy.loginfo(f"✅ Gray cell detected: {cell}")

    # ③ 해당 셀의 START 자세로 이동
    start_pose = self.ASM_GRID_POSES[cell]["start"]
    self.goJ(start_pose, f"{cell} start (state6)")
    rospy.sleep(0.3)

    # ④ /grid1Fallback/result 감지 시도
    rospy.loginfo("⌚ Waiting for /grid1Fallback/result ...")
    fb_msg = None

```

```

        t0 = rospy.Time.now().to_sec()
        while (rospy.Time.now().to_sec() - t0) < 2.5 and not
rospy.is_shutdown():
    msg = self.grid1Fallback.get()
    if msg and (msg.x != 0.0 or msg.y != 0.0):
        fb_msg = msg
        break
    rospy.sleep(0.05)

if fb_msg:
    # ! 단위만 m로 변환 - 축변환 금지
    dx = fb_msg.x / 1000.0
    dy = fb_msg.y / 1000.0
    rospy.loginfo(f"grid1Fallback offset: dx={dx:.3f} m, dy={dy:.3f} m")
    self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
    rospy.sleep(1.0)
    self.ur5e.go_to_pose_rel([0, 0, -0.115], [0, 0, 0])
    self.grip_on_6s()
    self.ur5e.go_to_pose_rel([0, 0, 0.115], [0, 0, 0])
else:
    rospy.logwarn("⚠️ No /grid1Fallback/result → skipping pre-pick")

# ⑤ RED DETECTION 기반 미세조정
self.goJ(self.ASM_RED_DETECT_TRIGGER_JOINTS,
"ASM_RED_DETECT_TRIGGER_JOINTS")
rospy.loginfo("⚠️ Waiting 1.5s for camera stabilization...")
rospy.sleep(0.5)

rospy.loginfo("⌚ Waiting for /red_detection/result ...")
red_msg = None
t0 = rospy.Time.now().to_sec()
while (rospy.Time.now().to_sec() - t0) < 3.0 and not
rospy.is_shutdown():
    msg = self.red_result.get()
    if msg and msg.x != 0.0 and msg.y != 0.0:
        red_msg = msg
        rospy.loginfo("⌚ Red detected - waiting 1.5s for EMA
stabilization...")
        rospy.sleep(0.5)    # ✓ EMA가 평균값으로 안정화될 시간을 확보
        break
    rospy.sleep(0.1)

# ! red 감지 실패 시 → state201
if not red_msg:

```

```

        rospy.logwarn("✖ No /red_detection/result → state201")

##### ☆ 여기 추가 #####
rospy.sleep(1.0)
self.open_stopper()
rospy.sleep(1.0)
##### ☆ 여기까지 #####

self.state = 201
return

dx = red_msg.x / 1000.0
dy = red_msg.y / 1000.0
rospy.loginfo(f"🔴 Red offset: dx={dx:.3f} m, dy={dy:.3f} m")

try:
    rospy.loginfo(f"🚀 RELATIVE MOVE START: X={dx:.4f}m, Y={dy:.4f}m,
Z=0.0m")
    self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
    rospy.sleep(0.3)
except Exception as e:
    rospy.logwarn(f"⚠ XY offset move failed: {e}")

# ⑥ Grip off
self.ur5e.go_to_pose_rel([0, 0, -0.04], [0, 0, 0])
self.grip_off_6s()
self.ur5e.go_to_pose_rel([0, 0, 0.04], [0, 0, 0])

# ⑦ 종료 및 다음 단계
rospy.loginfo("✓ state_6 complete → move to state 1")

##### ☆ 여기 추가 #####
rospy.sleep(1.0)
self.open_stopper()
rospy.sleep(1.0)
##### ☆ 여기까지 #####

self.state = 1

def state_101(self):
    rospy.loginfo("➡ Enter state_101()")

# ✓ 시작 포즈로 이동
self.goJ(self.ASM_OBS_START_JOINTS, "ASM_OBS_START_JOINTS")
rospy.sleep(1.0)

```

```

has_red = self.point_detected(self.red_result)
if has_red:
    rospy.loginfo("🔴 Red detected immediately → state 103")
    self.state = 103
    rospy.loginfo("➡️ state 103")
    return # ← 이후 로직 절대 실행되지 않게

# -----
# ② 감지 확인 (노이즈 방어 포함)
# -----
rospy.loginfo("⌚ Waiting for /grid1_fallback/result ...")
fb_msg = None
recent_points = []
t0 = rospy.Time.now().to_sec()

while (rospy.Time.now().to_sec() - t0) < 2.5 and not
rospy.is_shutdown():
    msg = self.grid1_fallback.get()
    if not msg or (msg.x == 0.0 and msg.y == 0.0):
        rospy.sleep(0.05)
        continue

    if abs(msg.x) > 200 or abs(msg.y) > 200:
        rospy.logwarn(f"⚠️ Ignored abnormal fallback detection: x={msg.x:.1f}, y={msg.y:.1f}")
        continue

    recent_points.append((msg.x, msg.y))
    if len(recent_points) > 15:
        recent_points.pop(0)

    if len(recent_points) >= 3:
        xs, ys = zip(*recent_points)
        std_x, std_y = np.std(xs), np.std(ys)
        if std_x < 2.0 and std_y < 2.0: # mm 기준 안정 조건
            fb_msg = msg
            rospy.loginfo("✅ Stable fallback detection confirmed.")
            break

    rospy.sleep(0.05)

has_red = self.point_detected(self.red_result)
has_gray_circle = fb_msg is not None

# -----
# ❤️ 회색 원 감지 성공 (EMA 기반 안정화 포함)

```

```

# -----
if has_gray_circle:
    rospy.loginfo("❤️ Gray circle detected - starting EMA
stabilization check")

rospy.sleep(0.5)

# ✅ 최신 감지값으로 보정
msg = self.grid1Fallback.get()
if msg and (msg.x != 0.0 or msg.y != 0.0):
    fb_msg = msg
    rospy.loginfo("🕒 Updated fallback position after delay.")

last_points = []
stable = False
start_time = rospy.Time.now().to_sec()

# EMA 안정화 루프
while not rospy.is_shutdown():
    msg = self.grid1Fallback.get()
    if msg and (msg.x != 0.0 or msg.y != 0.0):
        last_points.append((msg.x, msg.y))
        if len(last_points) > 5:
            last_points.pop(0)

        if len(last_points) >= 3:
            diffs = []
            for i in range(1, len(last_points)):
                dx = last_points[i][0] - last_points[i - 1][0]
                dy = last_points[i][1] - last_points[i - 1][1]
                diffs.append((dx**2 + dy**2)**0.5)
            avg_move = sum(diffs) / len(diffs)
            rospy.loginfo_throttle(1.0, f"📈 EMA Δ movement avg=
{avg_move:.2f} mm")

            if avg_move < 3.0: # 1mm 이하 변화 → 안정화 완료
                stable = True
                break

            if rospy.Time.now().to_sec() - start_time > 6.0:
                rospy.logwarn("⌚ EMA stabilization timeout - proceeding
anyway")
                break

    rospy.sleep(0.1)

```

```

        if stable:
            rospy.loginfo("✓ EMA stabilized - executing pickup")
        else:
            rospy.logwarn("⚠ Proceeding without full EMA stabilization")

        dx = fb_msg.x / 1000.0
        dy = fb_msg.y / 1000.0
        rospy.loginfo(f"📍 Gray circle offset: dx={dx:.3f} m, dy={dy:.3f} m")

    rospy.sleep(0.3)

    # XY 이동 → Z 하강 → Grip → 상승
    self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
    rospy.sleep(0.3)
    self.ur5e.go_to_pose_rel([0, 0, -0.07], [0, 0, 0])
    self.grip_on_6s()
    self.ur5e.go_to_pose_rel([0, 0, 0.115], [0, 0, 0])

    # 다음 단계
    self.goJ(self.OBS_GRID_JOINTS, "OBS_GRID_JOINTS")
    rospy.sleep(0.3)
    self.state = 102
    rospy.loginfo("➡ state 102")

# -----
# ● 빨간 원 감지 시 (EMA 없이 즉시)
# -----
elif has_red and not has_gray_circle:
    rospy.loginfo("⚠ No gray circle, but red detected → state 103")
    self.state = 103
    rospy.loginfo("➡ state 103")

# -----
# ✗ 아무 감지도 없음
# -----
else:
    rospy.loginfo("|| state101 hold")

def state_102(self):
    msg = self.inv_gray_result.get()
    cell = self.choose_cell_from_string(msg.data if msg else "")
    if cell:
        self.pick_cycle(self._FALLBACK_POSES, cell, grip_mode="off")
    else:

```

```

        rospy.loginfo("|| state102 no inv-gray")
        self.state = 103
        rospy.loginfo("➡ state 103")

def state_103(self):
    rospy.loginfo("➡ Enter state_103()")

    # ✅ 감지 포즈 이동
    self.goJ(self.ASM_RED_DETECT_TRIGGER_JOINTS,
"ASM_RED_DETECT_TRIGGER_JOINTS")
    has_red = self.point_detected(self.red_result)
    if has_red:
        rospy.loginfo("🔴 Red detected immediately → state 103")
        self.state = 105
        rospy.loginfo("➡ state 103")
        return # ← 이후 로직 절대 실행되지 않게

    # -----
    # ② 감지 확인
    # -----
    rospy.loginfo("⌚ Waiting for /grid1Fallback/result ...")
    fb_msg = None
    t0 = rospy.Time.now().to_sec()
    while (rospy.Time.now().to_sec() - t0) < 2.5 and not
rospy.is_shutdown():
        msg = self.grid1Fallback.get()
        if msg and (msg.x != 0.0 or msg.y != 0.0):
            fb_msg = msg
            break
        rospy.sleep(0.05)

    has_red = self.point_detected(self.red_result)
    has_gray_circle = fb_msg is not None # grid1Fallback 감지 성공 시 True

    # -----
    # ❤️ 회색 원 감지 성공 (grid1Fallback + EMA 안정화)
    # -----
    if has_gray_circle:
        rospy.loginfo("❤️ Gray circle detected - starting EMA
stabilization check")

        rospy.sleep(0.5)

    # ✅ 최신 감지값으로 보정
    msg = self.grid1Fallback.get()
    if msg and (msg.x != 0.0 or msg.y != 0.0):

```

```

fb_msg = msg
rospy.loginfo("🕒 Updated fallback position after delay.")

last_points = []
stable = False
start_time = rospy.Time.now().to_sec()

# EMA 안정화 루프
while not rospy.is_shutdown():
    msg = self.grid1Fallback.get()
    if msg and (msg.x != 0.0 or msg.y != 0.0):
        last_points.append((msg.x, msg.y))
        if len(last_points) > 5:
            last_points.pop(0)

        if len(last_points) >= 3:
            diffs = []
            for i in range(1, len(last_points)):
                dx = last_points[i][0] - last_points[i - 1][0]
                dy = last_points[i][1] - last_points[i - 1][1]
                diffs.append((dx**2 + dy**2)**0.5)
            avg_move = sum(diffs) / len(diffs)
            rospy.loginfo_throttle(1.0, f"〽️ EMA Δ movement avg={avg_move:.2f} mm")

            if avg_move < 3.0: # 1mm 이하 변화 → 안정화 완료
                stable = True
                break

            if rospy.Time.now().to_sec() - start_time > 6.0:
                rospy.logwarn("⌚ EMA stabilization timeout - proceeding anyway")
                break

            rospy.sleep(0.1)

    if stable:
        rospy.loginfo("✅ EMA stabilized - executing pickup")
    else:
        rospy.logwarn("⚠️ Proceeding without full EMA stabilization")

    dx = fb_msg.x / 1000.0
    dy = fb_msg.y / 1000.0
    rospy.loginfo(f"📍 Gray circle offset: dx={dx:.3f} m, dy={dy:.3f} m")

```

```

# ❶ XY 평면 이동
rospy.loginfo("➡ Moving in XY plane first...")
self.ur5e.go_to_pose_rel(
    relative_xyz=[dx, dy, 0.0],
    relative_rpy=[0.0, 0.0, 0.0]
)

# ❷ 안정화 대기
rospy.sleep(0.5)

# ❸ Z축 하강
rospy.loginfo("⬇ Descend 70 mm (Z only)")
self.ur5e.go_to_pose_rel(
    relative_xyz=[0.0, 0.0, -0.07],
    relative_rpy=[0.0, 0.0, 0.0]
)

# ❹ Grip ON
rospy.loginfo("👉 Gripper ON")
self.grip_on_6s()

# ❺ 상승
rospy.loginfo("⬆ Lift up 115 mm (Z only)")
self.ur5e.go_to_pose_rel(
    relative_xyz=[0.0, 0.0, 0.115],
    relative_rpy=[0.0, 0.0, 0.0]
)

# ❻ 관찰 자세로 복귀 및 다음 단계 전환
self.goJ(self.OBS_GRID_JOINTS, "OBS_GRID_JOINTS")
rospy.sleep(0.3)
self.state = 104
rospy.loginfo("➡ state 102")

# -----
# ❼ 회색 원(X), 빨간 원(O) → state 105
# -----
elif has_red and not has_gray_circle:
    rospy.loginfo("⚠ No gray circle, but red detected → state 105")
    self.state = 105
    rospy.loginfo("➡ state 105")

# -----
# ❽ 아무 감지도 없음 → hold
# -----
else:

```

```

        rospy.loginfo("|| state103 hold")

def state_104(self):
    msg = self.inv_gray_result.get()
    cell = self.choose_cell_from_string(msg.data if msg else "")
    if cell:
        self.pick_cycle(self._FALLBACK_POSES, cell, grip_mode="off")
    else:
        rospy.loginfo("|| state104 no inv-gray")
    self.state = 105
    rospy.loginfo("➡️ state 105")

def state_105(self):
    rospy.loginfo("➡️ Enter state_105()")

    # ① 관찰 포즈 이동
    self.goJ(self.ASM_OBS_GRID_JOINTS, "ASM_OBS_GRID_JOINTS")
    rospy.sleep(0.5)

    # ② inverse grid 감지 시도
    rospy.loginfo("⌚ Waiting for /inverse_grid_detection_result ...")
    inv_grid_msg = None
    t0 = rospy.Time.now().to_sec()
    while (rospy.Time.now().to_sec() - t0) < 2.5 and not
rospy.is_shutdown():
        msg = self.inv_grid_result.get()
        if msg and msg.data and msg.data.lower() != "none":
            inv_grid_msg = msg
            break
        rospy.sleep(0.1)

    if inv_grid_msg:
        cell = inv_grid_msg.data.strip()
        rospy.loginfo(f"✅ Inverse grid cell detected: {cell}")

        if cell in self.DIS_GRID_POSES:
            start_pose = self.DIS_GRID_POSES[cell]["start"]
            self.goJ(start_pose, f"{cell} start (inverse grid)")
            rospy.sleep(0.5)

    # ③ grid1Fallback 상대좌표 보정
    rospy.loginfo("⌚ Waiting for /grid1Fallback/result ...")
    fb_msg = None
    t0 = rospy.Time.now().to_sec()

```

```

        while (rospy.Time.now().to_sec() - t0) < 2.5 and not
rospy.is_shutdown():
    msg = self.grid2Fallback.get()
    if msg and (msg.x != 0.0 or msg.y != 0.0):
        fb_msg = msg
        break
    rospy.sleep(0.05)

if fb_msg:
    dx = fb_msg.x / 1000.0
    dy = fb_msg.y / 1000.0
    rospy.loginfo(f"🔴 grid1Fallback offset: dx={dx:.3f} m,
dy={dy:.3f} m")

    self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
    rospy.sleep(0.3)
    self.ur5e.go_to_pose_rel([0, 0, -0.115], [0, 0, 0])
    self.grip_on_6s()
    self.ur5e.go_to_pose_rel([0, 0, 0.115], [0, 0, 0])
else:
    rospy.logwarn("⚠️ No /grid1Fallback/result → skipping
pre-pick")

# ④ ASM_OBS_START_JOINTS로 복귀 후 red detection 수행
self.goJ(self.ASM_OBS_START_JOINTS, "ASM_OBS_START_JOINTS")
rospy.sleep(0.5)

rospy.loginfo("⌚ Waiting for /red_detection/result ...")
red_msg = None
t0 = rospy.Time.now().to_sec()
while (rospy.Time.now().to_sec() - t0) < 3.0 and not
rospy.is_shutdown():
    msg = self.red_result.get()
    if msg and msg.x != 0.0 and msg.y != 0.0:
        red_msg = msg
        break
    rospy.sleep(0.1)

if red_msg:
    dx = red_msg.x / 1000.0
    dy = red_msg.y / 1000.0
    rospy.loginfo(f"🔴 Red offset: dx={dx:.3f} m, dy={dy:.3f}
m")

try:
    rospy.loginfo(f"🚀 RELATIVE MOVE START: X={dx:.4f}m,

```

```

Y={dy:.4f}, Z=0.0m")
        self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
        rospy.sleep(0.3)
    except Exception as e:
        rospy.logwarn(f"⚠ XY offset move failed: {e}")

    # ⑤ 배치 및 복귀
    self.ur5e.go_to_pose_rel([0, 0, -0.04], [0, 0, 0])
    self.grip_off_6s()
    self.ur5e.go_to_pose_rel([0, 0, 0.04], [0, 0, 0])

    # ✅ state 전환
    self.state = 106
    rospy.loginfo("➡ state 106")
else:
    rospy.logwarn("✖ No /red_detection/result after inverse
pick - skipping placement")
    self.state = 1
    rospy.loginfo("➡ Return to state 1 (no red detection)")

else:
    rospy.logwarn(f"⚠ Invalid grid cell name: {cell}")
    self.state = 1
    rospy.loginfo("➡ Return to state 1 (invalid cell)")

else:
    rospy.logwarn("✖ No inverse grid detection result received")
    self.state = 1
    rospy.loginfo("➡ Return to state 1 (no inverse grid)")

def state_106(self):
    rospy.loginfo("➡ Enter state_106()")

    # ① 관찰 포즈 이동 (inverse grid 감지용)
    self.goJ(self.ASM_OBS_GRID_JOINTS, "ASM_OBS_GRID_JOINTS")
    rospy.sleep(0.5)

    # ② inverse grid 감지 시도
    rospy.loginfo("⌚ Waiting for /inverse_grid_detection_result ...")
    inv_grid_msg = None
    t0 = rospy.Time.now().to_sec()
    while (rospy.Time.now().to_sec() - t0) < 2.5 and not
rospy.is_shutdown():
        msg = self.inv_grid_result.get()

```

```

        if msg and msg.data and msg.data.lower() != "none":
            inv_grid_msg = msg
            break
        rospy.sleep(0.1)

    if inv_grid_msg:
        cell = inv_grid_msg.data.strip()
        rospy.loginfo(f"✓ Inverse grid cell detected: {cell}")

    if cell in self.DIS_GRID_POSES:
        start_pose = self.DIS_GRID_POSES[cell]["start"]
        self.goJ(start_pose, f"{cell} start (inverse grid)")
        rospy.sleep(0.5)

        # ④ grid1Fallback 상대좌표 보정
        rospy.loginfo("⌚ Waiting for /grid1Fallback/result ...")
        fb_msg = None
        t0 = rospy.Time.now().to_sec()
        while (rospy.Time.now().to_sec() - t0) < 2.5 and not
rospy.is_shutdown():
            msg = self.grid2Fallback.get()
            if msg and (msg.x != 0.0 or msg.y != 0.0):
                fb_msg = msg
                break
            rospy.sleep(0.05)

        if fb_msg:
            dx = fb_msg.x / 1000.0
            dy = fb_msg.y / 1000.0
            rospy.loginfo(f"📍 grid1Fallback offset: dx={dx:.3f} m,
dy={dy:.3f} m")

            self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
            rospy.sleep(0.3)
            self.ur5e.go_to_pose_rel([0, 0, -0.115], [0, 0, 0])
            self.grip_on_6s()
            self.ur5e.go_to_pose_rel([0, 0, 0.115], [0, 0, 0])
        else:
            rospy.logwarn("⚠️ No /grid1Fallback/result → skipping
pre-pick")

        # ④ ASM_RED_DETECT_TRIGGER_JOINTS로 복귀 후 red detection 수행
        self.goJ(self.ASM_RED_DETECT_TRIGGER_JOINTS,
"ASM_RED_DETECT_TRIGGER_JOINTS")
        rospy.sleep(0.5)

```

```

        rospy.loginfo("⌚ Waiting for /red_detection/result ...")
        red_msg = None
        t0 = rospy.Time.now().to_sec()
        while (rospy.Time.now().to_sec() - t0) < 3.0 and not
rospy.is_shutdown():
            msg = self.red_result.get()
            if msg and msg.x != 0.0 and msg.y != 0.0:
                red_msg = msg
                break
            rospy.sleep(0.1)

        if red_msg:
            dx = red_msg.x / 1000.0
            dy = red_msg.y / 1000.0
            rospy.loginfo(f"🔴 Red offset: dx={dx:.3f} m, dy={dy:.3f} m")

try:
    rospy.loginfo(f"🚀 RELATIVE MOVE START: X={dx:.4f}m, Y={dy:.4f}m, Z=0.0m")
    self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0, 0, 0])
    rospy.sleep(0.5)
except Exception as e:
    rospy.logwarn(f"⚠ XY offset move failed: {e}")

# ⑤ 배치 및 복귀
self.ur5e.go_to_pose_rel([0, 0, -0.04], [0, 0, 0])
self.grip_off_6s()
self.ur5e.go_to_pose_rel([0, 0, 0.04], [0, 0, 0])

##### ★ 여기 추가 #####
rospy.sleep(1.0)
self.open_stopper()
rospy.sleep(1.0)
##### ★ 여기까지 #####

```

#  state 전환

```

self.state = 101
rospy.loginfo("➡ state 101")
else:
    rospy.logwarn("✖ No /red_detection/result after inverse
pick - skipping placement")

##### ★ 여기 추가 #####
rospy.sleep(1.0)
self.open_stopper()

```

```

        rospy.sleep(1.0)
        ##### ★ 여기까지 #####
        self.state = 301
        rospy.loginfo("➡ Move to state 301 (no red detection)")

    else:
        rospy.logwarn(f"⚠ Unknown grid cell name: {cell}")

        ##### ★ 여기 추가 #####
        rospy.sleep(1.0)
        self.open_stopper()
        rospy.sleep(1.0)
        ##### ★ 여기까지 #####
        self.state = 301
        rospy.loginfo("➡ Move to state 301 (invalid cell)")

    else:
        # ✗ inverse grid 감지 실패 시
        rospy.logwarn("✗ No inverse grid detection result received")

        ##### ★ 여기 추가 #####
        rospy.sleep(1.0)
        self.open_stopper()
        rospy.sleep(1.0)
        ##### ★ 여기까지 #####
        self.state = 301
        rospy.loginfo("➡ Move to state 301 (no inverse grid)")


def state_201(self):
    rospy.loginfo("➡ Enter state_201()")

    # ① 시작 자세
    self.goJ(self.ASM_OBS_START_JOINTS, "ASM_OBS_START_JOINTS")
    rospy.sleep(3.0)

    # ② 감지
    msg_orange = self.orange_result.get()
    has_orange = self.point_detected(self.orange_result)
    has_red = self.point_detected(self.red_result)

    # 🍊 오렌지 감지 시 → pick & place → state 202
    if has_orange and msg_orange:

```

```

dx = msg_orange.x
dy = msg_orange.y

# 비정상 좌표 방지
if abs(dx) > 200 or abs(dy) > 200:
    rospy.logwarn(f"⚠️ Ignored abnormal orange detection: x={dx:.1f}, y={dy:.1f}")
    return

# =====
# ◆◆◆ ① EMA 초기화 (state_1 그대로)
# =====

if self.prev_orange is None:
    self.prev_orange = np.array([dx, dy], dtype=float)
    self.ema_stable_count = 0
    rospy.loginfo("📊 EMA 초기화 중... (state_201)")
    return

# =====
# ◆◆◆ ② EMA 적용
# =====

curr = np.array([dx, dy], dtype=float)
self.prev_orange = (1 - self.ema_alpha) * self.prev_orange +
self.ema_alpha * curr

diff = np.linalg.norm(curr - self.prev_orange)

if diff < self.ema_stable_thresh_mm:
    self.ema_stable_count += 1
else:
    self.ema_stable_count = 0

rospy.loginfo_throttle(
    1.0,
    f"📈 (state201) EMA 안정도: diff={diff:.2f}mm, count={self.ema_stable_count}"
)

# =====
# ◆◆◆ ③ EMA 안정화 대기
# =====

if self.ema_stable_count < self.ema_min_frames:
    rospy.loginfo("⚠️ (state201) EMA 안정화 대기 중...")
    return

```

```

rospy.loginfo("✓ (state201) EMA 안정화 완료 → 핵업 시작")

# =====
# ◆ EMA 안정된 좌표 사용
# =====

dx_m = self.prev_orange[0] / 1000.0
dy_m = self.prev_orange[1] / 1000.0

# ===== 원본 위치 그대로 유지 =====
self.ur5e.go_to_pose_rel([dx_m, dy_m, 0], [0,0,0])
rospy.sleep(0.8)
self.ur5e.go_to_pose_rel([0,0,-0.07],[0,0,0])
self.grip_on_6s()
self.ur5e.go_to_pose_rel([0,0,0.115],[0,0,0])

# Grid 놓기
self.goJ(self.ASM_OBS_GRID_JOINTS, "ASM_OBS_GRID_JOINTS")
msg = self.darkgrid_result.get()
cell = self.choose_cell_from_string(msg.data if msg else "")

if cell and cell in self.DARKGRID_POSES:
    start_pose = self.DARKGRID_POSES[cell]["start"]
    pick_pose = self.DARKGRID_POSES[cell]["pick"]
    self.goJ(start_pose, f"{cell} start")
    rospy.sleep(0.5)
    self.goJ(pick_pose, f"{cell} place")
    self.grip_off_6s()
    rospy.sleep(0.5)
    self.goJ(start_pose, f"{cell} return start")
else:
    rospy.logwarn("✗ No valid dark grid detected.")

# 다음 단계
self.goJ(self.ASM_RED_DETECT_TRIGGER_JOINTS,
"ASM_RED_DETECT_TRIGGER_JOINTS")
self.state = 202
rospy.loginfo("→ Transition to state_202")

# ● 빨간색만 감지
elif has_red and not has_orange:
    rospy.loginfo("● Red only detected → move to red trigger (state
202)")
    self.goJ(self.ASM_RED_DETECT_TRIGGER_JOINTS,
"ASM_RED_DETECT_TRIGGER_JOINTS")
    self.state = 202

```

```

# ❌ 아무 감지도 없음
else:
    rospy.loginfo("!! state201 hold (no orange/red detected)")

# =====
# 🍊 state_202: 두 번째 오렌지 pick + grid 놓기 + state101로 복귀
# =====

def state_202(self):
    rospy.loginfo("➡ Enter state_202()")

    msg_orange2 = self.orange_result.get()
    has_orange2 = self.point_detected(self.orange_result)
    has_red2    = self.point_detected(self.red_result)

    # 🍊 두 번째 오렌지 감지 → pick & place → state101
    if has_orange2 and msg_orange2:
        dx = msg_orange2.x / 1000.0
        dy = msg_orange2.y / 1000.0
        rospy.sleep(2.0)
        rospy.loginfo(f"🍊 (Second) Orange detected: dx={dx:.4f}, dy={dy:.4f}")

    # 학습
    self.ur5e.go_to_pose_rel([dx, dy, 0], [0,0,0])
    rospy.sleep(0.8)
    self.ur5e.go_to_pose_rel([0,0,-0.07],[0,0,0])
    self.grip_on_6s()
    self.ur5e.go_to_pose_rel([0,0,0.115],[0,0,0])

    # Grid 놓기
    self.goJ(self.ASM_OBS_GRID_JOINTS, "ASM_OBS_GRID_JOINTS")
    msg2 = self.darkgrid_result.get()
    cell2 = self.choose_cell_from_string(msg2.data if msg2 else "")
    if cell2 and cell2 in self.DARKGRID_POSES:
        start_pose2 = self.DARKGRID_POSES[cell2]["start"]
        pick_pose2  = self.DARKGRID_POSES[cell2]["pick"]
        self.goJ(start_pose2, f"{cell2} start")
        rospy.sleep(0.5)
        self.goJ(pick_pose2, f"{cell2} place")
        self.grip_off_6s()
        rospy.sleep(0.5)
        self.goJ(start_pose2, f"{cell2} return start")
    else:

```

```

        rospy.logwarn("✖ No valid dark grid detected in state_202.")

# 완료 후 state101로 복귀
self.goJ(self.ASM_OBS_START_JOINTS, "ASM_OBS_START_JOINTS")

##### ☆ 여기 추가 #####
rospy.sleep(1.0)
self.open_stopper()
rospy.sleep(1.0)
##### ☆ 여기까지 #####

self.state = 101
rospy.loginfo("✓ Finished second orange → state101")

# ● 빨간색만 감지 → state101로 복귀
elif has_red2 and not has_orange2:
    rospy.loginfo("● Red only detected → state101")

##### ☆ 여기 추가 #####
rospy.sleep(1.0)
self.open_stopper()
rospy.sleep(1.0)
##### ☆ 여기까지 #####

self.state = 101

# ✎ 아무 감지도 없음 → hold
else:
    rospy.loginfo("|| state202 hold (no orange/red detected)")

# =====
# ❤ state_301: 첫 번째 회색 원 감지 및 픽업 → grid에 놓기 → state_302 전환
# =====

def state_301(self):
    rospy.loginfo("➡ Enter state_301()")

    # ① 시작 자세
    self.goJ(self.ASM_OBS_START_JOINTS, "ASM_OBS_START_JOINTS")
    rospy.sleep(3.0)

    # ② 회색 원 감지 시도 (/grid1Fallback/result)
    rospy.loginfo("⌚ Waiting for /grid1Fallback/result ...")
    fb_msg = None
    recent_points = []
    t0 = rospy.Time.now().to_sec()

```

```

    while (rospy.Time.now().to_sec() - t0) < 5.0 and not
rospy.is_shutdown():
    msg = self.grid1Fallback.get()
    if not msg or (msg.x == 0.0 and msg.y == 0.0):
        rospy.sleep(0.05)
        continue

    # 🚧 Outlier filter
    if abs(msg.x) > 200 or abs(msg.y) > 200:
        rospy.logwarn(f"⚠️ Ignored abnormal fallback detection: x={msg.x:.1f}, y={msg.y:.1f}")
        continue

    # 🚧 Stability filter
    recent_points.append((msg.x, msg.y))
    if len(recent_points) > 15:
        recent_points.pop(0)

    if len(recent_points) >= 4:
        xs, ys = zip(*recent_points)
        std_x, std_y = np.std(xs), np.std(ys)
        if std_x < 3.0 and std_y < 3.0:
            fb_msg = msg
            rospy.loginfo("✅ Stable fallback detection confirmed.")
            break
    rospy.sleep(0.05)

has_red = self.point_detected(self.red_result)
has_gray_circle = fb_msg is not None

# -----
# ❤️ 회색 원 감지 성공 → 픽업 절차 수행
# -----
if has_gray_circle:
    dx = fb_msg.x / 1000.0
    dy = fb_msg.y / 1000.0
    rospy.loginfo(f"📍 Gray circle offset: dx={dx:.3f} m, dy={dy:.3f} m")
    rospy.sleep(2.0)

# XY 이동
rospy.loginfo("➡️ Moving in XY plane first...")
self.ur5e.go_to_pose_rel([dx, dy, 0.0], [0.0, 0.0, 0.0])
rospy.sleep(0.8)

```

```

# 하강 → Grip ON → 상승
self.ur5e.go_to_pose_rel([0, 0, -0.07], [0, 0, 0])
self.grip_on_6s()
self.ur5e.go_to_pose_rel([0, 0, 0.115], [0, 0, 0])

# 관찰자세 이동 후 그리드로 이동
self.goJ(self.OBS_GRID_JOINTS, "OBS_GRID_JOINTS")
msg = self.inv_gray_result.get()
cell = self.choose_cell_from_string(msg.data if msg else "")

if cell and cell in self._FALLBACK_POSES:
    start_pose = self._FALLBACK_POSES[cell]["start"]
    pick_pose = self._FALLBACK_POSES[cell]["pick"]
    self.goJ(start_pose, f"{cell} start (gray)")
    rospy.sleep(0.5)
    self.goJ(pick_pose, f"{cell} pick (gray)")
    rospy.loginfo("👉 Grip OFF (6s)")
    self.grip_off_6s()
    rospy.sleep(0.5)
    self.goJ(start_pose, f"{cell} return start (gray)")

else:
    rospy.logwarn("✖ No valid inv-gray grid detected.")

# ✅ 다음 단계로 전환
self.goJ(self.ASM_RED_DETECT_TRIGGER_JOINTS,
"ASM_RED_DETECT_TRIGGER_JOINTS")
self.state = 302
rospy.loginfo("➡ Move to state_302")

# ● 빨간 원만 감지 → 핑 없이 바로 state_302 전환
elif has_red and not has_gray_circle:
    rospy.loginfo("● Red detected only → move to
ASM_RED_DETECT_TRIGGER_JOINTS")
    self.goJ(self.ASM_RED_DETECT_TRIGGER_JOINTS,
"ASM_RED_DETECT_TRIGGER_JOINTS")
    self.state = 302
    rospy.loginfo("➡ state_302")

# ❌ 아무 감지도 없음
else:
    rospy.loginfo("|| state301 hold (no detection)")

# =====
# ❤️ state_302: 두 번째 회색 원 감지 및 핑업 → grid에 놓기 → state_1 복귀
# =====

```

```

def state_302(self):
    rospy.loginfo("➡ Enter state_302()")

    # ① 시작 포즈 (레드 트리거 위치)
    self.goJ(self.ASM_RED_DETECT_TRIGGER_JOINTS,
"ASM_RED_DETECT_TRIGGER_JOINTS")

    # ② 감지 시도
    rospy.loginfo("⌚ Waiting for /grid1Fallback/result ...")
    fb_msg = None
    recent_points = []
    t0 = rospy.Time.now().to_sec()

    while (rospy.Time.now().to_sec() - t0) < 5.0 and not
rospy.is_shutdown():
        msg = self.grid1Fallback.get()
        if not msg or (msg.x == 0.0 and msg.y == 0.0):
            rospy.sleep(0.05)
            continue

        if abs(msg.x) > 200 or abs(msg.y) > 200:
            rospy.logwarn(f"⚠ Ignored abnormal fallback detection: x={msg.x:.1f}, y={msg.y:.1f}")
            continue

        recent_points.append((msg.x, msg.y))
        if len(recent_points) > 15:
            recent_points.pop(0)

        if len(recent_points) >= 4:
            xs, ys = zip(*recent_points)
            std_x, std_y = np.std(xs), np.std(ys)
            if std_x < 3.0 and std_y < 3.0:
                fb_msg = msg
                rospy.loginfo("✅ Stable fallback detection confirmed.")
                break
            rospy.sleep(0.05)

has_red = self.point_detected(self.red_result)
has_gray_circle = fb_msg is not None

# ❤ 회색 원 감지 성공 시 → 픽업 후 grid 놓기
if has_gray_circle:
    dx = fb_msg.x / 1000.0
    dy = fb_msg.y / 1000.0
    rospy.loginfo(f"📍 Gray circle offset: dx={dx:.3f} m, dy={dy:.3f} m")

```

```

m")
    rospy.sleep(2.0)

    self.ur5e.go_to_pose_rel([dx, dy, 0], [0, 0, 0])
    rospy.sleep(0.8)
    self.ur5e.go_to_pose_rel([0, 0, -0.07], [0, 0, 0])
    self.grip_on_6s()
    self.ur5e.go_to_pose_rel([0, 0, 0.115], [0, 0, 0])

    # 관찰자세로 복귀 후 grid 놀기
    self.goJ(self.OBS_GRID_JOINTS, "OBS_GRID_JOINTS")
    msg = self.inv_gray_result.get()
    cell = self.choose_cell_from_string(msg.data if msg else "")

    if cell and cell in self._FALLBACK_POSES:
        start_pose = self._FALLBACK_POSES[cell]["start"]
        pick_pose = self._FALLBACK_POSES[cell]["pick"]
        self.goJ(start_pose, f"{cell} start (gray2)")
        rospy.sleep(0.5)
        self.goJ(pick_pose, f"{cell} pick (gray2)")
        rospy.loginfo("👉 Grip OFF (6s)")
        self.grip_off_6s()
        rospy.sleep(0.5)
        self.goJ(start_pose, f"{cell} return start (gray2)")
    else:
        rospy.logwarn("✖ No valid inv-gray grid detected
(state302.)")

    # ✅ 완료 후 state 1 복귀
    self.goJ(self.ASM_OBS_START_JOINTS, "ASM_OBS_START_JOINTS")

    ##### ☆ 여기 추가 #####
    rospy.sleep(1.0)
    self.open_stopper()
    rospy.sleep(1.0)
    ##### ☆ 여기까지 #####
    self.state = 1
    rospy.loginfo("✅ Finished second gray → state 1")

    # ● 빨간 원만 감지 → pick 없이 바로 state 1 전환
    elif has_red and not has_gray_circle:
        rospy.loginfo("🔴 Red only detected → skip pick → state 1")

    ##### ☆ 여기 추가 #####
    rospy.sleep(1.0)

```

```

        self.open_stopper()
        rospy.sleep(1.0)
        ##### ★ 여기까지 #####
        self.state = 1

    # ❌ 아무 감지도 없음 → hold
    else:
        rospy.loginfo("!! state302 hold (no detection)")

if __name__ == "__main__":
    node = AsmFsmNode()
    node.spin()

```

winding\_detect\_node.py

```

#!/usr/bin/env python3
# -*- coding:utf-8 -*-

import rospy, cv2, numpy as np, os, math
from sensor_msgs.msg import Image
from cv_bridge import CvBridge
from geometry_msgs.msg import Point

class StableGrayDetectionNode:
    def __init__(self):
        rospy.init_node('stable_gray_detection_node', anonymous=True)
        self.bridge = CvBridge()
        self.detection_pub = rospy.Publisher('/orange_detection/result',
Point, queue_size=1)
        self.image_sub = rospy.Subscriber("/camera/image_raw", Image,
self.image_callback)

        # =====
        # ❁ 사용자 조정 파라미터 (변경 금지)
        # =====
        self.ROI_WIDTH = 400
        self.ROI_HEIGHT = 400
        self.TARGET_SIZE = (1200, 1200)
        self.CENTER_PX = (600, 600)
        self.DETECTION_OFFSET = 300
        self.scale_x = 0.115
        self.scale_y = 0.115
        self.CAMERA_OFFSET_X_MM = 87.0

```

```

        self.CAMERA_OFFSET_Y_MM = 2.0
        self.MIN_RADIUS = 250
        self.MAX_RADIUS = 320
        self.CENTER_TOL_MM = 60.0
        self.LOWER_GRAY = 140
        self.UPPER_GRAY = 255
        self.HOUGH_DP = 1
        self.HOUGH_MIN_DIST = 100
        self.HOUGH_PARAM1 = 50
        self.HOUGH_PARAM2 = 20
        self.prev_center = None
        self.prev_radius = None
        self.alpha = 0.2
        self.ORANGE_RATIO_THRESH = 0.03
        self.ORANGE_MIN = (50, 80, 240)
        self.ORANGE_MAX = (120, 150, 255)

# =====
# 📁 카메라 캘리브레이션
# =====

calib_path =
"/home/kiminyeop/catkin_ws/src/ur_python/src/dataset_bra2_checkboard3/circlegrid_calibration_results_8x6_20mm.npz"
if os.path.exists(calib_path):
    data = np.load(calib_path)
    self.camera_matrix = data["camera_matrix"]
    self.dist_coeffs = data["dist_coeffs"]
    rospy.loginfo("📸 Loaded camera calibration from: {}").format(calib_path)
else:
    rospy.logwarn("⚠️ Calibration file not found - skipping undistortion.")
    self.camera_matrix, self.dist_coeffs = None, None

rospy.loginfo("🔴 Stable Gray Detection Node initialized (Hough + Orange area + dx/dy display)")

# -----
def image_callback(self, msg):
    try:
        frame = self.bridge.imgmsg_to_cv2(msg, "bgr8")
        if self.camera_matrix is not None:
            frame = cv2.undistort(frame, self.camera_matrix,
self.dist_coeffs)

        H, W = frame.shape[:2]
        x1 = int(W/2 - self.ROI_WIDTH/2)

```

```

        y1 = int(H/2 - self.ROI_HEIGHT/2)
        cropped = frame[y1:y1+self.ROI_HEIGHT, x1:x1+self.ROI_HEIGHT]
        resized = cv2.resize(cropped, self.TARGET_SIZE,
interpolation=cv2.INTER_LINEAR)

        self.detect_gray_circle(resized)

    except Exception as e:
        rospy.logerr(f"Gray Detection Error: {e}")

# -----
def detect_gray_circle(self, frame):
    output = frame.copy()
    gray = cv2.cvtColor(frame, cv2.COLOR_BGR2GRAY)
    gray_filtered = cv2.inRange(gray, self.LOWER_GRAY, self.UPPER_GRAY)
    gray_blurred = cv2.GaussianBlur(gray_filtered, (9, 9), 2)

    OFFSET = self.DETECTION_OFFSET
    HOUGH_SIZE = 600
    HOUGH_INPUT = gray_blurred[OFFSET:OFFSET + HOUGH_SIZE, OFFSET:OFFSET +
HOUGH_SIZE]

    circles = cv2.HoughCircles(
        HOUGH_INPUT, cv2.HOUGH_GRADIENT,
        self.HOUGH_DP, self.HOUGH_MIN_DIST,
        param1=self.HOUGH_PARAM1, param2=self.HOUGH_PARAM2,
        minRadius=self.MIN_RADIUS, maxRadius=self.MAX_RADIUS
    )

    best_circle_data = None
    min_dist_to_center = float('inf')

    # ❶ 중앙에 가장 가까운 원 선택
    if circles is not None:
        circles = np.uint16(np.around(circles))
        for i in circles[0, :]:
            x_relative, y_relative, r = i[0], i[1], i[2]
            x = x_relative + OFFSET
            y = y_relative + OFFSET
            dx_px = float(x - self.CENTER_PX[0])
            dy_px = float(y - self.CENTER_PX[1])
            dist_px = math.sqrt(dx_px**2 + dy_px**2)
            if dist_px < min_dist_to_center:
                min_dist_to_center = dist_px
                best_circle_data = (x, y, r, 1.0)

```

```

# ❷ 결과 처리
if best_circle_data is not None:
    x, y, r, _ = best_circle_data

    # EMA 안정화
    if self.prev_center is None:
        self.prev_center = np.array([x, y], dtype=float)
        self.prev_radius = r
    else:
        self.prev_center = (1 - self.alpha) * self.prev_center +
self.alpha * np.array([x, y])
        self.prev_radius = (1 - self.alpha) * self.prev_radius +
self.alpha * r

    x, y = self.prev_center
    r = self.prev_radius

    # 🟠 원 내부 오렌지 비율 계산
    mask = np.zeros(frame.shape[:2], dtype=np.uint8)
    cv2.circle(mask, (int(x), int(y)), int(r), 255, -1)
    orange_mask = cv2.inRange(frame, self.ORANGE_MIN, self.ORANGE_MAX)
    orange_inside = cv2.bitwise_and(orange_mask, orange_mask,
mask=mask)
    orange_ratio = np.sum(orange_inside > 0) / np.sum(mask > 0)
    rospy.loginfo_throttle(1.0, f"🟠 Orange ratio inside circle:
{orange_ratio*100:.2f}%")


    # === 픽셀 → mm 변환 ===
    dx_px = float(x - self.CENTER_PX[0])
    dy_px = float(y - self.CENTER_PX[1])
    dx_mm = dx_px * self.scale_x
    dy_mm = dy_px * self.scale_y
    dist_mm = math.sqrt(dx_mm**2 + dy_mm**2)

    # === 카메라 오프셋 보정 ===
    dx_mm_total = -dy_mm + self.CAMERA_OFFSET_X_MM
    dy_mm_total = -dx_mm + self.CAMERA_OFFSET_Y_MM

    if dist_mm <= self.CENTER_TOL_MM and orange_ratio >
self.ORANGE_RATIO_THRESH:
        cv2.circle(output, (int(x), int(y)), int(r), (0, 255, 0), 2)
        cv2.circle(output, (int(x), int(y)), 5, (0, 0, 255), -1)
        cv2.circle(output, self.CENTER_PX, 5, (255, 0, 0), -1)

    # --- ✅ 화면 표시 부분 수정 (X offset 적용된 값 표시)
    cv2.putText(output, f"dx={dx_mm:.1f} dy={dy_mm:.1f} OR=

```

```

{orange_ratio*100:.1f}%" ,
(25,45), cv2.FONT_HERSHEY_SIMPLEX, 0.8, (0,255,0),
2)
cv2.putText(output, f"XOFF -> dx={dx_mm_total:.1f} dy=
{dy_mm_total:.1f}" ,
(25,85), cv2.FONT_HERSHEY_SIMPLEX, 0.8,
(255,255,0), 2)

# 퍼블리시
self.detection_pub.publish(Point(x=float(dx_mm_total),
y=float(dy_mm_total), z=float(r)))
rospy.loginfo_throttle(1.0, f"✓ Valid Circle + Orange: dx=
{dx_mm_total:.1f}, dy={dy_mm_total:.1f}")
else:
    rospy.logwarn_throttle(1.0, f"⚠ Circle ignored (dist=
{dist_mm:.1f}mm, orange={orange_ratio*100:.1f}%)")
    self._publish_fail()
else:
    rospy.logwarn_throttle(1.0, "✗ No circle found.")
    self._publish_fail()

# 3 시각화
cv2.rectangle(output, (OFFSET, OFFSET), (OFFSET + HOUGH_SIZE, OFFSET +
HOUGH_SIZE), (255, 0, 0), 2)
cv2.imshow("Stable Orange Detection (Gray + Orange Filter)", output)
cv2.imshow("Hough Filtered Input", gray_blurred)
cv2.imshow("Orange Mask Inside Circle", orange_inside)
cv2.waitKey(1)

# -----
def _publish_fail(self):
    self.detection_pub.publish(Point(x=0.0, y=0.0, z=0.0))

# -----
if __name__ == '__main__':
    try:
        StableGrayDetectionNode()
        rospy.spin()
    except rospy.ROSInterruptException:
        cv2.destroyAllWindows()

```

yellow\_bracket\_detection\_node.py

```

#!/usr/bin/env python3
# -*- coding: utf-8 -*-

```

```

import rospy, cv2, numpy as np, os, math
from sensor_msgs.msg import Image
from cv_bridge import CvBridge
from geometry_msgs.msg import Point

class StableRedDetectionNode:
    def __init__(self):
        rospy.init_node('stable_red_detection_node', anonymous=True)
        self.bridge = CvBridge()
        self.detection_pub = rospy.Publisher('/red_detection/result', Point,
queue_size=1)
        self.image_sub = rospy.Subscriber("/camera/image_raw", Image,
self.image_callback)

        # =====
        # 폴더 카메라 캘리브레이션 결과 불러오기
        # =====
        calib_path =
"/home/kiminyeop/catkin_ws/src/ur_python/src/dataset_bra2_checkboard3/circlegr
id_calibration_results_8x6_20mm.npz"
        if os.path.exists(calib_path):
            data = np.load(calib_path)
            self.camera_matrix = data["camera_matrix"]
            self.dist_coeffs = data["dist_coeffs"]
            rospy.loginfo(f" CAMERA Calibration loaded from: {calib_path}")
        else:
            rospy.logwarn(⚠ Calibration file not found - skipping
undistortion.)
            self.camera_matrix = None
            self.dist_coeffs = None

        # =====
        # ROI 및 화면 설정
        # =====
        self.ROI_WIDTH = 400
        self.ROI_HEIGHT = 400
        self.TARGET_SIZE = (1200, 1200)
        self.CENTER_PX = (600, 600)

        # =====
        # Red HSV 임계값
        # =====
        # Yellow detection (Hue 20~32)
        self.lower_red1 = np.array([20, 120, 120])
        self.upper_red1 = np.array([32, 255, 255])

```

```

# Not used for yellow, but placeholder to avoid errors
self.lower_red2 = np.array([0, 0, 0])
self.upper_red2 = np.array([0, 0, 0])

# =====
# Morphology 커널
# =====
self.kernel = np.ones((5,5), np.uint8)

# =====
# px → mm 변환 비율 (실험값)
# =====
self.scale_x = 0.1435 # mm/px
self.scale_y = 0.1425 # mm/px

# =====
# 카메라 오프셋 (Tool0 기준)
# =====
self.CAMERA_OFFSET_X_MM = 89.0    # X축 방향 (mm)
self.CAMERA_OFFSET_Y_MM = 4.0      # Y축 방향 (mm)

# =====
# 기울기 보정 (deg)
# =====
self.roll_tilt_deg = 0.0    # x축 방향 (좌우)
self.pitch_tilt_deg = 0.0    # y축 방향 (앞뒤)

# =====
# 지수평활 필터 (EMA)
# =====
self.prev_center = None
self.prev_radius = None
self.alpha = 0.35

rospy.loginfo("🔴 Stable Red Detection Node initialized (Calibrated + 82 mm offset + tilt correction)")

# -----
# 📹 메인 콜백
# -----
def image_callback(self, msg):
    try:
        frame = self.bridge.imgmsg_to_cv2(msg, "bgr8")

        # === 📸 왜곡 보정 적용 ===

```

```

        if self.camera_matrix is not None and self.dist_coeffs is not
None:
            frame = cv2.undistort(frame, self.camera_matrix,
self.dist_coeffs)

            # === 중앙 ROI 자르기 ===
            H, W = frame.shape[:2]
            x1 = int(W/2 - self.ROI_WIDTH/2)
            y1 = int(H/2 - self.ROI_HEIGHT/2)
            cropped = frame[y1:y1+self.ROI_HEIGHT, x1:x1+self.ROI_WIDTH]

            # === 1200x1200 확대 ===
            resized = cv2.resize(cropped, self.TARGET_SIZE,
interpolation=cv2.INTER_LINEAR)

            # === 빨간 원 검출 ===
            self.red_detect(resized)

    except Exception as e:
        rospy.logerr(f"Red Detection Error: {e}")

# -----
# ● 빨간 원 검출
# -----
def red_detect(self, frame):
    # --- 영상 안정화 대기 (1 초) ---

    hsv = cv2.cvtColor(frame, cv2.COLOR_BGR2HSV)
    mask1 = cv2.inRange(hsv, self.lower_red1, self.upper_red1)
    mask2 = cv2.inRange(hsv, self.lower_red2, self.upper_red2)
    mask = cv2.bitwise_or(mask1, mask2)
    mask = cv2.morphologyEx(mask, cv2.MORPH_CLOSE, self.kernel,
iterations=2)
    mask = cv2.morphologyEx(mask, cv2.MORPH_OPEN, self.kernel,
iterations=1)
    mask = cv2.GaussianBlur(mask, (9,9), 2)

    circles = cv2.HoughCircles(mask, cv2.HOUGH_GRADIENT, dp=1.2,
minDist=190,
                                param1=100, param2=25, minRadius=210,
maxRadius=430)
    output = frame.copy()

    if circles is not None:
        circles = np.uint16(np.around(circles))[0]
        x, y, r = max(circles, key=lambda c: c[2])

```

```

# === EMA 안정화 ===
if self.prev_center is None:
    self.prev_center = np.array([x, y], dtype=float)
    self.prev_radius = r
else:
    self.prev_center = (1 - self.alpha) * self.prev_center +
self.alpha * np.array([x, y])
    self.prev_radius = (1 - self.alpha) * self.prev_radius +
self.alpha * r

x, y = self.prev_center
r = self.prev_radius

# === 픽셀 → mm 변환 ===
dx_px = float(x - self.CENTER_PX[0])
dy_px = float(y - self.CENTER_PX[1])
dx_mm = dx_px * self.scale_x
dy_mm = dy_px * self.scale_y

# === 기울기 보정 ===
pitch_rad = math.radians(self.pitch_tilt_deg)
roll_rad = math.radians(self.roll_tilt_deg)
dx_mm_corr = dx_mm / math.cos(pitch_rad)
dy_mm_corr = dy_mm / math.cos(roll_rad)

# === 오프셋 적용 (카메라 → Tool 기준) ===
dx_mm_total = -dy_mm_corr + self.CAMERA_OFFSET_X_MM
dy_mm_total = -dx_mm_corr + self.CAMERA_OFFSET_Y_MM

# === 시각화 ===
cv2.circle(output, (int(x), int(y)), int(r), (0, 255, 0), 2)
cv2.circle(output, (int(x), int(y)), 5, (0, 0, 255), -1)
cv2.circle(output, self.CENTER_PX, 5, (255, 0, 0), -1)
cv2.putText(output, f"dx={dx_mm_total:.1f} mm, dy=" +
{dy_mm_total:.1f} mm",
            (25, 45), cv2.FONT_HERSHEY_SIMPLEX, 1, (0, 255, 0), 2)

# === 퍼블리시 ===
point_msg = Point(x=float(dx_mm_total), y=float(dy_mm_total),
z=float(r))
self.detection_pub.publish(point_msg)
rospy.loginfo(f"published: dx={dx_mm_total:.1f} mm, dy=" +
{dy_mm_total:.1f} mm, r={r:.1f}")
else:
    self.detection_pub.publish(Point(x=0.0, y=0.0, z=0.0))

```

```
        rospy.logwarn("✖ Red circle not found, publishing (0,0,0)")

        cv2.imshow("Stable Red Detection (Tilt-corrected + 82 mm offset)",
output)
        cv2.imshow("mask", mask)
        cv2.waitKey(1)

# -----
# 🚀 실행부
# -----

if __name__ == '__main__':
    try:
        StableRedDetectionNode()
        rospy.spin()
    except rospy.ROSInterruptException:
        cv2.destroyAllWindows()
```