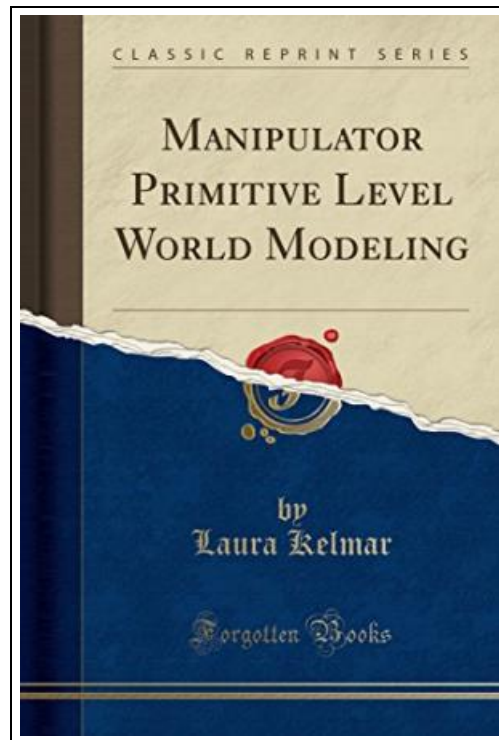


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Forgotten Books, 2017. Paperback. Condition: New. Language: English . Brand New Book ***** Print on Demand *****. Excerpt from Manipulator Primitive Level World Modeling The modules can be logically recombined according to their function in the system, as shown in figure 3. The system pictured consists of two main branches; the left branch contains the perception processes and the right branch contains the manipulation processes. The perception processes provide sensory feedback from devices such as cameras, range sensors and tactile array sensors. The manipulator processes plan and execute manipulator trajectories. Note that while the two branches decompose tasks independently within each branch, communication between processes, both within a branch and across branches, occurs via the global data system. The second level of the Task Decomposition hierarchy is called the Primitive Level (prim). It generates dynamic motion and force commands from a static description of the desired behavior of a device. Prim creates the time sequence of attractor sets needed to produce a dynamic trajectory and sends these as commands to the Servo level of the Task Decomposition hierarchy [wav8s]. The Prim World Modeling support module uses sensory input to provide Prim Task Decomposition with the most current models of the manipulator and its world. A manipulator control system, such as the one described in [alb87], allows for many controlled devices, as well as many sensors. For example, the Task Decomposition hierarchy may control actuators for the camera lens, the gripper, and the manipulator joints, while the Sensory Processing hierarchy may process camera images, tactile arrays, and manipulator joint data. In general, each device requires separate World Modeling support at each level. That is, a complete pictorial representation of the control hierarchy would contain a separate World Modeling box for each device and associated sensor, as in figure 3. The scope...



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