Programming Assignments 1 & 2 601.455 and 601/655 Fall 2023
Please also indicate which section(s) you are in (one of each is OK)

Score Sheet

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Grade Factor		
Program (40)		
Design and overall program structure	20	
Reusability and modularity	10	
Clarity of documentation and programming	10	
Results (20)		
Correctness and completeness	20	
Report (40)		
Description of formulation and algorithmic approach	15	
Overview of program	10	
Discussion of validation approach	5	
Discussion of results	10	
TOTAL	100	

Question 1

Algorithm of Approach

For this question, we were told to develop (or develop proficiency with) a Cartesian math package for 3D points, rotations, and frame transformations. The programming language we chose to implement our assignment in is Python, so we searched for packages in this language. We chose to use the "pytransform3d" package, which is available open source on Github with a fully documented API.[1] This package includes rotation matrices, quaternions, transformation matrices, and a transform manager class, which stores various frames by name and automatically allows for conversion between any of the stored frames, as long as they are connected. We also developed our own class, called "Point," which stores the x, y, and z coordinates of a point in a way that is intuitive to access.

Structure of Program

We made use of the following methods:

from pytransform3d.transformations._conversions:

transform_from(R, p)

- This method creates and returns a 4x4 transformation matrix from a rotation matrix R and transformation vector p
- We had to make a change in check_transform helper method from np.float to just float due to a bug caused by np no longer supporting its own data types

from pytransform3d.transformations._transform_operations;

transform(A2B, PA)

- This method takes a transformation matrix A2B and transforms a point or group of points PA, then returns the transformed point(s)

The Point class that we wrote stores the x, y, and z coordinates of a point as class attributes. This allows for more easily readable code, because point coordinates can be accessed by writing [pointName].z, for example. However, the pytransform3d package treats points as array-like objects. As such, we included a "to_array" method in the Point class in order to use our Point class with the downloaded package. This method converts the 3 coordinates into a 1x3 array, with each array value being the x, y, and z coordinate, respectively.

Validation of Approach

We created a test suite for this problem called test_Point. The test suite followed official Python unit testing guidelines.[2]

test_Point has five test methods:

- Test that when a Point is initialized without parameters, the default coordinates are (0, 0, 0)
- Test that when a Point is initialized with parameters, the coordinates are set to the ones that were passed in the initialization

- Test that the output of the to_array() method is a 1x3 array [x, y, z]
- Test changing the coordinates of the Point manually through point.x = new_x
- Test the from_array() method correctly updates the point coordinates

The pyratransform file we used the methods from had pre written tests for rotations and transformations. We checked over the validity of these tests and verified that they worked paying close attention to the methods we used.

Discussion of Results

We found that this method worked as expected since our test cases passed successfully and the test cases written in the pyratransform package did as well. The test_point class file was submitted to show how our PointClass class successfully works with the imported pyratransform.

Question 2

Algorithm of Approach

To develop a 3D point set to 3D point set registration algorithm, we chose to follow Arun's approach[3]. Following slide 17 in the "Point cloud to point cloud rigid transformations" class slides, we began by calculating H.

$$\mathbf{H} = \sum_i \begin{bmatrix} \tilde{a}_{i,x}\tilde{b}_{i,x} & \tilde{a}_{i,x}\tilde{b}_{i,y} & \tilde{a}_{i,x}\tilde{b}_{i,z} \\ \tilde{a}_{i,y}\tilde{b}_{i,x} & \tilde{a}_{i,y}\tilde{b}_{i,y} & \tilde{a}_{i,y}\tilde{b}_{i,z} \\ \tilde{a}_{i,z}\tilde{b}_{i,x} & \tilde{a}_{i,z}\tilde{b}_{i,y} & \tilde{a}_{i,z}\tilde{b}_{i,z} \end{bmatrix}$$

To calculate H, we needed to first find a-tilde and b-tilde. On slide 31 of the same powerpoint, a-tilde-i and b-tilde-i are defined as (vector_ai) - (mean of a) and (vector_bi) - (mean of b). We then summed over the number of points, following the multiplication outlined in each step the formula for H, to get our H matrix. Then, we took the singular value decomposition of H to get U, S, and V_transform. We computed R as the product of V and U_transform. To verify the algorithm worked, we checked if the determinant of R was equal to 1. If the algorithm failed, we followed the process outlined in Arun's paper of inverting the sign of v3 in V = [v1 v2 v3] so our new value of V would be [v1 v2 -v3][3] and found our new R the same way as before, from the product of V and U_transform.

Once we verified we had the correct R, we found vector_p = mean of b - R * mean of a ("Point cloud to point cloud rigid transformations" slide 31).

Structure of Program

We created a point set registration class. In this class, we have a method initializing the point set, a method to find the registration (our main method), a method to check the rotation algorithm, and a method to find the translation. The method that checks the rotation algorithm checks if the determinant of R is equal 1 and if it isn't, it provides the necessary adjustments and returns the correct R. The method to find the translation, finds the p_vector from the a and b pointsets and R.

The method to find the registration calls the previous 2 methods mentioned and takes in the 2 point clouds to return R and p_vector. To find the H vector as mentioned in the algorithm, we use a for loop to iterate over all the a_tilde and b_tilde. To find the singular value decomposition, we call the numpy linalg svd function[4]. Other pre-defined numpy functions we call are transpose, numpy dot (for multiplying), and numpy det (for finding the determinant). We wrote our own mean method to find the correct midpoint of the vectors.

We also wrote a method when checking the determinant called is_almost_one. During testing we found that the determinant was being calculated as .999 as opposed to 1 and this was causing our algorithm to fail and rerun to find a new rotation matrix even though the previous R was correct. This new method fixed this error by checking if the determinant was almost 1, meaning that the algorithm worked correctly.

Validation of Approach

To test our method, we wrote a test file named testRegistration.py. In this file, we created a source cloud and then applied a known transformation to get our target cloud. We then ran our written method on the source cloud and target cloud to determine the transformation matrix as calculated. We compared this calculated transformation matrix to the expected transformation we ran to find the target cloud from the source cloud.

To further verify it works, the source cloud and transformation can be changed in the file to ensure the code works with a wide range, including edge cases.

Discussion of Results

We found that this method worked as expected because the test method asserted that the known transformations equaled the calculated transformations from source cloud to target cloud.

Question 3

Algorithm of Approach

For our pivot calibration method, we followed a modification of the algorithm in the slides for the programming assignment. We first created an initial set of rotation matrices, F_G, by combining the first rotation matrix from the R_fks list with a negated identity matrix. Then created an initial translation vector, t_g, by negating the first translation vector from the p_fks list. We went through the remaining rotation and translation matrices in the lists (R_fks and p_fks) and each iteration, updated the rotation matrix collection F_G by appending the next rotation matrix and a negated identity matrix to it. This extends the transformation to account for the new rotation. It also appended the negated translation vector to the existing t_g vector, accumulating the translations. Once all the rotations and translations have been incorporated into F_G and t_g, we use least-squares (Least squares from numpy's least squares uses Lawson and Hanson)[5] to find a solution. This solution represents the transformation. It calculates a new vector p_dimple that minimizes the difference between the transformed points and their desired positions and returns the resulting p_dimple vector, but discards the first 3 elements. These first 3 elements correspond to the rotational part of the transformation, and we are only interested in the translation between the two coordinate systems.

Structure of Program

The function written takes in two arguments: R_fks (a list of rotation matrices) and p_fks (a list of translation vectors). It begins by initializing two variables, F_G that represents a transformation matrix and is created by horizontally stacking the first rotation matrix from R_fks with a negated 3x3 identity matrix and t_g which represents a translation vector and is initialized by negating the first translation vector from p_fks. The code then enters a for loop that iterates through the remaining rotation and translation matrices from R_fks and p_fks. Within each iteration of the loop, np.vstack is used to vertically stack the existing F_G with a new matrix. It combines the previous transformation matrix with the next rotation matrix and negated identity matrix and np.append is used to append a negated translation vector to the existing t_g vector. It accumulates the translation information. After incorporating all the rotation and translation matrices into F_G and t_g, the code uses the np.linalg.lstsq method to solve a linear equation system represented by F_G and t_g. This method finds a solution, p_dimple, that minimizes the difference between the transformed points and their desired positions.

Validation of Approach

To test this method before it was used in questions 5 and 6, we wrote a testPivotCalibration method. In this method, we created a default transformation (defining rotation matrix and translation vector). We then generated a set of points and applied the transformation to the points. We then called our pivot calibration method we wrote to find the estimated translation between the points. We compared this estimated translation to our known translation to confirm that the method correctly identified the translation, ensuring the pivot calibration was accurate.

Discussion of Results

By changing the transformation parameters and transformed points, we could ensure that our pivot calibration method could work for a wide range of points and transformations, meaning that the location of the pivot relative to the tracker could differ and the code would still work.

Question 4

Algorithm of Approach

In this problem, we were given a distortion calibration data set and computed the expected values from this set. The algorithm for this problem was outlined in the problem scenario in the assignment. We first computed the transformation between the optical tracker and EM tracker coordinates. To do this, we found the registration from the trackers to the position and then the transformation from that rotation and translation vector. We did this for the EM data for D and A (giving us FD and FA). We calculated Ci expected as Ci expected = FD_inverse * FA * ci_vector (the passed in as a parameter) and then output Ci expected.

Structure of Program

The method we wrote inputted the EM data for D and A and the data for vectors dj, aj, and cj. It followed the algorithmic approach outlined above, using numpy's inverse (taking inverse of transformation) and dot functions (multiplying), and calling the methods find_registration and transform_from from the pyratransform package. We called our OutputCreator class we wrote, to output the Ci expected data in the correct file format.

Question 5

Algorithm of Approach
In this problem, our goal was to apply EM tracking data to perform a pivot calibration for the EM probe and determine the position relative to the EM tracking system. We follow the approach described in the slides for the programming assignment and the problem 5 description. We began by finding the initial reference point, Go, which is the mean of the EM tracking data from the first frame. We then calculate the relative positions of each tracking marker with respect to Go. This is done for each frame in our EM tracking data, and we create a set of vectors gj. Each gj vector represents the position of a marker relative to the reference point Go. For each frame of our EM tracking data, we found the registration from 'gjSet' to 'GjSet' and the results were stored in lists. We then performed pivot calibration as outlined in question 3 passing in our R and p lists from the registration data.

Structure of Program
This function accepts an instance of the EMPivot class, denoted as 'emPivot,' as its input argument. It extracts the data from emPivot.GArray and assigns it to the variable Gj. Then, it calculates the mean point denoted as 'Go' for the first frame, employing the 'meanPoint.mean_point' function that we wrote in its own file for reference in programs. Following this, it determines the relative positions 'gj' for the first (now reference) frame and each coordinate, achieved by subtracting 'Go' from each point within the frame using a nested for loop. The program then establishes a 'PointSet' object named 'gjSet' for managing the 'gj' data. It initializes two empty lists, namely 'R_fks' and 'p_fks,' to store the registration parameters associated with each frame. In another for loop, the program systematically traverses each frame, generating a 'PointSet' object, 'GjSet,' from the data contained in 'Gj[k].' Then it computes the registration parameters 'R_fK' and 'p_fK' for each frame using the 'gjSet.find_registration' function, taken from pyratransform, and records these parameters within their respective lists, 'R_fks' and 'p_fks.' Ultimately, the program concludes by executing pivot calibration calling the method we wrote in question 3.

Question 6

Algorithm of Approach
We followed the exact steps for question 5 except instead of starting with the Gj vector we started with a Pj vector which is defined as FD * vector Hj. We found FD as the transformation from Dj to dj for each frame in opt pivot.
Structure of Program
It begins by obtaining two sets of points, Dj and dj, from the optPivot.DArray and calBody.dArray. It then creates a PointSet object, djSet, using the dj array from the calibration body. This allows for increased

accuracy because these are known values, compared to calculating dj as a transformation by the mean of the first frame of Dj like for the EM pivot. The program then initializes an empty list, Pj, which will store the transformed points for each frame.

Inside a loop, it iterates through the frames. For each frame, it creates a PointSet object, DjSet, based on the points from the Dj array specific to that frame. It proceeds to find a registration transformation between DjSet and djSet, resulting in a rotation matrix, R_D, and a translation vector, p_D. The F_D transformation matrix is then constructed from these parameters, representing a rigid-body transformation between the two point sets. These methods were called from our pyratransform package.

The script also retrieves another set of 3D points, Hj, specific to the frame from optPivot.HArray[k]. It extends each point in Hj to a 4D point by adding a 1 as the fourth element. This is done because a 4th dimension (scale factor) is needed to apply a transformation matrix to the point. However, in the problem we were told to assume a constant scale factor of 1 for all points, so we did not worry about calculating the 4th element, and rather hard-coded in the addition of a 1. The transform function from pyratransform is applied to these 4D points using the F_D transformation matrix. The transformed points are then appended to the Pj list for each frame after removing the scale factor from the end. This set of points is the result of the transformation operation for the entire sequence of frames. We then followed the exact structure in question 5, using Pj instead of Gj everywhere.

Validation of Approach and Discussion of Results for 4, 5, and 6

<u>Validation of Approach</u>

To validate our approach was correct we followed a similar procedure for questions 4, 5, and 6. This involved running the debugger and checking the values for each variable with a hand calculated value to ensure it matched as expected with data we knew the output for. As a final check, we ran the provided input files (see appendix) and matched up our outputs with the expected to see that they were similar. As expected for our case with no noise, file A, the expected matched our output.

<u>Discussion of Results</u>

File A expected output exactly.

File B was subject to EM noise. Our questions 5 and 6 worked exactly with the posts matching up. The ci expected were close, within +- .5

File C was subject to EM distortion. EM pivot differed slightly as expected and so did Ci expected but Ci expected was very close again and the difference between the EM pivot and the actual pivot and the Ci expected and the actual Ci expected was never more than +-1 and often was much lower.

File D was subject to OT jiggle. Our file output matched the expected actually.

File E was subject to EM distortion and OT jiggle. Only the ci expected differed slightly but never more than +-1 and often was much lower.

File F, J were subject to EM noise, EM distortion, and OT jiggle.

In F, our opt pivot differed slightly but within a +-.55 tolerance. The Ci expected also differed slightly but within a +-.55 tolerance.

Sometimes when running our program, we get an SVD error, “the SVD couldn’t converge”. We are not sure why we get this but realized if you just re-run the program it works without having to change anything.

Workload Division Statement

To write the code and come up with how to write it for each question, we both worked together and discussed as we wrote the code. Hannah wrote the input classes for reading and structuring the output data and worked on a large portion of the debugging and how to best structure our code. Nidhi worked on the report, commenting and explaining the files, and some test files.

References

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Appendix: Results from Running Program

The first line of the data file specifies the number of EM markers on the calibration object, the number of data frames of data and the name. The second line is the estimated post position with EM calibration data (Question 5). The third line is the estimated post position with optical probe pivot calibration. The following N lines (corresponding to the number of frames) outputs the Ci expected vector for each frame (Question 4).

Since our data file A expected matches our actual we can further confirm that our questions 4, 5, and 6 work.

File B was subject to EM noise.
File C was subject to EM distortion.
File D was subject to OT jiggle.
File E was subject to EM distortion and OT jiggle.
File F, J, H, and I were subject to EM noise, EM distortion, and OT jiggle.

File	Expected Output	Actual Output
A	27, 8, pa1-debug-a-output1.txt 197.66, 193.62, 206.43 408.52, 405.88, 191.00 209.46, 210.23, 209.09 207.06, 208.45, 334.06 204.65, 206.66, 459.02 206.24, 335.18, 210.81 203.83, 333.39, 335.78 201.42, 331.61, 460.74 203.01, 460.12, 212.54 200.60, 458.34, 337.50 198.19, 456.55, 462.46 334.40, 213.42, 211.55 331.99, 211.64, 336.51 329.58, 209.86, 461.48 331.17, 338.37, 213.27 328.76, 336.59, 338.23 326.35, 334.80, 463.20 327.94, 463.32, 214.99 325.53, 461.53, 339.95 323.13, 459.75, 464.92 459.33, 216.62, 214.00 456.93, 214.83, 338.97 454.52, 213.05, 463.93 456.11, 341.56, 215.72 453.70, 339.78, 340.69 451.29, 338.00, 465.65	27, 8, pa1-debug-a-output1.txt 197.66, 193.62, 206.44 408.52, 405.88, 191.0 209.47, 210.23, 209.09 207.06, 208.44, 334.05 204.66, 206.66, 459.02 206.24, 335.17, 210.81 203.83, 333.39, 335.78 201.43, 331.6, 460.74 203.01, 460.12, 212.54 200.61, 458.33, 337.5 198.2, 456.55, 462.46 334.4, 213.42, 211.54 332.0, 211.63, 336.51 329.59, 209.85, 461.47 331.18, 338.37, 213.26 328.77, 336.58, 338.23 326.36, 334.8, 463.19 327.95, 463.31, 214.99 325.54, 461.53, 339.95 323.14, 459.74, 464.91 459.34, 216.61, 213.99 456.93, 214.83, 338.96 454.53, 213.04, 463.92 456.11, 341.56, 215.71 453.7, 339.77, 340.68 451.3, 337.99, 465.64

	452.88, 466.51, 217.44 450.47, 464.73, 342.41 448.06, 462.94, 467.37 210.58, 208.21, 448.58 212.42, 211.67, 573.52 214.25, 215.14, 698.46 212.74, 333.15, 445.09 214.58, 336.61, 570.02 216.42, 340.07, 694.96 214.90, 458.08, 441.59 216.74, 461.54, 566.53 218.58, 465.00, 691.47 335.54, 206.00, 446.80 337.38, 209.46, 571.74 339.22, 212.92, 696.68 337.71, 330.93, 443.31 339.55, 334.39, 568.25 341.39, 337.86, 693.18 339.87, 455.86, 439.81 341.71, 459.33, 564.75 343.55, 462.79, 689.69 460.51, 203.79, 445.02 462.35, 207.25, 569.96 464.19, 210.71, 694.90 462.68, 328.72, 441.53 464.51, 332.18, 566.47 466.35, 335.64, 691.41 464.84, 453.65, 438.04 466.68, 457.11, 562.97 468.52, 460.57, 687.91 210.58, 450.24, 208.08 207.59, 449.22, 333.04 204.60, 448.19, 458.00 211.89, 575.23, 209.13 208.90, 574.20, 334.09 205.91, 573.18, 459.05 213.21, 700.22, 210.19 210.21, 699.19, 335.15 207.22, 698.17, 460.11 335.54, 448.90, 211.06 332.55, 447.88, 336.02 329.55, 446.85, 460.98 336.85, 573.89, 212.12 333.86, 572.87, 337.08 330.87, 571.84, 462.04 338.16, 698.88, 213.17 335.17, 697.86, 338.13 332.18, 696.83, 463.09 460.50, 447.56, 214.04 457.50, 446.54, 339.00	452.88, 466.51, 217.44 450.48, 464.72, 342.4 448.07, 462.94, 467.37 210.58, 208.21, 448.58 212.41, 211.68, 573.52 214.25, 215.14, 698.46 212.74, 333.15, 445.09 214.58, 336.61, 570.02 216.42, 340.07, 694.96 214.9, 458.08, 441.59 216.74, 461.54, 566.53 218.58, 465.0, 691.47 335.54, 206.0, 446.8 337.38, 209.46, 571.74 339.22, 212.92, 696.68 337.71, 330.93, 443.31 339.55, 334.39, 568.25 341.39, 337.86, 693.18 339.87, 455.86, 439.81 341.71, 459.33, 564.75 343.55, 462.79, 689.69 460.51, 203.79, 445.02 462.35, 207.25, 569.96 464.19, 210.71, 694.9 462.67, 328.72, 441.53 464.51, 332.18, 566.47 466.35, 335.64, 691.41 464.84, 453.65, 438.04 466.68, 457.11, 562.97 468.52, 460.57, 687.91 210.58, 450.24, 208.08 207.59, 449.22, 333.04 204.6, 448.19, 458.0 211.89, 575.23, 209.13 208.9, 574.2, 334.09 205.91, 573.18, 459.05 213.21, 700.22, 210.19 210.22, 699.19, 335.15 207.22, 698.17, 460.11 335.54, 448.9, 211.06 332.55, 447.88, 336.02 329.56, 446.85, 460.98 336.85, 573.89, 212.11 333.86, 572.87, 337.07 330.87, 571.84, 462.03 338.17, 698.88, 213.17 335.17, 697.85, 338.13 332.18, 696.83, 463.09 460.5, 447.56, 214.04 457.5, 446.54, 339.0

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	210.34, 451.50, 211.81 209.75, 451.84, 336.98 209.84, 452.24, 461.42 212.61, 575.54, 211.23 213.02, 576.78, 335.65 213.38, 577.33, 461.28 215.66, 701.13, 209.89 215.88, 701.43, 335.28 215.82, 702.78, 460.00 334.81, 447.61, 211.26 334.88, 448.53, 336.67 335.61, 449.68, 461.28 337.66, 572.99, 210.74 338.37, 573.59, 335.57 338.50, 574.49, 461.36 341.41, 698.22, 210.24 340.99, 698.42, 335.10 341.22, 699.01, 460.62 460.23, 445.29, 211.49 459.78, 445.52, 336.49 460.57, 446.45, 461.30 462.73, 570.18, 211.38 462.74, 571.01, 335.48 462.93, 571.38, 461.35 465.94, 695.31, 210.68 465.80, 695.09, 335.24 466.31, 696.75, 459.72 209.97, 450.63, 451.22 209.87, 450.66, 576.11 208.68, 451.91, 700.88 208.94, 575.30, 450.46 207.96, 576.35, 575.55 208.11, 576.59, 700.66 207.51, 700.04, 449.56 207.05, 700.78, 574.96 206.87, 701.82, 699.87 334.94, 450.88, 451.66 334.72, 452.37, 576.82 333.83, 452.44, 700.96 333.81, 576.10, 450.77 333.73, 577.14, 575.36 333.40, 578.09, 700.62 332.45, 700.93, 449.85 331.86, 702.23, 575.03 331.92, 702.66, 700.19 459.64, 452.40, 451.28 459.05, 453.40, 576.82 459.26, 453.63, 701.31 458.27, 577.51, 450.64 458.55, 578.06, 575.78	209.95, 451.06, 211.83 210.06, 451.78, 336.83 210.18, 452.51, 461.82 213.01, 576.02, 211.1 213.12, 576.74, 336.1 213.24, 577.47, 461.1 216.06, 700.98, 210.38 216.18, 701.71, 335.38 216.29, 702.43, 460.38 334.91, 448.01, 211.73 335.03, 448.73, 336.73 335.14, 449.45, 461.73 337.97, 572.97, 211.01 338.08, 573.69, 336.01 338.2, 574.41, 461.0 341.03, 697.93, 210.28 341.14, 698.65, 335.28 341.25, 699.37, 460.28 459.88, 444.95, 211.64 459.99, 445.67, 336.63 460.1, 446.39, 461.63 462.93, 569.91, 210.91 463.05, 570.63, 335.91 463.16, 571.35, 460.91 465.99, 694.87, 210.19 466.1, 695.59, 335.19 466.22, 696.31, 460.18 209.66, 450.27, 451.14 209.42, 451.0, 576.13 209.17, 451.73, 701.13 208.6, 575.26, 450.4 208.35, 576.0, 575.4 208.11, 576.73, 700.4 207.53, 700.26, 449.67 207.28, 700.99, 574.67 207.04, 701.72, 699.66 334.66, 451.34, 451.37 334.41, 452.07, 576.37 334.17, 452.8, 701.37 333.59, 576.33, 450.64 333.35, 577.06, 575.64 333.1, 577.8, 700.64 332.52, 701.33, 449.91 332.28, 702.06, 574.9 332.04, 702.79, 699.9 459.65, 452.41, 451.61 459.41, 453.14, 576.61 459.17, 453.87, 701.61 458.59, 577.4, 450.88 458.34, 578.13, 575.87

	458.58, 579.03, 701.33 457.51, 702.68, 449.66 457.63, 703.45, 575.32 457.16, 703.37, 700.50 448.42, 210.51, 211.85 444.69, 208.05, 336.98 441.22, 205.07, 461.84 446.15, 335.64, 214.10 442.79, 332.56, 339.07 438.66, 329.94, 464.22 442.99, 460.20, 217.01 439.37, 457.51, 341.87 435.75, 455.23, 466.89 573.56, 213.60, 215.31 570.46, 210.22, 340.12 566.19, 207.85, 465.53 571.30, 338.14, 218.06 567.38, 335.53, 342.56 563.68, 332.33, 468.27 568.44, 463.02, 220.49 564.41, 460.28, 345.39 561.11, 457.65, 470.27 698.87, 215.81, 219.45 695.18, 213.38, 343.78 691.78, 210.08, 468.99 695.43, 340.52, 222.11 692.49, 337.48, 346.44 689.12, 335.03, 471.47 692.87, 465.87, 223.93 689.34, 462.47, 348.98 686.31, 459.73, 474.32 451.76, 210.51, 450.99 452.05, 207.19, 575.99 451.97, 203.68, 700.05 452.59, 335.47, 453.53 452.32, 331.70, 578.85 452.80, 328.77, 704.07 453.83, 460.27, 457.16 453.43, 456.96, 582.40 453.13, 453.94, 707.28 576.72, 209.92, 450.71 576.50, 206.63, 575.21 577.30, 202.88, 700.47 577.78, 334.26, 454.25 577.34, 331.04, 579.11 577.73, 327.47, 704.03 578.23, 459.26, 457.53 578.26, 456.65, 582.20 578.11, 452.38, 707.01 702.42, 208.44, 450.30	458.1, 578.87, 700.87 457.52, 702.4, 450.14 457.27, 703.13, 575.14 457.03, 703.86, 700.14 448.61, 210.54, 211.72 445.05, 207.77, 336.64 441.49, 204.99, 461.55 445.95, 335.49, 214.42 442.39, 332.71, 339.34 438.83, 329.93, 464.26 443.29, 460.43, 217.12 439.73, 457.65, 342.04 436.17, 454.87, 466.96 573.53, 213.13, 215.33 569.97, 210.35, 340.25 566.42, 207.57, 465.17 570.87, 338.07, 218.03 567.31, 335.29, 342.95 563.75, 332.51, 467.87 568.21, 463.01, 220.74 564.65, 460.23, 345.65 561.09, 457.46, 470.57 698.45, 215.71, 218.95 694.89, 212.93, 343.87 691.34, 210.15, 468.78 695.79, 340.65, 221.65 692.23, 337.87, 346.57 688.68, 335.09, 471.49 693.13, 465.59, 224.35 689.57, 462.81, 349.27 686.02, 460.04, 474.19 451.93, 210.48, 450.63 451.91, 207.11, 575.58 451.89, 203.73, 700.54 452.73, 335.44, 454.01 452.71, 332.06, 578.96 452.69, 328.69, 703.91 453.53, 460.39, 457.38 453.5, 457.01, 582.33 453.48, 453.64, 707.29 576.93, 209.69, 450.63 576.91, 206.31, 575.59 576.89, 202.94, 700.54 577.73, 334.64, 454.01 577.7, 331.26, 578.96 577.68, 327.89, 703.91 578.52, 459.59, 457.38 578.5, 456.21, 582.34 578.48, 452.84, 707.29 701.93, 208.89, 450.63

	701.66, 205.38, 575.32	701.9, 205.51, 575.59
	701.64, 201.76, 700.61	701.88, 202.14, 700.54
	702.63, 333.84, 454.40	702.72, 333.84, 454.01
	702.63, 330.47, 579.45	702.7, 330.46, 578.96
	702.77, 327.46, 703.67	702.68, 327.09, 703.92
	703.46, 459.06, 456.92	703.52, 458.79, 457.38
	703.93, 455.74, 582.76	703.5, 455.42, 582.34
	703.95, 452.11, 707.10	703.48, 452.04, 707.29
	449.11, 451.44, 210.99	448.79, 451.34, 211.3
	447.35, 448.36, 336.44	447.77, 448.48, 336.27
	446.36, 445.75, 461.54	446.75, 445.62, 461.23
	449.31, 576.66, 214.10	449.23, 576.31, 214.17
	448.70, 573.75, 338.74	448.21, 573.45, 339.13
	446.76, 570.98, 464.26	447.19, 570.59, 464.09
	449.83, 700.77, 217.30	449.66, 701.27, 217.03
	448.91, 698.55, 342.22	448.65, 698.41, 341.99
	447.30, 695.80, 466.85	447.63, 695.56, 466.95
	573.83, 450.61, 211.92	573.78, 450.88, 212.31
	572.27, 447.62, 337.11	572.76, 448.02, 337.27
	571.33, 445.12, 461.89	571.75, 445.16, 462.24
	574.42, 576.32, 215.12	574.22, 575.84, 215.17
	572.97, 573.47, 340.63	573.2, 572.99, 340.14
	572.09, 570.59, 464.78	572.18, 570.13, 465.1
	574.18, 700.40, 218.28	574.66, 700.81, 218.04
	573.72, 697.97, 342.63	573.64, 697.95, 343.0
	572.58, 695.25, 467.88	572.62, 695.09, 467.96
	699.10, 450.75, 213.17	698.78, 450.42, 213.32
	698.10, 447.97, 338.71	697.76, 447.56, 338.28
	696.94, 444.63, 463.51	696.74, 444.7, 463.25
	699.34, 575.46, 216.26	699.22, 575.38, 216.18
	697.90, 572.21, 341.27	698.2, 572.53, 341.14
	697.16, 569.91, 466.19	697.18, 569.67, 466.11
	699.47, 700.60, 219.10	699.65, 700.35, 219.04
	698.88, 697.61, 343.87	698.64, 697.49, 344.01
	697.45, 694.81, 469.09	697.62, 694.63, 468.97
	449.35, 450.44, 452.31	449.35, 450.1, 451.91
	446.18, 447.01, 576.52	446.33, 446.68, 576.83
	443.58, 442.91, 701.98	443.31, 443.25, 701.74
	447.27, 575.53, 454.85	447.57, 575.05, 455.29
	444.65, 571.85, 580.28	444.56, 571.62, 580.21
	442.01, 567.78, 705.03	441.54, 568.19, 705.13
	445.63, 700.27, 458.22	445.8, 699.99, 458.68
	442.71, 696.84, 583.21	442.78, 696.56, 583.6
	440.22, 692.88, 708.89	439.76, 693.13, 708.51
	574.35, 452.22, 455.21	574.3, 451.8, 454.97
	571.54, 448.61, 579.67	571.28, 448.37, 579.89
	568.29, 444.66, 705.07	568.26, 444.94, 704.81
	572.80, 576.74, 458.77	572.53, 576.74, 458.36
	569.58, 573.71, 583.68	569.51, 573.31, 583.28
	566.89, 570.13, 708.46	566.49, 569.88, 708.19

	570.50, 701.85, 461.29 567.95, 698.22, 586.73 564.85, 695.08, 711.60 699.40, 453.09, 457.75 696.47, 450.23, 583.26 693.62, 446.93, 707.64 697.04, 578.24, 461.58 694.86, 574.71, 586.19 691.34, 571.62, 711.53 695.62, 703.05, 464.54 693.14, 699.85, 590.19 690.09, 696.55, 714.36	570.75, 701.68, 461.74 567.73, 698.25, 586.66 564.72, 694.82, 711.58 699.25, 453.49, 458.04 696.23, 450.06, 582.96 693.21, 446.63, 707.87 697.48, 578.43, 461.42 694.46, 575.0, 586.34 691.44, 571.57, 711.26 695.7, 703.37, 464.81 692.68, 699.94, 589.73 689.67, 696.51, 714.64
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	212.45, 461.69, 569.62 209.38, 465.03, 694.18 334.12, 205.61, 454.38 331.52, 209.00, 579.35 328.88, 212.48, 704.15 337.29, 330.38, 450.76 334.53, 333.81, 575.74 331.66, 337.23, 700.62 340.35, 455.19, 447.06 337.46, 458.63, 572.01 334.45, 462.00, 697.00 459.01, 202.77, 457.51 456.22, 206.20, 582.37 453.63, 209.73, 706.70 462.23, 327.39, 453.56 459.44, 330.80, 578.54 456.71, 334.22, 703.35 465.27, 452.12, 449.62 462.50, 455.54, 574.74 459.65, 458.97, 699.99 211.03, 451.19, 208.72 210.06, 449.32, 334.03 208.88, 447.42, 459.25 211.15, 576.07, 210.81 210.25, 574.23, 335.98 209.13, 572.28, 461.06 210.95, 701.00, 213.08 210.15, 699.10, 337.91 209.32, 697.11, 462.68 335.76, 450.82, 209.87 334.86, 448.95, 334.81 333.86, 447.04, 459.80 335.96, 575.85, 211.92 334.88, 574.02, 336.80 333.77, 572.15, 461.68 336.06, 701.10, 214.01 334.73, 699.14, 338.94 333.46, 697.22, 463.77 460.60, 450.55, 211.03 459.73, 448.63, 335.67 458.85, 446.64, 460.58 460.83, 575.69, 213.04 459.65, 573.78, 337.68 458.62, 571.89, 462.47 461.20, 701.10, 215.00 459.63, 699.13, 339.96 458.11, 697.26, 464.90 210.01, 451.41, 450.35 210.10, 452.98, 575.26 210.15, 454.44, 699.89	212.44, 461.6, 569.37 209.67, 465.07, 694.29 334.25, 205.41, 454.12 331.48, 208.89, 579.04 328.72, 212.37, 703.96 337.19, 330.33, 450.71 334.43, 333.81, 575.63 331.66, 337.29, 700.55 340.14, 455.25, 447.29 337.37, 458.73, 572.21 334.61, 462.21, 697.14 459.18, 202.55, 456.96 456.42, 206.02, 581.88 453.65, 209.5, 706.81 462.12, 327.46, 453.55 459.36, 330.94, 578.47 456.6, 334.42, 703.39 465.07, 452.38, 450.14 462.31, 455.86, 575.06 459.54, 459.34, 699.98 210.81, 451.21, 208.95 209.73, 449.24, 333.93 208.65, 447.27, 458.91 210.98, 576.19, 210.92 209.89, 574.22, 335.9 208.81, 572.26, 460.88 211.14, 701.18, 212.89 210.06, 699.21, 337.87 208.97, 697.24, 462.85 335.81, 451.03, 210.03 334.72, 449.06, 335.01 333.64, 447.09, 459.99 335.97, 576.01, 212.0 334.89, 574.05, 336.98 333.8, 572.08, 461.96 336.13, 701.0, 213.97 335.05, 699.03, 338.95 333.97, 697.06, 463.93 460.8, 450.85, 211.11 459.72, 448.88, 336.09 458.64, 446.91, 461.07 460.97, 575.83, 213.08 459.88, 573.87, 338.06 458.8, 571.9, 463.04 461.13, 700.82, 215.05 460.05, 698.85, 340.03 458.96, 696.88, 465.01 209.75, 451.27, 450.03 210.09, 452.88, 575.02 210.43, 454.48, 700.01

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	707.66, 455.09, 456.94 450.51, 208.41, 450.37 447.18, 210.63, 575.29 444.02, 212.96, 699.68 451.82, 333.07, 447.57 448.49, 335.29, 572.59 445.19, 337.53, 697.43 452.93, 457.88, 444.80 449.62, 460.12, 569.91 446.22, 462.35, 695.17 575.47, 207.34, 453.47 572.08, 209.68, 578.41 569.16, 212.08, 702.96 576.74, 332.01, 450.84 573.41, 334.26, 575.92 570.22, 336.58, 700.84 577.94, 456.82, 448.33 574.60, 459.09, 573.60 571.18, 461.39, 698.82 700.24, 206.39, 456.20 697.14, 208.77, 581.21 694.60, 211.19, 706.57 701.58, 330.97, 454.07 698.36, 333.26, 579.25 695.15, 335.88, 704.52 703.02, 455.82, 452.13 699.55, 458.19, 577.48 695.77, 460.77, 702.56 451.12, 448.91, 208.94 454.62, 449.24, 333.56 458.12, 449.51, 458.43 450.27, 574.05, 208.73 453.46, 574.40, 333.35 456.79, 574.76, 458.11 449.55, 699.47, 208.45 452.39, 699.75, 333.40 455.22, 700.14, 458.31 576.13, 449.93, 205.72 579.65, 450.16, 330.31 583.11, 450.35, 455.35 575.16, 575.06, 205.50 578.55, 575.30, 330.13 581.99, 575.58, 455.08 574.53, 700.35, 205.22 577.54, 700.72, 330.15 580.60, 701.12, 455.08 701.24, 451.23, 202.48 704.77, 451.24, 327.25 708.18, 451.23, 452.49 700.13, 576.11, 202.23	707.28, 455.45, 456.77 450.67, 208.17, 449.86 447.36, 210.46, 574.79 444.05, 212.75, 699.73 451.7, 333.15, 447.6 448.4, 335.44, 572.53 445.09, 337.73, 697.47 452.74, 458.12, 445.33 449.43, 460.41, 570.27 446.13, 462.7, 695.2 575.62, 207.19, 453.18 572.31, 209.48, 578.12 569.01, 211.77, 703.05 576.66, 332.17, 450.92 573.35, 334.46, 575.86 570.04, 336.75, 700.79 577.69, 457.14, 448.66 574.38, 459.44, 573.59 571.08, 461.73, 698.53 700.57, 206.22, 456.51 697.27, 208.51, 581.44 693.96, 210.8, 706.38 701.61, 331.19, 454.25 698.3, 333.48, 579.18 694.99, 335.77, 704.12 702.64, 456.17, 451.98 699.34, 458.46, 576.92 696.03, 460.75, 701.85 451.32, 449.2, 209.02 454.62, 449.48, 333.98 457.91, 449.77, 458.94 450.4, 574.2, 208.77 453.7, 574.48, 333.72 456.99, 574.76, 458.68 449.48, 699.19, 208.51 452.78, 699.48, 333.46 456.07, 699.76, 458.42 576.28, 450.11, 205.73 579.57, 450.4, 330.68 582.87, 450.68, 455.64 575.35, 575.11, 205.47 578.65, 575.39, 330.43 581.95, 575.68, 455.38 574.43, 700.11, 205.21 577.73, 700.39, 330.17 581.02, 700.67, 455.12 701.23, 451.03, 202.43 704.52, 451.31, 327.39 707.82, 451.59, 452.34 700.31, 576.02, 202.17

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	703.05, 700.65, 564.38 705.42, 704.36, 689.30	703.06, 700.64, 564.38 705.43, 704.35, 689.3
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	340.46, 450.20, 707.23 457.64, 204.87, 447.57 458.46, 202.13, 572.61 458.96, 200.36, 698.25 459.04, 330.99, 451.22 460.36, 327.48, 575.96 462.74, 323.27, 701.16 461.21, 456.47, 454.52 462.86, 452.43, 579.90 466.35, 447.30, 705.01 205.24, 450.77, 213.79 205.58, 452.01, 337.06 205.91, 453.29, 460.95 205.52, 575.13, 212.67 206.08, 577.04, 336.43 206.63, 578.68, 460.39 207.85, 699.28, 210.76 208.04, 701.52, 334.72 207.93, 703.28, 458.68 331.68, 449.71, 213.56 330.69, 451.52, 337.52 329.84, 453.23, 462.07 332.84, 575.06, 212.71 331.28, 577.16, 337.06 329.91, 578.78, 461.87 334.69, 700.88, 211.96 332.27, 702.19, 336.95 329.83, 703.20, 461.62 458.73, 449.44, 213.34 456.25, 451.21, 338.33 454.01, 452.70, 463.78 459.98, 575.51, 212.69 456.65, 577.05, 337.83 453.80, 578.00, 463.54 460.72, 702.11, 213.27 456.91, 702.51, 338.87 453.51, 702.75, 463.94 208.39, 449.12, 450.82 210.88, 446.04, 576.00 211.69, 442.00, 702.46 207.47, 574.49, 454.11 209.77, 571.31, 578.98 210.33, 567.31, 705.29 207.18, 699.07, 456.22 209.24, 695.94, 581.27 210.08, 692.20, 707.44 332.33, 450.72, 448.24 334.83, 447.40, 573.57 337.48, 442.70, 699.67 330.81, 576.27, 451.84	340.85, 451.33, 706.33 458.24, 205.97, 448.18 459.8, 202.62, 573.12 461.35, 199.27, 698.07 460.47, 330.9, 451.5 462.03, 327.55, 576.45 463.58, 324.2, 701.39 462.71, 455.84, 454.82 464.26, 452.49, 579.77 465.82, 449.14, 704.71 208.07, 450.72, 211.57 206.8, 451.5, 336.56 205.53, 452.29, 461.55 208.2, 575.72, 210.79 206.93, 576.5, 335.78 205.66, 577.29, 460.77 208.33, 700.72, 210.01 207.06, 701.5, 335.0 205.79, 702.28, 459.99 333.07, 450.6, 212.84 331.8, 451.38, 337.83 330.53, 452.17, 462.82 333.2, 575.6, 212.06 331.93, 576.38, 337.05 330.66, 577.16, 462.04 333.33, 700.6, 211.28 332.06, 701.38, 336.27 330.79, 702.16, 461.26 458.06, 450.48, 214.11 456.79, 451.26, 339.1 455.52, 452.04, 464.09 458.19, 575.48, 213.33 456.92, 576.26, 338.32 455.65, 577.04, 463.31 458.32, 700.47, 212.55 457.05, 701.26, 337.54 455.78, 702.04, 462.53 208.11, 448.15, 451.41 210.56, 445.14, 576.35 213.0, 442.14, 701.29 206.6, 573.1, 454.45 209.05, 570.1, 579.39 211.5, 567.09, 704.33 205.09, 698.06, 457.48 207.54, 695.05, 582.42 209.99, 692.05, 707.36 333.08, 449.71, 449.0 335.52, 446.71, 573.94 337.97, 443.71, 698.88 331.57, 574.67, 452.03

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		697.87, 702.96, 574.87 700.22, 700.35, 699.82
J	X	27, 8, pa1-unknown-j-output1.txt 201.67, 206.17, 207.78 394.8, 392.48, 201.56 208.96, 211.6, 210.83 208.34, 214.19, 335.8 207.72, 216.77, 460.77 210.86, 336.56, 208.25 210.24, 339.15, 333.23 209.61, 341.73, 458.2 212.76, 461.52, 205.68 212.14, 464.11, 330.65 211.51, 466.69, 455.62 333.94, 209.72, 211.49 333.32, 212.3, 336.46 332.7, 214.88, 461.43 335.84, 334.68, 208.91 335.22, 337.26, 333.89 334.6, 339.84, 458.86 337.74, 459.64, 206.34 337.12, 462.22, 331.31 336.5, 464.8, 456.28 458.93, 207.83, 212.15 458.3, 210.42, 337.12 457.68, 213.0, 462.09 460.83, 332.79, 209.57 460.2, 335.37, 334.55 459.58, 337.96, 459.52 462.72, 457.75, 207.0 462.1, 460.33, 331.97 461.48, 462.92, 456.94 210.94, 211.38, 450.5 209.57, 215.06, 575.44 208.2, 218.74, 700.38 208.16, 336.3, 446.79 206.79, 339.97, 571.73 205.43, 343.65, 696.67 205.39, 461.21, 443.08 204.02, 464.89, 568.02 202.65, 468.57, 692.96 335.9, 214.2, 451.79 334.53, 217.87, 576.72 333.16, 221.55, 701.66 333.13, 339.11, 448.08 331.76, 342.79, 573.02 330.39, 346.47, 697.95 330.35, 464.02, 444.37 328.98, 467.7, 569.31

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K	X	27, 8, pa1-unknown-k-output1.txt 205.56, 205.46, 193.54 400.62, 392.67, 203.25 208.2, 211.82, 211.86 210.17, 210.06, 336.83 212.14, 208.31, 461.81 208.22, 336.8, 213.61 210.19, 335.05, 338.59 212.17, 333.3, 463.56 208.25, 461.79, 215.37 210.22, 460.04, 340.34 212.19, 458.29, 465.31 333.19, 211.82, 209.89 335.16, 210.07, 334.86 337.13, 208.32, 459.84 333.21, 336.81, 211.64 335.18, 335.06, 336.62 337.15, 333.31, 461.59 333.23, 461.8, 213.4 335.2, 460.05, 338.37 337.17, 458.29, 463.34 458.17, 211.83, 207.92 460.14, 210.08, 332.89 462.11, 208.33, 457.87 458.19, 336.82, 209.67 460.16, 335.07, 334.65 462.13, 333.31, 459.62

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