UR10 Performance Analysis

Ravn, Ole; Andersen, Nils Axel; Andersen, Thomas Timm

Publication date:
2014

Document Version
Publisher's PDF, also known as Version of record

Citation (APA):

General rights
Copyright and moral rights for the publications made accessible in the public portal are retained by the authors and/or other copyright owners and it is a condition of accessing publications that users recognise and abide by the legal requirements associated with these rights.

- Users may download and print one copy of any publication from the public portal for the purpose of private study or research.
- You may not further distribute the material or use it for any profit-making activity or commercial gain
- You may freely distribute the URL identifying the publication in the public portal

If you believe that this document breaches copyright please contact us providing details, and we will remove access to the work immediately and investigate your claim.
UR10 Performance Analysis

by Asger Winther-Jørgensen
& Christian Ahlburg Dirksen

Technical University of Denmark
Institute for Automation and Control
Ole Ravn
Nils Axel Andersen
Thomas Timm Andersen
29. juni 2014
Contents

1 Introduction 1

2 Real-time Interface 2
   2.1 Congestion Control - Nagle’s algorithm? 2
   2.2 Sample Frequency 5
   2.3 Calculation time and delays 8

3 Commands 11
   3.1 The movec command 13
   3.2 The movej command 14
   3.3 The movel command 16
   3.4 The servoj and servoc commands 17
   3.5 The speedj command 17
   3.6 The speedl command 17
   3.7 The stopj command 24
   3.8 The stopl command 25

4 Conclusion 28
1 Introduction

While working with the UR-10 robot arm, it has become apparent that some commands have undesired behaviour when operating the robot arm through a socket connection, sending one command at a time. This report is a collection of the results obtained when testing the performance of the different commands available in URScript to control the robot. It will also describe the different time delays discovered when using the UR-10 robot arm.
2 Real-time Interface

Glossary for the following sections:

Controller:
The program running on the UR-10’s internal computer, broadcasting robot arm data, receiving and interpreting commands and controlling the arm accordingly.

Interfacing program or program:
A program running on an arbitrary computer, connecting (interfacing) with the controller over a TCP Connection to the controller’s ‘real time’- or MATLAB-Interface port.

2.1 Congestion Control - Nagle’s algorithm?

The first thing that becomes evident when looking at the Matlab interface output of the UR-10 robot is that it appears to have some sort of anti-congestion algorithm in place.

Figures 2.1 and 2.2 show a joint angle as a function of time. In each of the figures, the two series are the same joint-variables plotted as functions of two different times. The red series is the joint angle as a function of the timestamp of the package in which it was broadcast. The blue series is the very same joint angle data series, but this time plotted as a function of the computer localtime at which the package was received by the program communicating with the UR Matlab interface.

In figure 2.1 the program was run on a remote computer communicating with the robot arm’s internal computer over Ethernet. In figure 2.2 the program was run on the robot arm’s internal computer.

Especially in figure 2.2 it is very visible that the packages are not broadcast at a rate of 125Hz, but rather at some other frequency, in this case 5 packages at a time at 25Hz, approximately. For this test, the program interfacing with the Matlab interface was run on the robot arm’s internal computer.
2.1. Congestion Control - Nagle’s algorithm?

Figure 2.1: Angle values from data packages plotted as a function of package timestamp and as a function of package arrival time when the program was run on a remote computer. It can be seen that the packages arrive at the computer two at a time.

NB: These plots do not in any way tell us anything about the time delay between the controller sending a package and the interfacing program receiving it. The controller timestamp and the program timestamp are on different time scales, but have been translated to the same range for the sole purpose of being displayed in one graph. The translation is arbitrary.

The 25Hz, or 40ms, is the standard acknowledge timeout for UNIX based systems, and Nagle’s algorithm will always wait for acknowledgement before sending the next package, so this again points towards the Nagle’s algorithm being the problem.

In both Python and C++, a socket parameter can be set, TCP_QUICKACK, which will force any pending acknowledgements to be sent immediately. Setting this flag every time a data package is received will make the Nagle’s Algorithm on the controller socket send the next package when it becomes available. This solves the problem of packages being bundled for delayed shipment.

This is a work-around of the problem, allowing the Matlab-interface to be used for real-time control in spite of the Nagle-algorithm. It is noteworthy that any closed-loop control of the robot arm automatically implements this
2.1. Congestion Control - Nagle’s algorithm?

Figure 2.2: Angle values from data packages plotted as a function of package timestamp and as a function of package arrival time when the program was run on the robot arm’s internal computer.

Figure 2.3: Angle values from data packages plotted as a function of package timestamp and as a function of package arrival time when the program included forced immediate acknowledgement. The results are similar for the robot arm’s internal computer and the remote computer.
work-around since sending a command as a reaction to the last received package will also send the acknowledgement so that the next package will appear on time.

2.2 Sample Frequency

Now that the receiving frequency has been determined to be 125Hz, it would be good to know the frequency with which one can send commands to the robot arm and expect them to be handled on time. To see if this frequency matched the broadcasting frequency, a sampled sinus curve was sent to the robot arm, one sample per received data package from the robot arm. Figure 2.4 displays the result of a test in which a sinusoidal velocity curve for one joint was sent to the robot arm at the same frequency the robot arm broadcasts with, achieved by sending each sample as a reaction to a received package. Here the code used was:

```python
starttime = time.now
while time.now < 2*pi+starttime:
    on received_new_data:
        qd = [0,0,0,0,0,0]
        qd[4] = sin(10*time.now)
        speedj(qd,5,0.02)
end
```

What can be seen on the figure is that the robot arm’s internal target velocity follows, with some delay, the same trajectory as is sent to it, that is it does not undersample or drop packages.

Something else to notice is the sometimes serrated nature of the controller target velocity curve. It seems that commands are lost one sample, but made up for in the next. This suggests that the controller handles input and output asynchronously. This serration also shows that, even though these commands are sent as soon as possible after receiving a package, one cannot be sure that a reaction will be seen until two samples later.

Looking at figure 2.5 we see a different behaviour. In this case, the same sinusoidal curve was sent to the robot arm, but at twice the frequency, that is both the frequency of the sinusoidal curve and the sample frequency were doubled. The code used here was:

```python
starttime = time.now
while time.now < 2*pi+starttime:
    qd = [0,0,0,0,0,0]
    qd[4] = sin(11*time.now)
```

```python
```
2.2. Sample Frequency

Figure 2.4: Sent target, the sinus shaped velocity curve sent to the robot arm plotted next to the received target velocity of the robot arm joint. The sent target is issued at the same frequency as the controller broadcasts.

```plaintext
sleep(0.004)
speedj(qd, 5, 0.02)
end
```

Misbehaviour was expected in this test, the hope being that samples would be dropped and that the robot target velocity would be an undersampled version of the sent target velocity. This was not the case. Instead, we saw every sample in the robot, but executed one for each controller sample without regard to the time at which it was received. It was also observed that the robot arm continued moving after the program was terminated.

From this, it can be deduced that the controller buffers any received commands and executes the oldest command, if any, in the buffer at each controller iteration. This can be desirable as no control commands are overlooked, but it does have drawbacks. Doing real-time control on the robot arm, any other command issued to the arm will cause delay in the real-time control if not accounted for by skipping one sample of the control.

When viewing results of long tests, it seems that the timescales used by the robot controller and the computers respectively do not agree on the length of a second. Plotting datasets as a function of controller timestamp and of computer timestamp on top of each other showed that the computer
2.2. Sample Frequency

Figure 2.5: Sent target, the sinus shaped velocity curve sent to the robot arm plotted next to the received target velocity of the robot arm joint. The sent target is issued at approximately twice the frequency of the controller broadcast.

Figure 2.6: Illustration of the timescale difference between the controller time and the program time. Timescales are offset to zero at sample one.
2.3 Calculation time and delays

Time delays are to be expected when working across networks. It is desirable to determine these delays, as they have a major impact on the actual bandwidth limitations of any controller implementations. This is addressed in this section.

For a quick estimate of computer-to-computer communication, tests were run in which packages of sizes similar to the commands and data packages were pinged back and forth, and these indicated a maximum response time of 1ms.

Through a series of tests in which a command was sent to the controller from a remote computer and the time was measured before a reaction could be seen from the controller (The round trip time). The best-case scenario was used when the command was sent immediately after receiving a package (no calculation time). A reaction from the controller, a change in the controller’s target velocity, was observed either 8ms later (one sample) or 16ms (two samples). In all cases, physical change was measured by the joint variable encoders in the next sample after controller target velocities had been set, giving a total round-trip time for the signal of 24ms.

To estimate the effect of calculation time before a reaction to a packet is sent, another sinus curve velocity is sent to the robot arm. The velocity command sending is triggered by the arrival of a data package. This time, however, a delay is induced between the package is received and the command is sent. In the beginning of the sinus curve, the delay is as short as possible, increasing by 0.000016 per sample until the delay reaches 0.008, a full sample. The code used was:

```python
while delay < 0.008:
    on received_new_data:
        qd = [0,0,0,0,0,0]
        qd[4] = qd[4] + 0.2*\sin(10*\times.now)
        sleep(delay)
```

This is not a big problem, one just has to account for this when creating controllers and make sure that it is designed for the actual sample time observed.
2.3. Calculation time and delays

delay += 0.008/500
speedj(qd,5,0.02)
sleep(0.00001)
end

One resulting graph is shown in 2.7. It can be seen that the target velocity graph is serrated in the beginning of the graph, indicating that the commands do not consistently take the same amount of samples before reaching the controller, as was seen when measuring reaction times for immediate responses. This serration is caused mainly by network and calculation time, and it is suspected that the controller interacts with network data and the robot asynchronously. Upon reaching a certain delay, the commands consistently reach the target velocity of the controller in two samples. Serration shows again at a 6ms delay, indicating that at a calculation time of less than 6ms will ensure that a command reaches the controller in maximum 2 samples (16ms), and that physical change can be seen within 3 samples (24ms).

This gives a total of somewhere between 16ms and 24ms from a command is issued until a physical change can be observed in the system. This results in a bandwidth limit of approximately 50Hz induced by the delays in communication in the best-case scenario where calculation time is less than 6ms and the robot arm and controlling computer are on the same local wired network.

These results are valid for programs run on a remote computer connected over ethernet and for the robot arm’s internal computer alike.
2.3. Calculation time and delays

Figure 2.7: Target velocity of the robot controller and the velocity sent in commands as a function of time. For each command sent, the delay until the next command is increased slightly.
3 Commands

The UR script provides a series of commands with which to control the robot arm. Each have their uses and caveats. Some tests of a selection of these commands have been run, and some of these problems have been documented. Table 3.1 shows a list of the tested commands, short descriptions of them and a brief summary of the test results in good/bad form. Extended explanations of the tests and results follow where they have been deemed worthwhile.
<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
<th>Good</th>
<th>Bad</th>
</tr>
</thead>
<tbody>
<tr>
<td>movec</td>
<td>Move along circular arc segment from current pose, through via pose to end pose.</td>
<td>Easy way to make soft motions/curves in cartesian space, for example around obstacles.</td>
<td>Jerks to a halt in final position. Jerks when interrupted.</td>
</tr>
<tr>
<td>movej</td>
<td>Simple joint space move command.</td>
<td>No singularity problems.</td>
<td>Jerks when interrupted, this can cause Torque Limit Violation</td>
</tr>
<tr>
<td>movel</td>
<td>Simple cartesian space move command.</td>
<td>Movement in cartesian space is easy to plan.</td>
<td>Singularity problems. Jerks when interrupted, can cause Torque limit violation.</td>
</tr>
<tr>
<td>servoj</td>
<td>Servo to joint coordinates without pathplanning.</td>
<td>Same as movej</td>
<td>Jerks to a halt in final position. Jerks when interrupted, this can cause Torque Limit Violation.</td>
</tr>
<tr>
<td>servoc</td>
<td>Servo to cartesian coordinates without pathplanning</td>
<td>Same as movel</td>
<td>Jerks to a halt in final position. Jerks when interrupted, this can cause Torque Limit Violation.</td>
</tr>
<tr>
<td>speedj</td>
<td>Set Joint speeds with desired acceleration.</td>
<td>Works as expected. Can be issued at 125Hz. Will not jerk if interrupted.</td>
<td>Nothing observed.</td>
</tr>
<tr>
<td>speedl</td>
<td>Set TCP speed in cartesian space with desired joint acceleration.</td>
<td>Possible to set speeds in cartesian space rather than joint space.</td>
<td>Jerks when interrupted, this can cause Torque Limit Violation. Jerks occur when interrupting movement with a new speed.</td>
</tr>
<tr>
<td>stopj</td>
<td>Decellerates joint speeds to zero.</td>
<td>Works as expected.</td>
<td>If given close to the end of a movement, it can result in an overshoot or an undershoot.</td>
</tr>
<tr>
<td>stopl</td>
<td>Decellerates TCP speed to zero.</td>
<td>Works as expected.</td>
<td>If given close to the end of a movement, it can result in an overshoot or an undershoot.</td>
</tr>
</tbody>
</table>

Tabel 3.1: List of commands and their caveats
3.1 The movec command

The code for this test:

```python
sleep (0.5)
movec (pvia, pend, 2.0, 0.6)
sleep (5)
```

![Target Joint velocities](image)

Figure 3.1: Target joint velocities during a movec command execution.

In figures 3.1 and 3.2 the behaviour of movec can be seen. When the movec reaches its final pose, the robot arm jerks violently to a halt, inducing notable vibrations in the robot setup. Looking at the target velocity curve, one could expect the target accelerations to be off the charts, similar to when move commands in general are interrupted, but this does not occur according to figure 3.2. It seems that the controller just abandons the robot to its own devices once the goal position is reached.

The lack of deceleration is an issue, but the lack of effort to break instantly does save the system from joint torque limit violation.
3.2 The movej command

The code for this test:

```python
sleep(0.5)
movj(q1)
sleep(1.2)
movj(q2)
sleep(1.3)
movj(q3)
sleep(5)
```

In figures 3.3 and 3.4 some results of testing the movj command are shown. In this test, three movj commands were sent to the robot arm. The first is sent at 0.5 sec when the robot arm is standing still. The second command is sent at 1.7 seconds, just before the first move is finished. The last command is sent at 3 seconds, midway through the second command’s execution.

The result is jerky. In itself, the movj command executes a nice, smooth trapezoid trajectory in configuration space, but if it is interrupted by a second movj command before completing, things go wrong.

One likely reason for this would be the controller calculating a new trapezoid from current position upon receiving the interrupting movj command, but
Figure 3.3: Target joint accelerations during a series of overlapping movej commands. One movej command is issued at 0.5 seconds, the next at 1.7s, just before the first finishes, and the third is issued at 3s, way before the second command has finished. Both interruptions lead to acceleration spikes and the second leads to joint torque limit violation.

As a consequence of this desired great acceleration, large currents are induced over the motors, in extreme cases triggering the joint torque violation safety limit. In this case, a current of over 15A is observed in the shoulder joint motor. These problems could be solved, it seems, by calculating trajectories for move commands not using just current position of the robot, but using the full current robot state including velocities.

Something else of interest observed here is that joint torque limits are not set on the torque caused by interaction with external objects, but total torque due to internal and external torques combined. This is of course the most cost-effective and error robust implementation, but it does force the user to have to consider the joint torque limits when planning sudden stops.
3.3 The movel command

The code for this test:

\begin{verbatim}
  sleep(0.5)
  movel(q1)
  sleep(1.2)
  movel(q2)
  sleep(1.3)
  movel(q3)
  sleep(5)
\end{verbatim}

This command is essentially similar to movej except for including inverse kinematics and, more importantly, inverse dynamics. This creates the ever-bothersome problem of singularities in the dynamics. Apart from that, the same problems exist as when moving with movej.

Figure 3.4: Target joint motor currents during a series of overlapping movej commands. One movej command is issued at 0.5 seconds, the next at 1.7s, just before the first finishes, and the third is issued at 3s, way before the second command has finished. Both interruptions lead to acceleration spikes and the second leads to joint torque limit violation.
3.4 The servoj and servoc commands

The code for this test:

```plaintext
sleep (0.5)
servoj (q, 0, 0, 0.8)
sleep (1)
```

These command seems to be essentially a less useful version of movej and movel. They do the job of getting from A to B, but the same stopping behaviour as with movec is exhibited, making the use of this command slightly faster and massively more jerky.

3.5 The speedj command

This command seems to be the only command useful for control real-time control of the robot. The robot accelerates to a set of joint velocities, both velocities and accelerations provided by the user. No combination of interruptions was found that would make the robot attempt accelerations exceeding what was sent in the command.

3.6 The speedl command

For figure 3.5, 3.6 and 3.7 two speedl commands were issued, one at t=0.5s, and then one with a lower speed at t=2s, before the first command finished.

```plaintext
sleep (0.5)
speedl (v1, 0.4, 1.5)
sleep (1.5)
speedl (v2, 0.4, 1.5)
sleep (1.5)
```

It can be seen that the target velocity jumps suddenly at t=2s, causing target acceleration to take a proportionally large value. This causes a very large current which triggers joint torque limit violation. The acceleration limits provided by the command is not enforced. This can be because the trajectory is planned with the limit in mind, but without accounting for current velocity. The reason that the accelerations are heeded in speedj may be that the same assumptions are made and the path is planned accordingly, but since the acceleration limits set by the user is in joint acceleration, it is applied to the joint speeds directly. The same cannot easily be done in the case of speedl.
3.6. The speedl command

![Target Joint velocities](image1)

Figure 3.5: Target joint velocities during two overlapping speedl commands

![Target joint accelerations](image2)

Figure 3.6: Target joint accelerations during two overlapping speedl commands
3.6. The speedl command

Issuing many commands in rapid succession with small incremental changes in speed as one would do in a feedback system also induces jerks. Looking at figures 3.8 and 3.9 where a circular speed pattern was sent to the robot, we can see something interesting. The code used was:

```python
sleep (0.5)
while t<16:
pd = [0,0,0,0,0,0]
pd[0] = pd[0] + 0.1*sin(t)
speedl(pd,0.1,0.009)
t = t + 0.008
sleep(0.008)
end
```

It is generally the case that in order to achieve a specific velocity and rotational velocity in cartesian space, several combinations of joint velocities can be chosen. In this case, it is very likely that each time the inverse dynamics are calculated in order to set the speed in cartesian space, the solution is chosen with some criteria in mind. A sensible criterion would be the lowest sum of joint speeds. Whichever criteria are used do not, it seems, take into account the robot’s current dynamic situation. As such, even though the linear
3.6. The speedl command

motion would be smooth if the target velocities were achieved, massive (infinite) accelerations would be required to do this. In reality, this is not possible, and the sampling time limits the acceleration so that joint torque limit violation does not happen.

The speedl command is tested again, this time by moving in one direction and changing the velocity every 8 ms by a random amount. This is done to simulate a control input which fluctuates a small amount. The code used was:

```python
sleep(0.5)
xd = [0.1, 0, 0, 0, 0, 0]
for 1 to 375:
    xd = [0.1 + randominteger(-1, 1)/100.0, 0, 0, 0, 0, 0]
speedl(xd, 0.4, 0.009)
sleep(0.008)
end
sleep(0.5)
```

The result is shown in Figures 3.10 and 3.11. Here it can be seen that the speedl command handles changes in the target velocity poorly, and it is suspected
3.6. The speedl command

![Graph: Joint acceleration targets during an attempted circular motion using speedl](image)

Figure 3.9: Joint acceleration targets during an attempted circular motion using speedl

that the poor behaviour occurs when the acceleration is opposite the current velocity. This behaviour results in the speedl command being unsuitable for real-time control use.
3.6. The speedl command

Figure 3.10: Target joint velocities during speedl command where the speed set i changed by a random amount every 8 ms
3.6. The speedl command

Figure 3.11: Target joint accelerations during speedl command where the speed set i changed by a random amount every 8 ms
3.7 The stopj command

The stopj command decellerates each joint independently to zero with the specified acceleration. The code used was:

```
sleep(0.5)
servoj(q, 0, 0, 0.8)
sleep(0.8)
stopj(1.0)
sleep(0.5)
```

Figures 3.12 and 3.13 illustrate the functionality of the stop commands. It is a good way to stop motions without causing joint torque limit violation.

![Figure 3.12: Target velocity during execution of servoj command, interrupted by stopj command](image-url)
3.8. The stopl command

The stopl command decelerates the TCP to zero with max joint acceleration specified. The code used was:

```
movec(p_via, p_end, 1, 0.3)
sleep(2)
stopl(1.0)
sleep(1)
```

Figures 3.14 and 3.15 illustrates the functionality of the stopl command. This commands works as expected, and none of the problems with cartesian space commands seen before is seen when using this command. This points to a problem in the inverse dynamics solution when calculating new trajectories.
3.8. The stopl command

Figure 3.14: Target velocity during execution of movec command, interrupted by stopl command
3.8. The stopl command

Figure 3.15: Target accelerations during execution of movec command, interrupted by stopl command
4 Conclusion

From tests we have seen that URScript and the URController is designed for open-loop point-to-point control. The only command that can handle interruptions is speedj, all other commands handle interruption poorly. The bandwidth with which one can expect to control the robot is determined by the 24ms round-trip time.