

# Simulated Robotic Manipulation Protocol

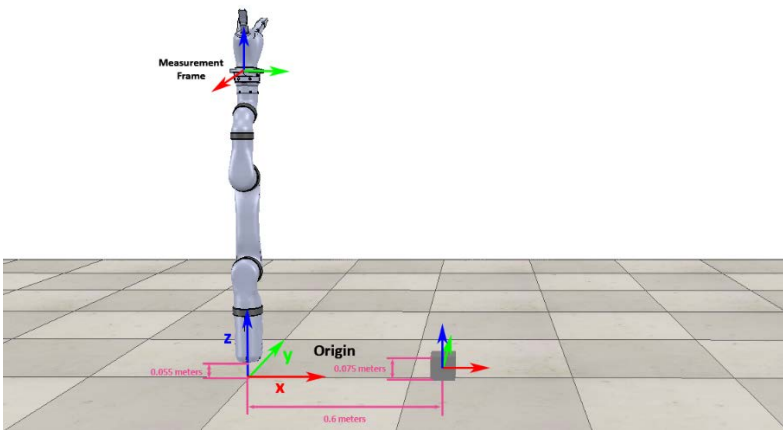
Reference No / Version	RAL-SI-2020-P[19-0842]_4-V1.1 for the latest versions of the protocol please refer to <a href="https://research.csiro.au/robotics/manipulation-benchmark/">https://research.csiro.au/robotics/manipulation-benchmark/</a>
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Purpose	A prehensile manipulation task to replicate the movement of a wooden cube. This will assess the environmental interactions of a robotic manipulator in addition to the kinematic motion of the arm. The contrast between wood and plastic objects is desired to see if the same robotic movements elicit the same resulting movements in the objects.
Task Description	The task involves a 13 second sequence of movements that prompts two movements of the cube from two different configurations. A video of the task being performed by the real world manipulator is available at <a href="https://research.csiro.au/robotics/manipulation-benchmark/">https://research.csiro.au/robotics/manipulation-benchmark/</a>
Setup Description	<p><u>List of objects and their descriptions:</u></p> <ul style="list-style-type: none"> <li>Flat laminated surface</li> <li>White Mahogany wooden cube (<math>0.075 \times 0.075 \times 0.075</math> meters), a mesh file of the cube is available at the benchmark website. Weight = 0.46 Kilograms</li> </ul> <p><u>Initial and target poses of the objects:</u></p> <p>The initial configuration of the cube within the scene can be seen in Figure 1 and Figure 2. The cube is centered 0.6 meters away from the origin.</p> <p><u>Description of the manipulation environment:</u></p> <ul style="list-style-type: none"> <li>Temperature: 20.5 °C</li> <li>Relative Humidity: 31%</li> </ul>
Robot/Hardware/Software/Subject Description	<p><u>Targeted robots/hardware/software:</u></p> <ul style="list-style-type: none"> <li>Kinova Mico<sup>2</sup> 6DOF Manipulator, sensor mounting bracket, Robotiq FT300 sensor, gripper mounting bracket and KG-3 Gripper. URDF of robot provided.</li> </ul> <p><u>Initial state of the robot/hardware/subject with respect to the setup:</u></p> <ul style="list-style-type: none"> <li>Robot is fixed 0.055 meters above origin and the base centered.</li> <li>The base frame of the robot should align with the origin frame of the simulator as demonstrated in Figure 1 and Figure 2.</li> </ul> 

Figure 1: Side orthographic view of scene setup with offsets and reference frames.

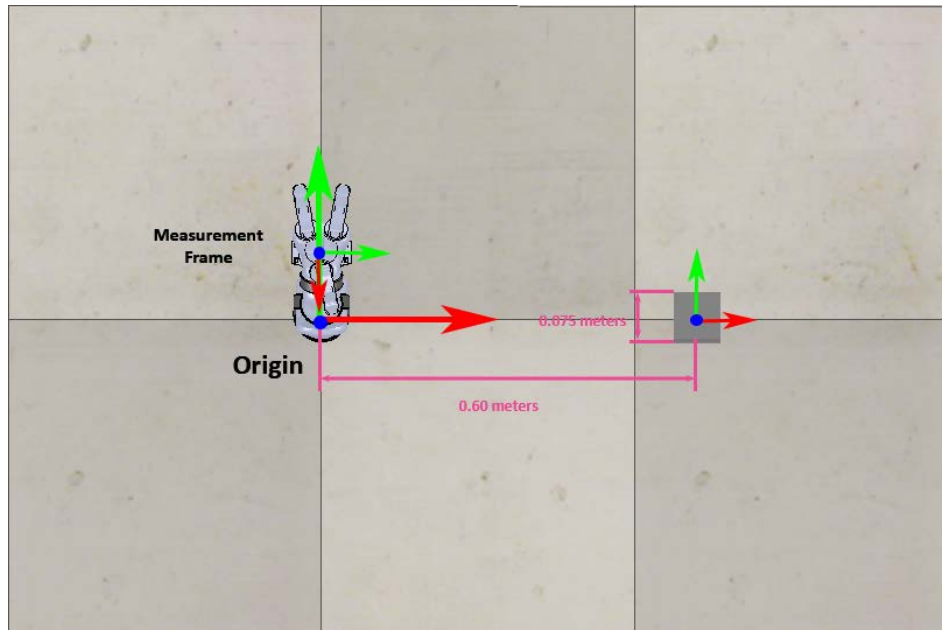


Figure 2: Top view of scene setup with offsets and reference frames.

- The robot begins with the following joint rotations (0,180,180,0,0,0)
- Gripper remains fully open.
- Control of the robot is at 10Hz using a Proportional controller to set joint velocities.
  - The gain of the P controller is 4
  - The controller requires the current joint rotations from the robot.

Prior information provided to the robot:  
Nil

#### Procedure

The following is a sequence of rotations and times the robot has to achieve the desired configurations. The proportional controller is supplied with this information to elicit the desired movements of the manipulator.

0. (0,180,180,0,0,0) at start
1. (-3,150,281,97,-4,-11) for 3 seconds
2. (-3,123,253,101,-4,-12) for 2 seconds
3. (-3,114,224,101,-4,-12) for 2 seconds
4. (15,120,229,107,-3,-96) for 2 seconds
5. (15,96,208,107,-4,-96) for 2 seconds
6. (-20,96,208,107,-4,-96) for 2 seconds

#### Execution Constraints

- The configuration of the robot and the proportional velocity controller are fixed parameters that are not user definable.