

# **UNIVERSITY OF MORATUWA**

Faculty of Engineering



Registered Module No: EN3992

## **INDUSTRIAL TRAINING REPORT**

LE Robotics (Pvt.) Ltd.

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# Preface

This report was composed as partial fulfillment of the requirements of Module EN3992 - Industrial Training, in the curriculum of B.Sc. in Engineering (Electronic and Telecommunication) at the University of Moratuwa, Sri Lanka. The experience and knowledge that I gained during the six months of my industrial training were used and were the inspiration to create this report.

# Acknowledgment

I would like to gratefully acknowledge all of the people who helped me to make this six months of special industrial training period a massive success, starting from the point of applying to a company to the point I left the training organization at the completion of six months.

First of all, I would like to express my heartfelt gratitude to Professor Kapila Jayasinghe who was our supervisor for us throughout the six months of the internship period. The advice he provided us with regard to professional engineering practices and ethics was invaluable. In addition to that the directions he provided us to gain the required technical skills required for the allocated project were priceless. I believe the mindset that he built in us, towards working under minimum supervision, will be a massive support for us to thrive in the fast-moving industry.

Next, I would like to express my gratitude toward Miss. Laknie Jayasinghe who was the Engineer in charge of us in our training period. The support she provided us to improve our soft skills as well as technical skills as a professional engineers, is highly appreciated. The support she provided when composing the technical documentation of my allocated task by pointing out the mistakes and the areas of improvement was invaluable and must be mentioned at this point. Moreover, her support in validating the project deliveries at the end of the training period is highly appreciated.

Last but not least, I would like to express my heartiest gratitude to Mr Janka Kulathunga, the manager of the Lanka Electronics research and development section and Mr Aloka Perera, an electronic engineer in LE Robotics (Pvt.) Ltd for being available for us whenever we needed their support.

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*\*PDF is clickable*

# List of Abbreviations

**CV** Computer Vision

**FOV** Field of View

**GUI** Graphical User Interface

**OOP** Object Oriented Programming

**R&D** Research and Development

**ROI** Region of Interest

**RPi** Raspberry Pi

**SCARA** Selective Compliance Articulated Robot Arm

**SE** Software Engineering

**SFTP** SSH(Secure shell) File Transfer Protocol

**SIFT** Scale Invariant Feature Transform

**SVM** Support Vector Machine

**UART** Universal Asynchronous Receiver/Transmitter

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# Chapter 1

## Description of the organization and business, its past, present and future

For my special industrial training, I got the opportunity to work as an engineering trainee at LE Robotics (Pvt.) Ltd. located at 100/4, Divulapitiya Road, Minuwangoda, Sri Lanka. It is a local Research and Development (**R&D**) facility where they work on industrial articulated robot arms and related technologies. This chapter provides an extensive description of the organization and business as well as information about its past, present and future.

### 1.1 Organization and Business

#### 1.1.1 Introduction

LE robotics (Pvt.) Ltd. is a local **R&D** facility that has been established by Prof. J.A.K.S. Jayasinghe who is a senior professor in the Department of Electronic and Telecommunication Engineering at the University of Moratuwa in Sri Lanka.

LE robotics (Pvt.) Ltd. is the first in the Sri Lankan market to offer fully customisable robotics solutions ‘Made in Sri Lanka’ for various automation needs for an affordable price with expertise based in Sri Lanka. In the year 2005, the company designed and manufactured the first custom robotics solution in their affiliated company, Lanka Electronics (Pvt.) Ltd. Since then, they have been developing various robotics solutions and related technologies in the facility.

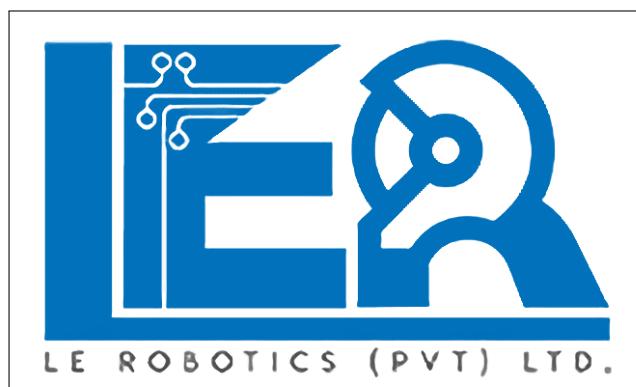


Figure 1.1: Logo of the LE Robotics (Pvt.) Ltd.

## 1.1.2 Services and Products

As mentioned previously LE Robotics Pvt. Ltd. provides services and tailor-made products for various automation needs of its customers. When it comes to the services they provide, the following key services can be highlighted.

1. Process Analysis to identify the automation needs and challenges of organizations
2. Product customization to provide the best tailor-made solution for requirements
3. Providing local expertise with ease of access
4. Providing lifetime support for the products

In addition to the services they provide, the following products are manufactured at LE Robotics Pvt. Ltd. **R&D** of the related technologies of those products is a key activity among the day-to-day activities in the facility.

1. **6 DOF Robots** - Robots with six degrees of freedom (Figure 1.2 depicts such a model)
  - Robotics solutions with the capability to mimic human arm operations
  - Offers the flexibility to provide you with fully customized robotic movements to suit your requirement
  - Around 1 m reach and 0.1 mm placement precision

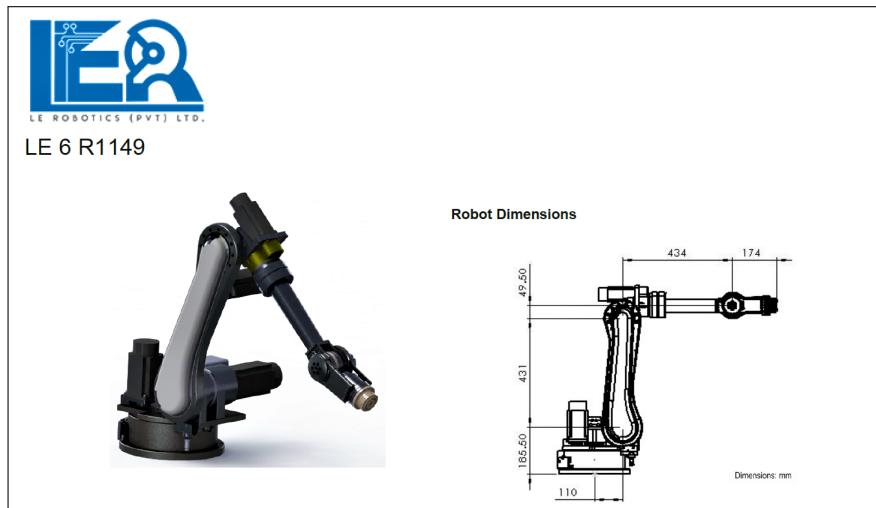


Figure 1.2: Model *LE 6 R1149* 6-DOF articulated robot arm[1]

2. **4 DOF Robots** - Robots with four degrees of freedom (Figure 1.3 depicts such a model)
  - Robotics solutions with superior high-speed performance, high rigidity and high accuracy
  - Array of options with a compact design
  - Around 500 mm reach and 0.1 mm placement precision

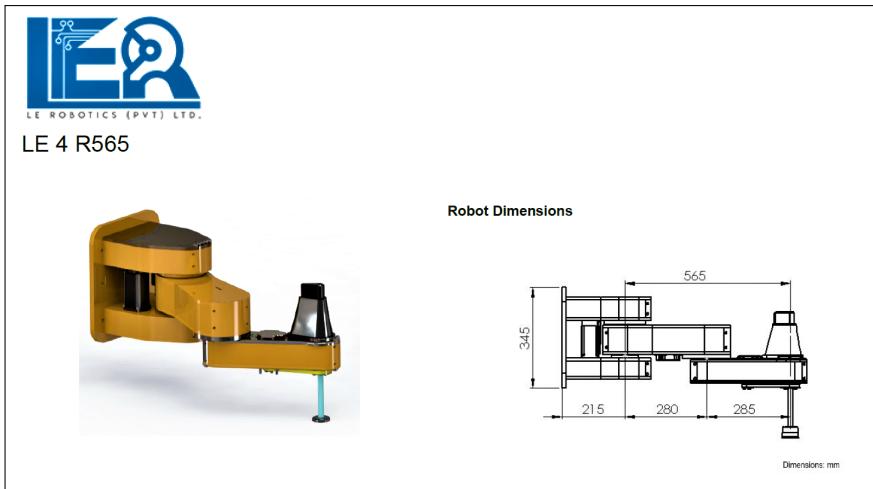


Figure 1.3: Model *LE 4 R565* 4-DOF SCARA robot arm[2]

### 3. Custom Made Robots - Robots designed according to the customer's needs

- Reach and Payload specifications are possible to be customized as per your process requirements
- Robotics Solutions to carry out simple pick and place operations

## **Chapter 2**

### **Description of familiarization work carried out**

# **Chapter 3**

**Exposure to systems (HSE, Financial,  
Administration, Logistics, etc.)**

# Chapter 4

## Project Work

By title, the project that I was assigned, was ***Machine vision based Real-time Motion Planning for an Industrial Articulated Robot Arm***. In simple words, it was a project related to an automatic pick and place machine which can be used to pick objects placed on a conveyor belt and pass them to the next stage of processing.

My contribution to that project was to develop the following three aspects of the system.

- I. Development of an object detection framework
- II. Development of an application for camera calibration (referred as *Camera Calibrator GUI* in this document)
- III. Development of an application to train an object classification model (referred as *Classifier Trainer GUI* in this document)

Subsequent sections explain the mentioned sub-projects that were undertaken by me during the industrial training period. Implementation details are not exposed in this report as it does not comply with professional engineering ethics.

## 4.1 Development of an Object Detection Framework

The first project, that I was assigned as a trainee electronic engineer was related to the **CV** field. In this project, an Object Detection Framework was developed to be deployed in an Automatic Pick and Place Machine. In a summary, the framework is capable of identifying Region of Interest (**ROI**), detecting and classifying objects, and determining the location and orientation of objects with respect to a real-world coordinate system for grasping (picking). This section explains everything related to the development of that framework.

### 4.1.1 Problem Definition

Most of the robotic arms used in industrial environments operate in a pre-programmed cycle. When it comes to the way a human does the same task is much different as the path planning for picking an object may change from cycle to cycle because of the perception obtained through human vision. **CV** is the technology and methods incorporated to mimic the human vision in order to gain insights into the operating environment of the robotics system.

When it comes to real-time object detection using **CV**, there is an inevitable trade-off between the accuracy and the speed of the operation. This depends entirely on the used **CV** algorithms and the computational power of the available hardware. If the robotic system/ arm in interest is not controlled through a dedicated industrial PC with adequate computational resources, the amount of resources that can be allocated to the **CV** unit becomes limited. This will eventually result in great delays (which is not desirable when it comes to real-time operations) to produce the required outputs by processing the acquired images through the associated camera.

Due to the limitations in the resources, the initial problem of real-time object detection on a moving conveyor was subdivided into three problems.

- **Case 1:** Detection of objects placed in a *static environment* (no conveyor belt is associated). Picking and placing is carried out by the robot in the usual way.
- **Case 2:** Detection of objects placed on a *non-continuous conveyor belt*. The conveyor belt can be paused when objects are detected and picking and placing is carried out thereafter.
- **Case 3:** Detection of objects placed on a *continuously moving conveyor belt*. Picking and placing happen while the conveyor is moving.

### 4.1.2 Solution

As the initial stage of the project, case 1 mentioned in Section 4.1.1 was developed. It consisted of developing a **CV** subsystem for detecting *stationary objects* placed in a *static environment*. In this case, no conveyor belt is used and objects are placed in the Field of View (**FOV**) of the camera.

Figure 4.1 shows the interconnection between inputs and outputs of the developed system. Once the video stream from a camera is fed into the system, it is capable of,

1. Determining the grasping location of an object in a real-world coordinate system. The centroid of the 2D view of the object was considered as the grasping location.

2. Determining the gripper's angle. Orientation of object with respect to the positive x direction of the same real-world coordinate system was used for this.
  3. Determining the class/ type of the detected objects using a Scale Invariant Feature Transform ([SIFT](#)) and Support Vector Machine ([SVM](#)) based classification algorithm.
- and providing them to the main controller of the pick and place machine as requested by it.

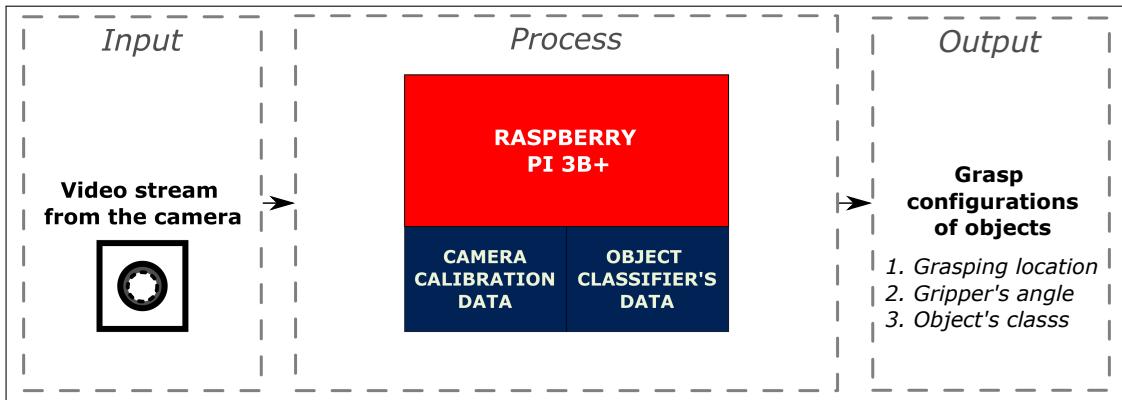


Figure 4.1: Interconnection between inputs and outputs of the [CV](#) subsystem

Figure 4.2 depicts the interconnections between the existing robot controller and the newly developed computer vision subsystem. Outputs shown in Figure 4.1 are provided to the robot controller through a serial communication link built using an Universal Asynchronous Receiver/Transmitter ([UART](#)) circuitry. For transferring data to the Raspberry Pi from the working PC, SSH(Secure shell) File Transfer Protocol ([SFTP](#)) over Wi-Fi technology was used.

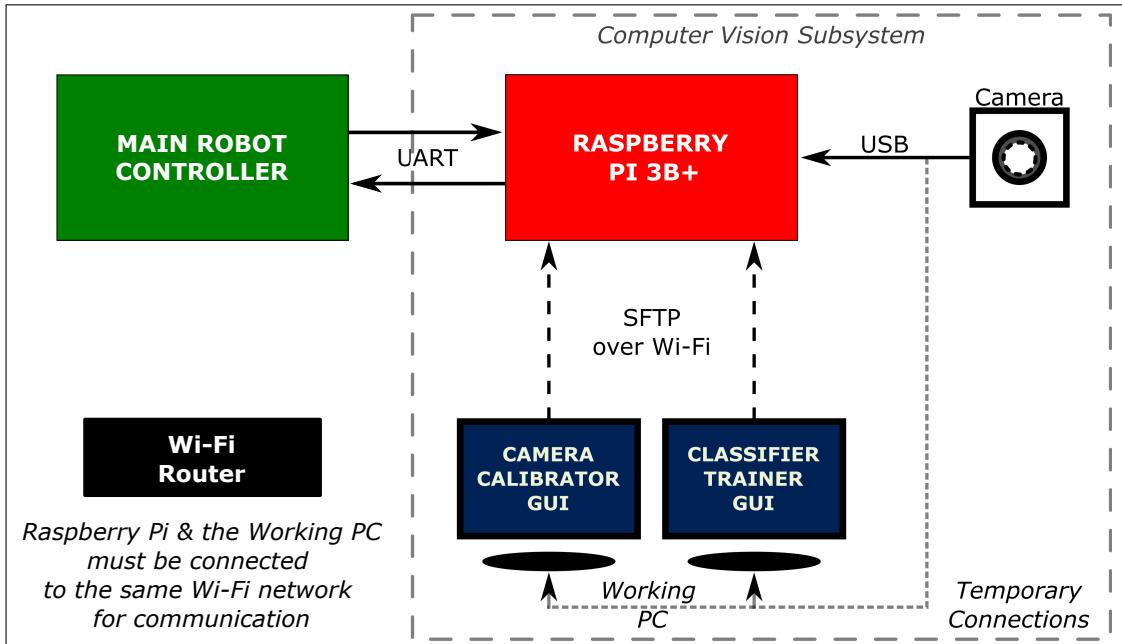


Figure 4.2: Interconnections between the existing robot controller and the [CV](#) subsystem

For the implementation of the prototype, third-party tools given below are used.

**1. Raspberry Pi (RPi) 3 B+ Single Board Computer (SBC)**

*Product brief:* Online available at <https://datasheets.raspberrypi.com/rpi/3/raspberry-pi-3-b-plus-product-brief.pdf>.

**2. Logitech C310 HD Webcam, 720p Video**

*Technical specifications:* Online available at <https://support.logi.com/hc/en-us/articles/360023464573-Logitech-HD-Webcam-C310-Technical-Specifications>.

**3. OpenCV open source computer vision library stable release 4.4.0[5]**

*Stable and development releases:* Online available at <https://github.com/opencv/opencv>; A pre-compiled version of this library, which is optimized for **CV** and Deep Learning on Raspberry Pi was used.

**4. Gordon's Arduino wiring-like WiringPi Library for the Raspberry Pi[7]**

*Unofficial Mirror for WiringPi bindings:* Online available at <https://github.com/WiringPi/WiringPi>.

During the operation of the pick and place robot, the developed object detection algorithm runs only inside the **RPi**. However, for the operation of that algorithm, it requires the data shown in Table 4.1. A Windows **GUI** was developed to generate those data and the ‘Description’ column of Table 4.1 provides only a simple overview of that data . Subsequent sections explain the functionality and the working principles of the mentioned **GUI**, in detail.

TABLE 4.1  
DATA FILES REQUIRED TO RUN THE OBJECT DETECTION  
FRAMEWORK

File Name	Description
calibration_data.xml	This file includes camera calibration data. That is, intrinsic and extrinsic parameters of the associated camera.
objects_data.xml	This file includes object classification model’s data. That is, the data required for the object classification (class names, trained support vector machines and etc.).

## 4.2 Development of an Application for Camera Calibration

The second project, that I was assigned as a trainee electronic engineer was related to the Software Engineering (**SE**) field. In this project, a Windows **GUI** was developed to calibrate a given camera. In a summary, the application is capable of generating the required data, to remove the distortions of captured images and to transform 2D image points back to a given 3D real-world coordinate system with an accuracy of  $\pm 0.5\text{ mm}$ .

### 4.2.1 Problem Definition

The end goal of the **CV** subsystem mentioned in the Section 4.1.2 is to provide the location and orientation of the identified objects, with respect to a known real-world coordinate system. However, when an image is captured, the details about the depth of the object relative to the camera are lost due to the real world to image plane transformation (the forward projection [6]) happens inside the camera. This operation is non-invertible.

There are several methods used in **CV** literature to back-project image plane coordinates to the real-world coordinate system. In this project, a method which uses a single calibrated camera and analytic geometry was implemented. It was observed that the back-projected coordinates are accurate at least to  $\pm 0.5\text{ mm}$ . As mentioned for this back-projection process, a *calibrated camera* is required and the rest is engineering mathematics. Therefore, the actual problem to be solved was to calibrate the camera associated with the pick and place machine.

### 4.2.2 Solution

Camera Calibration refers to the extraction of various parameters related to the camera that will be used to capture the video stream/ images. These parameters are required when the back-projection is done. For the camera calibration, the method that uses an asymmetric chess board was used[3]. Because that method was really simple and could be implemented easily using the resources that were available in the facility.

The important input data needed for calibration of the camera is a set of 3D real world points and the corresponding 2D coordinates of these points in the image. 3D points are called object points and 2D image points are called image points.

- I. **2D Image Points:** These points can be easily found from the images. These image points are the locations where two black squares touch each other in chess board. Functions in OpenCV is used to extract those points[3].
- II. **Object Points:** For simplicity, the chess board was kept stationary at XY plane, (so Z=0 always) and camera was moved accordingly. This consideration helps us to find only X,Y values. Now for X,Y values, we can simply pass the points as (0,0,0), (1,0,0), (2,0,0), ... which denotes the location of points. In this case, the results we get will be in the scale of size of chess board square[3]. But if we know the square size, (for our implementation square size of the chess board was 30 mm), we can pass the values as (0,0,0), (30,0,0), (60,0,0).

The process of camera calibration is given below. Once the camera calibration is done, we will be able to extract the intrinsic and extrinsic parameters of a given camera. Those parameters

can then be used for back-projection which was my problem at hand.

1. Keep the chess board stationary in the XY plane of the real world coordinate system as shown in the Figure 4.3 and do not let it move due to any reason.

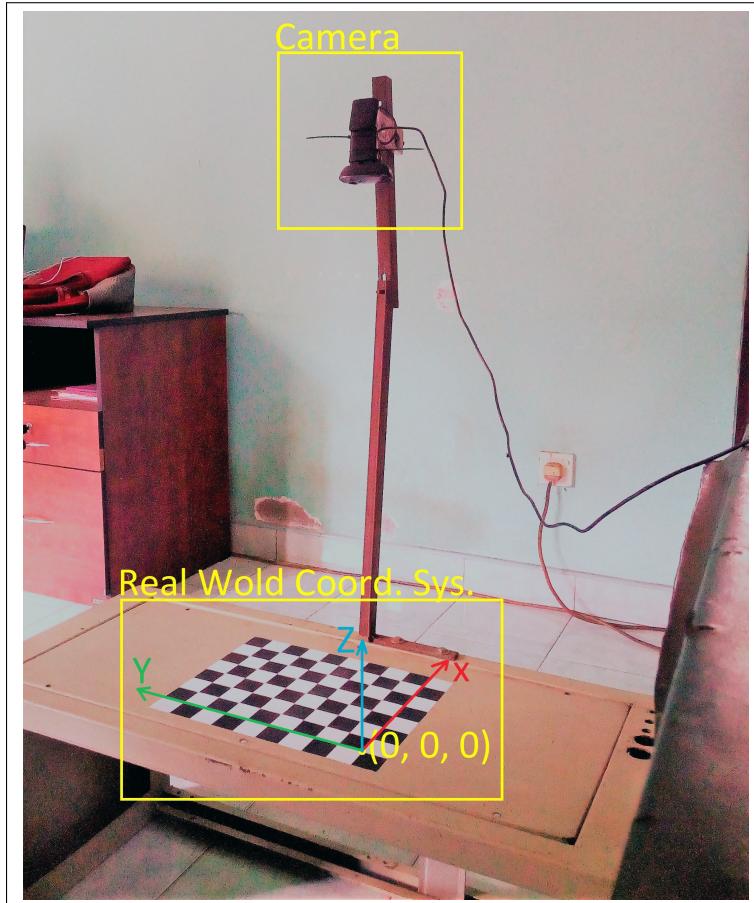


Figure 4.3: Real world coordinate system and the position of the camera with respect to it.

2. Capture about 10-15 images (higher the better) as shown in the Figure 4.4 using the camera that will be used for object detection, in several distances and orientations.

The actual number of required images is around 6. However, in some scenarios OpenCV is unable to detect the chess board pattern properly in every image. Two of such reasons are given below.

- **Only a part of the chessboard is visible in the captured image:** For the program to work, whole chessboard must be visible in the captured image.
- **No proper lighting conditions:** if the environment that the chessboard is placed, does not have proper lighting conditions application will not work as expected. Therefore make sure that the chessboard pattern receives enough light.

Hence, it's better to capture images more than the required amount so that we can filter out damaged/ useless images later.

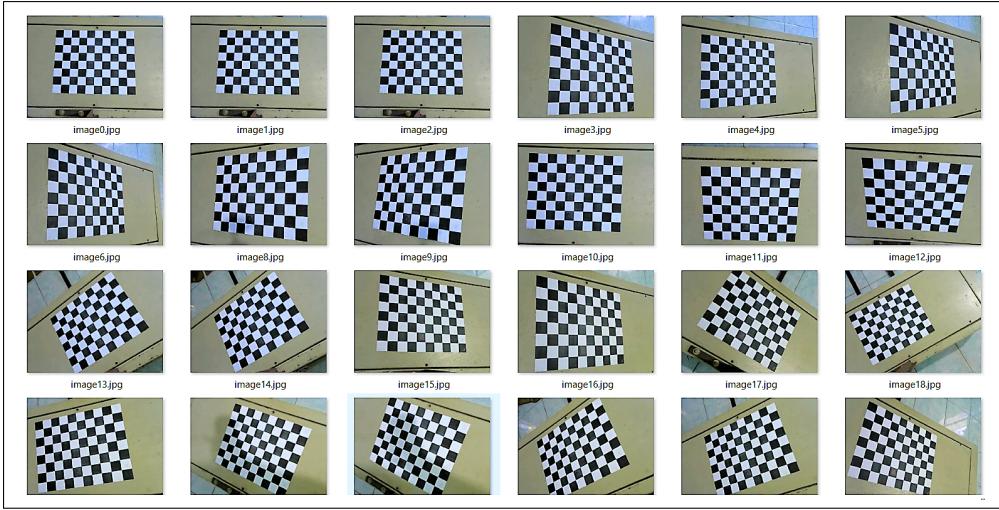


Figure 4.4: Raw images captured by placing the camera in various distance and orientations

3. Capture one additional special image, placing the camera in the place that it will be mounted when the actual object detection algorithm runs. Extrinsic parameters[6] corresponding to this image will be directly used in our Back-projection algorithm.

Extrinsic parameters contains a translation vector and a rotation matrix. These two together brings the calibration pattern from the object coordinate space (in which object points are specified) to the camera coordinate space. In more technical terms, the rotation matrix and translation vector performs a change of basis from object coordinate space to camera coordinate space. Due to its duality, it is equivalent to the position of the calibration pattern with respect to the camera coordinate space [4].

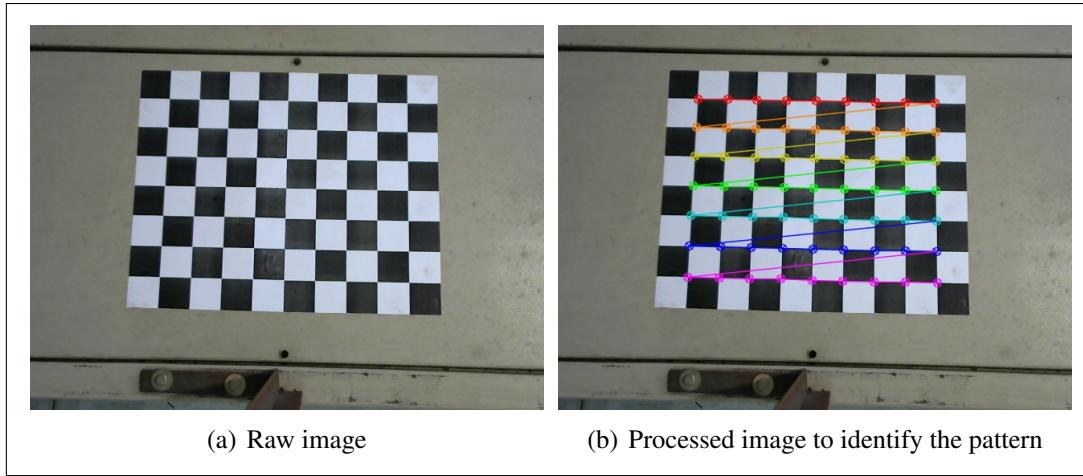


Figure 4.5: Captured special image to extract the extrinsic parameters that are useful for back-projection

4. Use all of the captured images to calibrate the camera. The necessary documentation of the used functions are explained in [4]. After carrying out those functions you will be

able to extract the extrinsic and intrinsic parameters related to the special image and the camera respectively.

Extracted intrinsic parameters which are specific to the used camera, do not depend on the image. Among those parameters, *Camera Matrix* is what has the greatest importance. *Radial/Tangential Distortions* have a minimal importance and therefore can be neglected. Extracted extrinsic parameters of the image shown in Figure 4.5 are specific for that image. If in any case, orientation or the place of the camera is altered, these must be recalculated in order to be used in the back-projection algorithm.

As mentioned previously ultimate goal of this sub project was to develop a **GUI** application for camera calibration. The process mentioned above was therefore implemented in C# programming language using ‘Visual Studio 2019’ software. For the implementation, the *Emgu CV* library which is a cross platform .Net wrapper to the OpenCV image processing library was also used. It allows OpenCV functions to be called from .NET compatible languages like C# and therefore make the software development process efficient. The developed **GUI** is shown in the Figure 4.6.

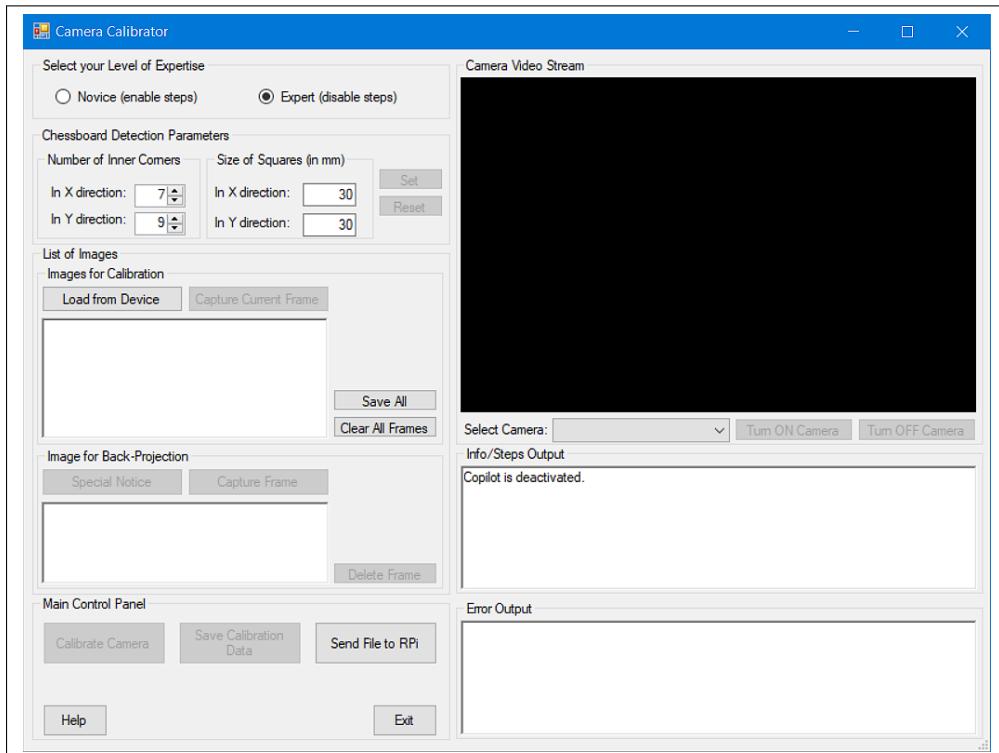


Figure 4.6: Camera calibrator **GUI** for Windows

### **4.3 Development of an Application to Train an Object Classification Model**

# **Chapter 5**

## **Hands on experiences**

# **Chapter 6**

## **Soft Skills Development**

# **Chapter 7**

## **SWOT Analysis of the organization and self**

# **Chapter 8**

**Conclusion: Own perspective of areas to be improved (of the whole training process including self)**

# **Appendices**

# **Appendix A**

## **Guidelines**

# References

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