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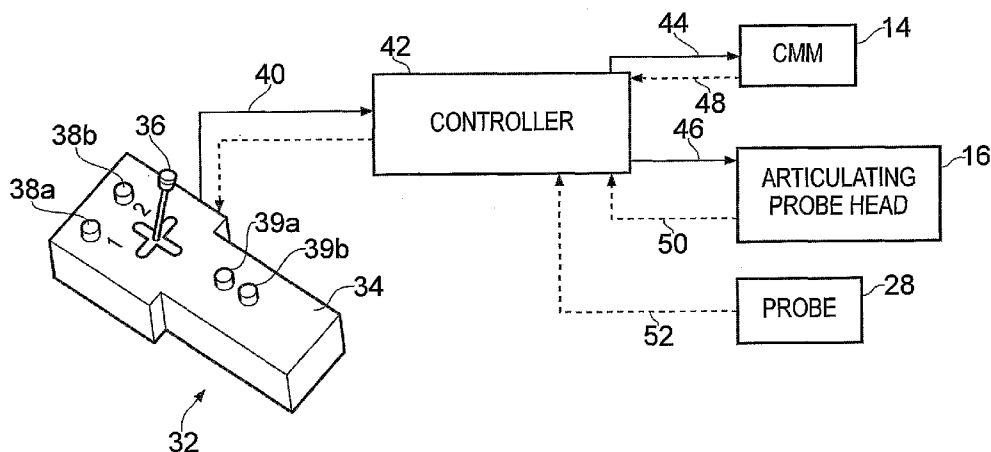


FIG. 3

(57) Abstract: A method and apparatus for controlling or programming a measurement path for a probe mounted on a coordinate positioning apparatus (e.g. an articulating probe head mounted on a CMM) which enables both the position of the probe tip and the orientation of the probe to be varied. In a first mode, the position of the probe tip is adjusted. In a second mode the orientation of the probe is adjusted, whilst keeping the location of the probe tip unchanged. This may be achieved either online on the coordinate positioning apparatus or offline in software.

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Apparatus and method for controlling or programming a
measurement routine.

5 The present invention relates to apparatus and method
for controlling or programming a measurement routine
for the measurement of an object using a measurement
probe mounted on a coordinate positioning apparatus. In
particular the invention is suitable for a probe
10 mounted on an articulating probe head capable of
rotational motion about two axes which is mounted on a
coordinate measuring machine (CMM), machine tool and
the like, or a measurement probe measured directly on
an apparatus providing both linear and rotational
15 motion, such as a manual coordinate measuring arm,
inspection robot etc.

It is common practice after workpieces have been
produced, to inspect them on a coordinate measuring
20 machine (CMM) or other type of coordinate positioning
apparatus having a quill onto which a measurement probe
is mounted which can be driven in three orthogonal
directions X,Y,Z within a working volume of the
machine.

25 US Patent No. 5,189,806 describes an articulating probe
head capable of orientating a probe with two degrees of
freedom to enable the probe to be used in an operation
for scanning the surface of workpieces. In general
30 such a probe head includes two rotary drive mechanisms
which enable a probe to be orientated about two
substantially orthogonal rotary axes. Such an
articulating probe head may be mounted on the quill of
a CMM to enable the probe tip to be positioned in 5
35 degrees of freedom (i.e. 3 linear degrees of freedom
provided by the CMM and 2 rotary degrees of freedom

provided by the articulating probe head).

When a workpiece is to be measured by the probe, the measurement path along which the path will move must be programmed. This may be done by mounting the workpiece on the CMM (or other coordinate positioning apparatus) and using a joystick to move the probe to discrete positions along the desired measurement path. These positions are saved and used to create subsequent measurement paths. When the probe is mounted on an articulating probe head which is in turn mounted on a CMM, movement of both the probe head and CMM may be controlled by a controller. The joystick may be provided with two modes; a first mode for moving the quill of the CMM and a second mode for controlling the articulating probe head to change the angle of the head.

A first aspect of the present invention provides a method for controlling or programming a measurement path for a probe mounted on a coordinate positioning apparatus which enables both the position of the probe tip and the orientation of the probe to be varied, the method comprising the steps of:

(a) adjusting the position of the probe tip or a representation of the probe tip;

(b) adjusting the orientation of the probe or a representation of the probe whilst keeping the location of the probe tip substantially unchanged.

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The coordinate positioning apparatus may comprise the combination of several, e.g. two, individual coordinate positioning apparatuses. For example one apparatus providing linear motion and another providing rotational motion. One of said two or more individual

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coordinate positioning apparatuses may comprise an articulating probe head, typically having two or more axes of rotation. The articulating probe head may be mounted on another coordinate positioning apparatus, such as a coordinate measuring machine (CMM). The coordinate positioning apparatus may comprise a single apparatus which provides both linear and rotational motion, for example a robotic arm.

10 In a first embodiment of the invention, the method is carried out on a coordinate positioning apparatus, and the method comprises the additional step of:

placing an object to be inspected on the coordinate positioning apparatus;

15 and wherein step (a) comprises positioning the probe tip at a desired location with respect to the object.

Step (b) may be used to ensure appropriate alignment of the longitudinal axis of the probe.

In a second embodiment of the invention, the method is carried out in software, and the position of the probe tip and angle of the probe in steps (a) and (b) are adjusted with respect to a 3D model (e.g. CAD) of an object.

In this method the position of the moveable parts of the coordinate positioning apparatus, for example an articulating probe head and movable parts of a coordinate measuring machine, are determined for positions of the probe tip and probe orientation and it is determined whether a collision would occur between the either the coordinate positioning apparatus or

probe and the object.

Preferably a signal is generated when a collision would occur.

5

Preferably this method is implemented by a computer program when run on a computer.

The method may include the step of selecting the
10 position of the probe tip or representation of the
probe tip and the orientation of the probe or
representation of the probe chosen in steps (a) and (b)
as an input used to create the measurement path. The
selected position of the probe tip and probe angle or
15 representation of the probe tip and probe angle may
comprise a 'measurement point' at which a measurement
will be taken or a 'via point' through which the
measurement path will move.

20 A second aspect of the present invention provides a
method for programming a measurement path for a probe
mounted on a coordinate positioning apparatus which
enables both the position of the probe tip and the
orientation of the probe to be varied, comprising the
25 steps of:

(a) placing an object on the coordinate
positioning apparatus;

(b) positioning a handheld device with its tip at
the desired position of the probe tip and its
30 longitudinal axis at the the desired orientation of the
probe;

(c) selecting the position of the tip and
orientation of the longitudinal axis chosen in step
(b);

(d) using the selected position of the tip and angle of the longitudinal axis as the position of the probe tip and probe orientation of a point on the measurement path.

5

A third aspect of the present invention provides apparatus for controlling or programming a measurement path for a probe mounted on a coordinate positioning apparatus which enables both the position of the probe tip and the orientation of the probe to be varied, the
10 apparatus comprising:

a controller for sending demand signals to the coordinate positioning apparatus;

a user interface capable of sending an output to
15 the controller, the user interface having two or more modes;

wherein the controller adjusts the position of the probe tip in response to a first mode;

and wherein the controller adjusts the orientation
20 of the probe in response to a second mode, such that the location of the probe tip is substantially unchanged.

Preferably an output from the user interface to the
25 controller is used to select the position of the probe tip and the angle of the probe as a point on a measurement path.

Preferably the user interface comprises a joystick. The
30 user interface may also comprise a keyboard, for example.

A fourth aspect of the present invention provides a computer programme for programming a measurement path

for a probe mounted on a coordinate positioning apparatus which enables both the position of the probe tip and the orientation of the probe to be varied, the computer programme comprising code adapted to perform
5 the following steps when executed on a computer:

- (a) combining a 3D model of the part and a 3D model of the coordinate positioning apparatus in the same coordinate frame;
- (b) adjusting the position of the model of the
10 coordinate positioning apparatus in response to an input in a first control mode in order to adjust the position of the probe tip within the 3D model;
- (c) adjusting the position of the model of the coordinate positioning apparatus in response to an
15 input in a second control mode, to adjust the orientation of the probe such that the location of the probe tip remains unchanged within the 3D model;
- (d) selecting the probe tip position and probe orientation selected in steps (b) and (c) in response
20 to a selection input

Preferably the computer programme is provided on a carrier, such as a CD, USB stick or other medium, which when loaded onto a computer carries out the invention.
25 The computer program may also be downloaded directly from the internet.

Preferably a signal is generated when a collision would occur.

30

A fifth aspect of the present invention comprises a hand-held device for programming a measurement path for a probe mounted on a coordinate positioning apparatus which enables both the position of the probe tip and

the orientation of the probe to be varied, the hand-held device comprising:

a body having a longitudinal axis and a workpiece contacting tip;

5 a sensor for determining the position of the tip and angle of the longitudinal axis within a coordinate frame;

an output for outputting the position data.

10 Preferably the hand-held device further comprising an input, which on receiving an input records or outputs the position data.

Preferred embodiments of the invention will now be
15 described by way of example with reference to the accompanying drawings wherein:

Fig 1 is a perspective view of a coordinate measuring machine;

Fig 2 is a cross section of an articulating head;

20 Fig 3 is a schematic illustration of a joystick, controller and measuring apparatus;

Figs 4A-4C are perspective views of the position of a probe mounted on an articulating head with respect to a horizontal bore;

25 Figs 5A-5C are perspective views of the positions of a probe mounted on an articulating head with respect to a horizontal bore according to the present invention;

Figs 6A-6C are views of a CAD model of a part and
30 a representation of a probe;

Fig 7 is a view of a CAD model of an inclined part;

Fig 8 is a perspective view of a handheld device;

Figs 9A-9B are side and plan views of a probe

mounted on an articulating head showing lean and lead angles;

Fig 10 illustrates the lean and lead angles; and

Fig 11 is a perspective view of the handheld
5 device of Fig 8 and cameras.

It is known from International Patent Application No. WO90/07097 to mount a motorised articulating probe head on a coordinate measuring machine. The
10 articulating probe head enables a probe or stylus mounted on the articulating probe head to be rotated about two orthogonal axes. Thus the probe or stylus may be positioned angularly about these two axes whilst the articulating probe head can be positioned by the
15 coordinate positioning machine in any position within the working volume of the machine.

Such an articulating probe head provides a coordinate positioning machine with greater scanning flexibility
20 because the articulating probe head can position the probe or stylus in many different orientations.

Fig 1 illustrates an articulating probe head mounted on a coordinate measuring machine (CMM). A workpiece 10 to
25 be measured is mounted on a table 12 of the CMM 14 and a articulating probe head 16 is mounted on a quill 18 of the CMM 14. The quill is driveable in three directions X,Y,Z relative to the table by motors in a known manner.

30
As illustrated in Fig 2, the articulating probe head 16 comprises a fixed part formed by a base or housing 20 supporting a movable part in the form of a shaft 22 rotatable by a motor M1 relative to the housing 20
35 about an axis A1. The shaft 22 is secured to a further housing 24 which in turn supports a shaft 26 rotatable

by a motor M2 relative to the housing 24 about an axis A2 perpendicular to the axis A1.

- A probe 28 with a stylus 29 having a workpiece contacting tip 30 is mounted onto the articulating probe head. The arrangement is such that the motors M1, M2 of the articulating probe head can position the workpiece-contacting tip angularly about the axes A1 or A2 and the motors of the CMM can position the articulating probe head linearly anywhere within the three-dimensional coordinate framework of the CMM to bring the stylus tip into a predetermined relationship with the surface being scanned.
- 15 The articulating probe head may be provided with a third axis which allows a probe mounted on it to be rotated about its own axis.

In such a three axis articulating probe head an additional or separate motor may be used to rotate the probe about its own axis.

Linear position transducers (not shown) are provided on the CMM for measuring linear displacement of the articulating probe head and angular position transducers T1 and T2 are provided in the articulating probe head for measuring angular displacement of the stylus about the respective axes A1 and A2.

- 30 The probe may be a contact probe having a deflectable stylus. In a touch trigger probe, deflection of the stylus causes an output which latches the position of the coordinate positioning apparatus at which the trigger occurred. For a scanning probe, transducers in the probe measure the amount of stylus deflection.
- 35 Alternatively a non contact probe may be used (for

example an optical, capacitance or inductance probe).
The probe may be one dimensional (e.g. a non-contact
probe which senses distance from surface), two
dimensional (e.g. a contact probe sensing deflection in
5 X and Y) or three dimensional (e.g. a contact probe
sensing deflection in X,Y and Z).

On a vertical arm CMM as shown in Fig 1, the A1 axis of
the articulating probe head 16 is nominally parallel
10 to the CMM Z axis (which is along the spindle 18). The
articulating probe head may rotate the probe
continuously about this axis. The A2 axis of the
articulating probe head is orthogonal to its A1 axis.

15 When a part is to be measured, the measurement path
which is to be followed by the measurement apparatus
must be programmed. This may be done either 'online'
or 'offline'.

20 Online programming of the measurement path will now be
described with reference to Figs 3-5. In online path
programming, the path is programmed by placing the part
on the table of the CMM and moving the measurement
apparatus around the part. Typically a user interface,
25 such as a joy stick is used to move the measurement
apparatus. Different modes enable the joystick to move
either the CMM quill or control the angles of the
articulating probe head.

30 Fig 3 illustrates the joystick 32 which has a body 32
and a stick 36. Mode selection buttons 38a,38b are
provided on the body 32 to enable the user to select
the desired mode. A position selection button 39 is
provided to enable the user to select a probe position.
35 This buttons 39 enables via points to be selected (as
will be described in more detail below).

The joystick 32 has an output 40 to a controller 42. The controller 42 may comprise for example a PC or CMM controller. The controller 42 has outputs 44,46 to the
5 CMM 14 and articulating probe head 16 through which it can send demand signals to the motors of the CMM and articulating probe head to control their positions. The controller 42 has inputs 48,50,52 from the CMM,
10 articulating probe head and probe respectively which provides position information from the transducers in these parts. From these inputs, the controller can determine the position of the workpiece contacting tip of the probe stylus.

15 Figs 4A-4C illustrate the steps of a known method for positioning the stylus relative to a part which includes a horizontal bore 54. In Fig 4A, the stylus tip is at the wrong position and the stylus is at the wrong angle. The joystick is used in one mode to adjust
20 the articulating probe head angles until the stylus 29 is parallel to the centre line 58 of the bore 54 as shown in Fig 4B. The joystick is then switched into a separate mode and used to adjust the position of the quill 18. Fig 4C shows the stylus positioned along the
25 centre line of the bore. The stylus tip can thus be brought into contact with internal surfaces of the bore 54.

Measurements are taken of discrete points on the
30 internal surface of the bore which enables the feature type (in this case a circle), orientation and dimensions to be determined. From this data, a measurement path can be calculated.

35 During the adjustment of the head angles, care must be taken that no part of the stylus collides with the

surface. Therefore, several iterations tend to be used in positioning the quill and head angles to avoid the stylus tip becoming too close to the surface.

5 In the present invention, two different modes are created. In a first mode, the position of the CMM quill is adjusted in three dimensions whilst the head angles remain stationary, to thereby adjust the stylus tip position. Alternatively, the first mode may entail
10 adjustment of the articulating probe head, about the two rotary axes whilst the CMM quill remains stationary, which also has the effect of adjusting the stylus tip position.

15 In the second mode, the stylus tip position remains stationary whilst the stylus angle is adjusted. Adjustment of the stylus angle requires movement in some or all of the two axes of the articulating probe head and three axes of the CMM.

20 By using the two modes of the present invention, the stylus tip can easily be adjusted to the desired position and angle.

25 Thus to place the stylus tip at a desired position and angle, only two adjustments are required. The first mode is used to position the stylus tip and the second mode is used to adjust the stylus angle. No further iterations are required.

30 Figs 5A-5C illustrate the steps of positioning the stylus relative to a horizontal bore 54 according to the present invention. In Fig 5A the stylus tip is in the wrong position and the stylus is at the wrong
35 angle. The joystick is used in a first mode to adjust the position of the quill 18 and thereby place the

stylus tip 30 in the desired position in the centre of the bore. In Fig 5C the joystick is used in a second mode to move both the quill 18 and the articulating probe head 16 to adjust the angle of the stylus 29 without moving the stylus tip 30. The stylus is now correctly positioned with the stylus tip 30 in the surface of the bore 54 and the longitudinal axis of the probe aligned along the centre line 58 of the bore 54.

10 The joystick has a button or other input (see 39 in Fig 2), which enables the user to select 'via' points (i.e. points not on the surface, which the measurement path will move through). The discrete measurement points taken of the surface are used to calculate a measurement path incorporating measurement points.

This invention is also suitable for controlling the probe tip position and probe orientation via the joystick for measurement of an object.

20 Although Fig 3 illustrates the use of a joystick for on-line programming, other control devices may also be used. Alternatively, a computer keyboard can be used, possibly in combination with a mouse or trackball.

25 The controller may be provided with a 'snap' function. The controller may receive a position input from the joystick and output demands to the nearest predetermined value. For example, the stylus orientation may be demanded to the nearest 5°. This snap function may be enabled by the joystick sending an output to the controller, such as the joystick being released, causing the controller to enter the snap mode and move the articulating probe head to the nearest angle (in this example the nearest 5°)

The invention is suitable for both contact and non contact probes (e.g. optical, capacitance and inductance probes). For non contact probes, a measurement is typically taken when the probe tip is at a threshold distance from the surface. Therefore, as with a contact probe, discrete measurement points of the surface are input automatically into the controller for calculating the measurement path whereas via points must be selected via the joystick.

The measurement path can be planned in software, rather than using a joystick. This is referred to as 'off-line part programming' and will be described with reference to figs 6-7.

Figs 6A-C illustrates a CAD model of a part 60 and a representation of the probe 62. Other representations of the measuring apparatus, e.g. comprising quill, articulating probe head and probe or simply a vector showing the stylus position and angle may be used. Fig 6A shows the probe out of contact with the CAD model of the part. As with online part programming two modes are provided to adjust the stylus tip position and angle respectively. As before the first mode adjusts the stylus tip position by moving the quill. Fig 6B illustrates the representation of the probe 62 now in contact with the CAD model 60, with the same angle as in Fig 6A. Alternatively the first mode could comprise moving the stylus tip by adjustment of the articulating probe head.

The second mode adjusts the stylus angle by moving both the quill and articulating probe head. Fig 6C shows the representation of the probe 62 has changed angle whilst the point of contact remains the same as in Fig 6B.

The user can select modes and adjust the position of the representation of the probe by an interface such as a keyboard, joystick, mouse or trackball. The user can select the measurement points or via points which have
5 the desired stylus tip position and angle.

The user may be able to select between a subset of the available axes (e.g. 3axis motion provided by the CMM or 2axis motion provided by the articulating probe
10 head) or the full set of available axes (e.g. 5 axis motion provided by both CMM and articulating probe head). This selection between may be made by a variety of inputs. For example the user may click on icons on the screen or the image of the desired measurement
15 apparatus (e.g. CMM for 3 axis motion, articulating probe head for 5 axis motion or probe for 2 axis motion). Alternatively, the user may select modes by using the keyboard. When in a selected mode, a mouse, trackball, keyboard or other input is used to move the
20 selected measurement apparatus (according to the mode) relative to the 3D model of the part.

When path planning, it is important to avoid collision between the part and the measuring apparatus. This is
25 particularly the case with an inclined part, when vertical movement of the measuring apparatus may collide with the incline.

Fig 7 illustrates a CAD model of an inclined part 64.
30 Representations of the probe 62 are shown in two places - positions A and B. The locations of the articulating probe head 16 and quill 18 required to position the probe in these positions are illustrated in dashed outline. It can be seen that at A there is adequate
35 clearance but at B a collision could result. To inform the user of the risk of collision, a warning is

created. For example the CAD model may change colour, or an audible warning may be produced.

In an alternative embodiment, a hand-held device is
5 used to mimic the position of the probe. This device
may be used to set stylus tip position and stylus angle
for points on the measurement path. Such a hand-held
device 66 is illustrated in Fig 8 and comprises a body
68 with a workpiece contacting tip 70 and a
10 longitudinal axis 72. It also includes apparatus to
enable both its position and orientation to be
determined. It may include accelerometers, may use
cameras or ultrasonic equipment, for example as
disclosed in US2007032951. The hand-held device may
15 have a surface provided with an illuminated pattern,
for example a pattern of LEDs. Two cameras may be
provided at an angle from one another in the working
volume of which the hand-held device will be used. The
illuminated pattern is detected by the two cameras and
20 the two images are used to determine the position and
orientation of the hand-held device. Such a system of
determining the coordinate position of a probe provided
with electromagnetic emitters using cameras and a
computer is described in US6115927. A commercially
25 available probe which uses light emitters to determine
its position is manufactured by Leica Geosystems and is
known as the Leica T probe.

Fig 11 illustrates the hand-held device 66 of Fig 8,
30 showing an array of LEDs 80 located on the body of the
coordinate positioning apparatus. Two cameras 82,84 are
located on the machine body, spaced apart and angled
relative to one another, both directed towards the
device. Outputs from the cameras 82,84 are sent to the
35 controller 42 which uses the data to determine the
position and orientation of the device.

The hand-held device may also be rotated about its longitudinal axis to mimic a third axis of the articulating probe head, in which it provides rotation
5 of the probe about it's longitudinal axis.

The hand-held device also has communication apparatus, such as optical, radio *or communication via a wire* to communicate its position to a controller or pc. An
10 optical transmitter 74 is shown in the body which communicated with an optical receiver 76 connected to the controller 42.

The user may place the hand-held device around the part
15 along the measurement path. A button 78 or other input is provided to allow the user to select whether a measurement point or via point is required. When the button is pressed, both the position of the tip and the orientation is recorded and output via the
20 communication apparatus.

The user may thus easily program how much 'lean' and 'lead' is required. 'Lean' is the angle of the probe from the surface vertical. 'Lead' is the angle of the
25 probe from the direction of travel.

Figs 9A and 9B illustrate a side and plan view of a probe mounted on an articulating probe head respectively. Fig 9A shows that the probe is α° from
30 the vertical - this is the lean angle. Fig 9B shows that the probe is β° from the direction of travel - this is the lead angle.

Fig 10 shows the lean and lead angles in more detail.
35 A probe mounted on an articulating probe head is illustrated, moving in a direction A. The surface

normal B and CMM vertical C are also shown. A line D is drawn extending from the probe tip to the CMM vertical C; line D is in the plane of direction of travel A and surface normal B. The angle between line D and the surface normal B is the lead angle. The angle between the longitudinal axis of the probe and the CMM vertical is the lean angle.

The software in the controller or pc will be provided with a set of rules, governing a range of optimal lean and lead angles. The optimal angles closest to the actual angles which the user holds the hand-held device are selected.

Although the above description describes the use of an articulating probe head on a coordinate measuring machine, the invention is also suitable for a probe mounted on other coordinate positioning apparatus which enables the position of the probe tip or orientation of the probe to be adjusted. Such a coordinate positioning apparatus may comprise a combination of apparatuses, such as an articulating probe head mounted on a CMM (as described) or machine tool. Alternatively, the coordinate positioning apparatus may comprise one piece of apparatus which can both position and orient the probe, e.g. a robotic arm. In all of these apparatus the same considerations of moving the probe tip about a part without collision apply.

Claims

1. A method for controlling or programming a measurement path for a probe mounted on a coordinate positioning apparatus which enables both the position of the probe tip and the orientation of the probe to be varied, the method comprising the steps of:
- 5 (a) adjusting the position of the probe tip or a representation of the probe tip;
- 10 (b) adjusting the orientation of the probe or a representation of the probe whilst keeping the location of the probe tip substantially unchanged.
2. A method according to claim 1 wherein the method is carried out on a coordinate positioning apparatus, and the method comprises the additional step of:
- 15 placing an object to be inspected on the coordinate positioning apparatus;
- and wherein step (a) comprises positioning the probe tip at a desired location with respect to the object.
- 20 3. A method according to claim 1 wherein the method is carried out in software, and the position of the probe tip and orientation of the probe in steps (a) and (b) are adjusted with respect to a 3D model (e.g. CAD) of an object.
- 25 4. A method according to claim 3 wherein the method includes the step of determining the required positions of the moveable parts of the coordinate positioning apparatus to achieve said positions of the probe tip and probe orientation and determining whether a collision would occur between either the coordinate
- 30

positioning apparatus or probe and the object.

5. A method according to claim 4 wherein a signal is generated if a collision would occur.

5

6. A method according to any of claims 3-5 wherein the method is implemented by a computer program when run on a computer.

10 7. A method according to any preceding claim wherein the method includes the step of selecting the position of the probe tip or representation of the probe tip and the orientation of the probe or representation of the probe chosen in steps (a) and (b) as an input used to
15 create the measurement path.

8. A method according to claim 7 wherein the selected position of the probe tip and probe angle or representation of the probe tip and probe angle
20 comprises a 'measurement point' at which a measurement will be taken or a 'via point' through which the measurement path will move.

9. A method for programming a measurement path for a
25 probe mounted on a coordinate positioning apparatus which enables both the position of the probe tip and the orientation of the probe to be varied, comprising the steps of:

(a) placing an object on the coordinate
30 positioning apparatus;

(b) positioning a handheld device with its tip at the desired position of the probe tip and its longitudinal axis at the the desired orientation of the probe;

(c) selecting the position of the tip and orientation of the longitudinal axis chosen in step (b);

(d) using the selected position of the tip and angle of the longitudinal axis as the position of the probe tip and probe orientation of a point on the measurement path.

10. Apparatus for controlling or programming a measurement path for a probe mounted on a coordinate positioning apparatus which enables both the position of the probe tip and the orientation of the probe to be varied, the apparatus comprising:

a controller for sending demand signals to the coordinate positioning apparatus;

a user interface capable of sending an output to the controller, the user interface having two or more modes;

wherein the controller adjusts the position of the probe tip in response to a first mode;

and wherein the controller adjusts the orientation of the probe in response to a second mode, such that the location of the probe tip is substantially unchanged.

25

11. Apparatus according to claim 10 wherein an output from the user interface to the controller is used to select the position of the probe tip and the orientation of the probe as a point on a measurement path.

30

12. Apparatus according to any of claims 10 or 11 wherein the user interface comprises a joystick.

13. A computer programme for programming a measurement path for a probe mounted on a coordinate positioning apparatus which enables both the position of the probe tip and the orientation of the probe to be varied, the
5 computer programme comprising code adapted to perform the following steps when executed on a computer:

- (a) combining a 3D model of the part and a 3D model of the coordinate positioning apparatus in the same coordinate frame;
- 10 (b) adjusting the position of the model of the coordinate positioning apparatus in response to an input in a first control mode in order to adjust the position of the probe tip within the 3D model;
- (c) adjusting the position of the model of the
15 coordinate positioning apparatus in response to an input in a second control mode, to adjust the orientation of the probe such that the location of the probe tip remains unchanged within the 3D model;
- (d) selecting the probe tip position and probe
20 orientation selected in steps (b) and (c) in response to a selection input

14. A hand-held device for programming a measurement path for a probe mounted on a coordinate positioning
25 apparatus which enables both the position of the probe tip and the orientation of the probe to be varied, the hand-held device comprising:

- a body having a longitudinal axis and a workpiece contacting tip;
- 30 a sensor for determining the position of the tip and angle of the longitudinal axis within a coordinate frame;
- an output for outputting the position data.

23

15. A hand-held device according to claim 14 further comprising an input, which on receiving an input records or outputs the position data.

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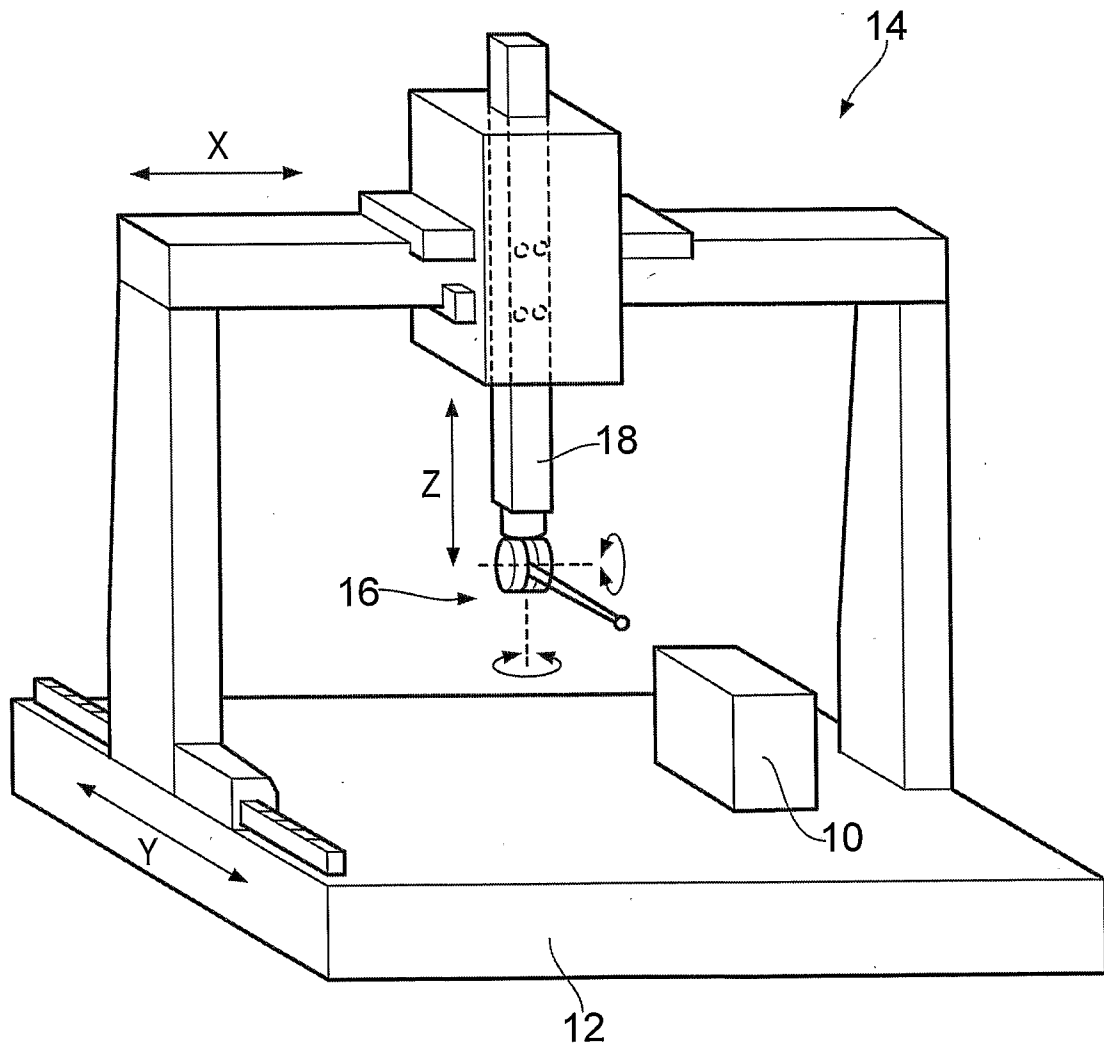


FIG. 1

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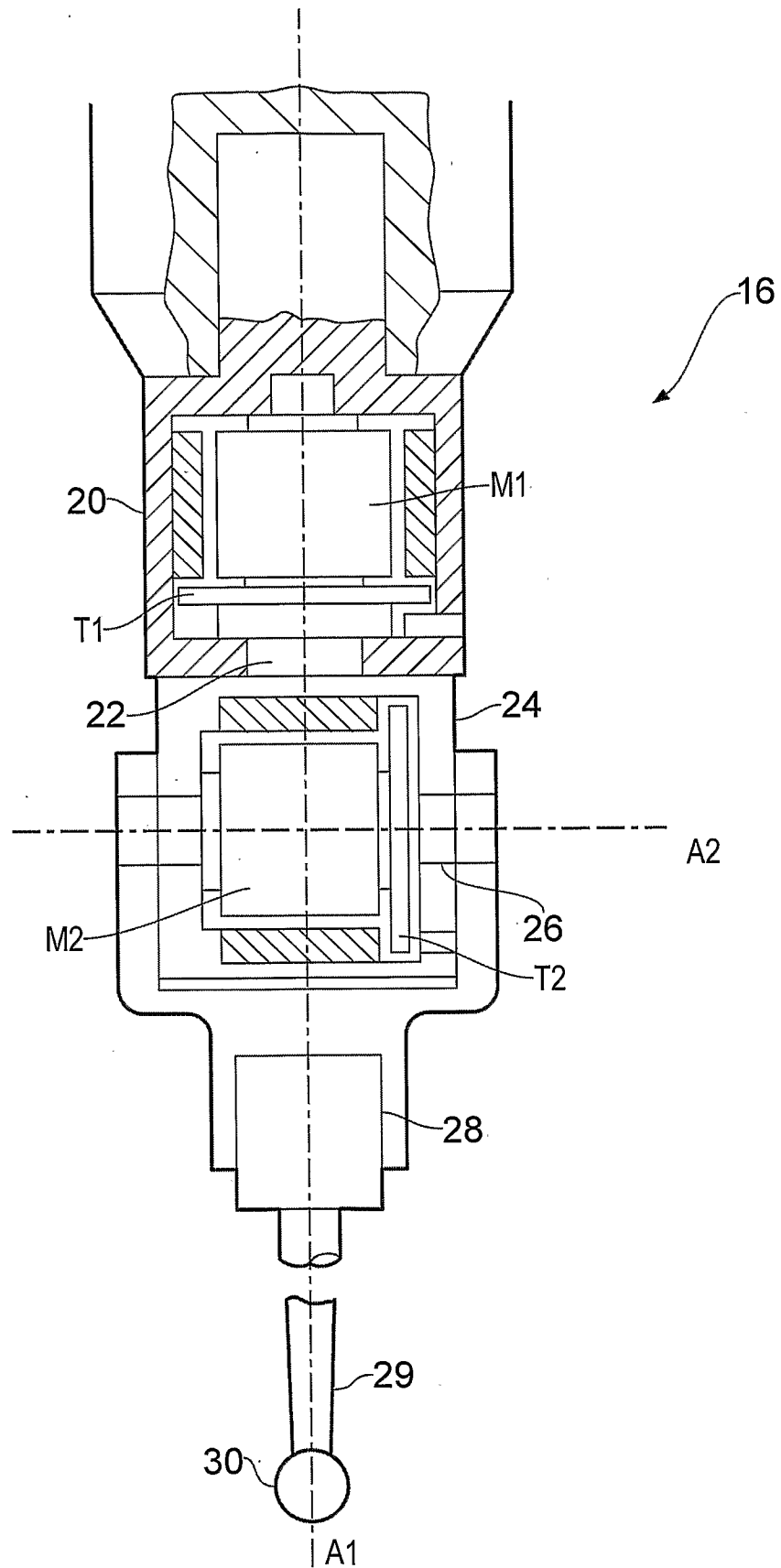


FIG. 2

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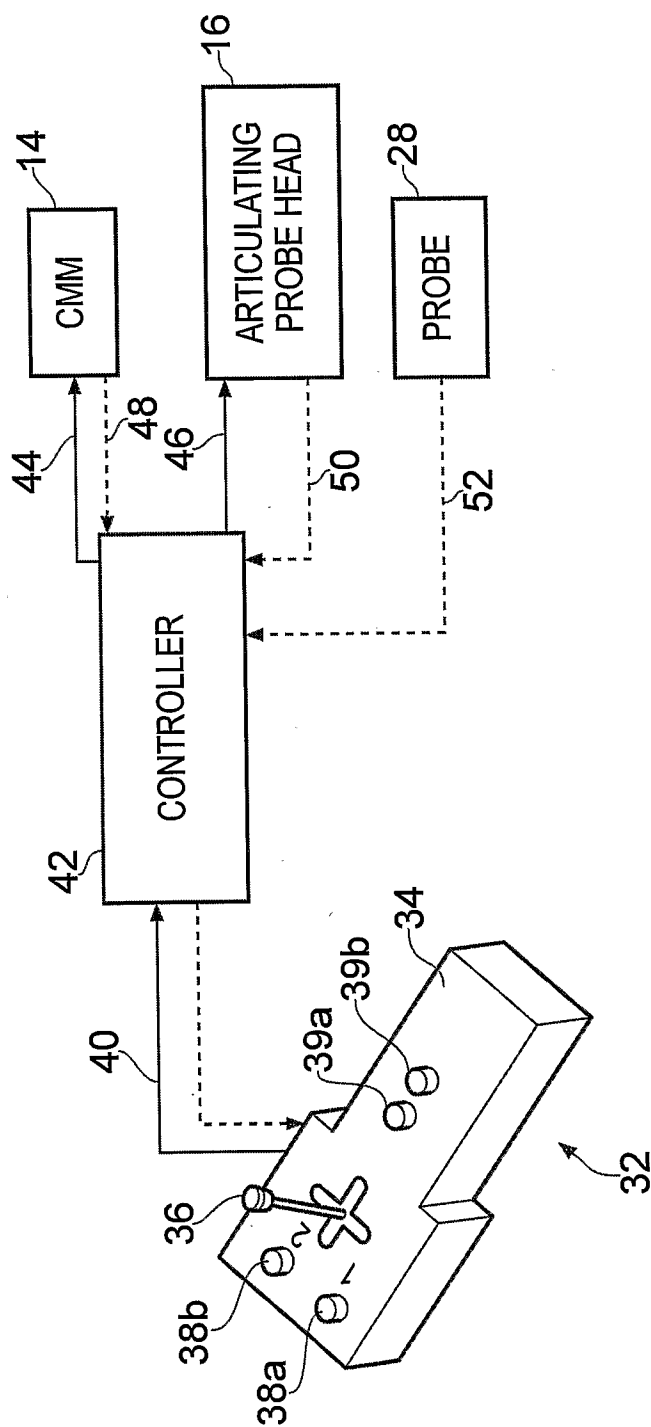


FIG. 3

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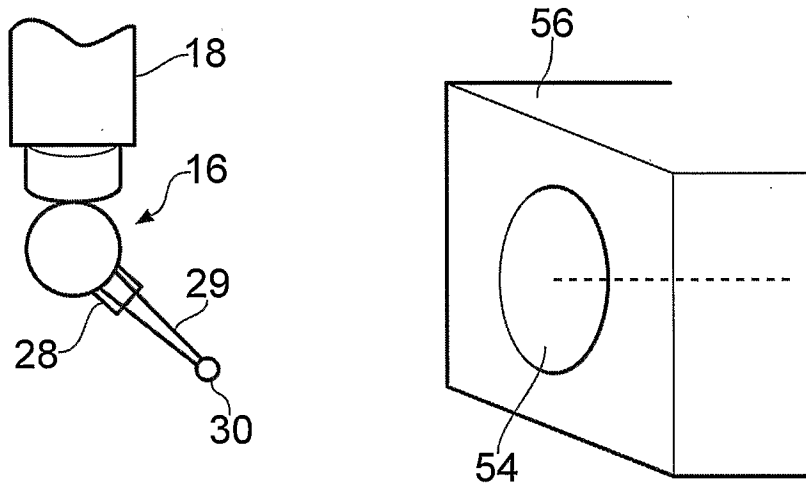


FIG. 4a

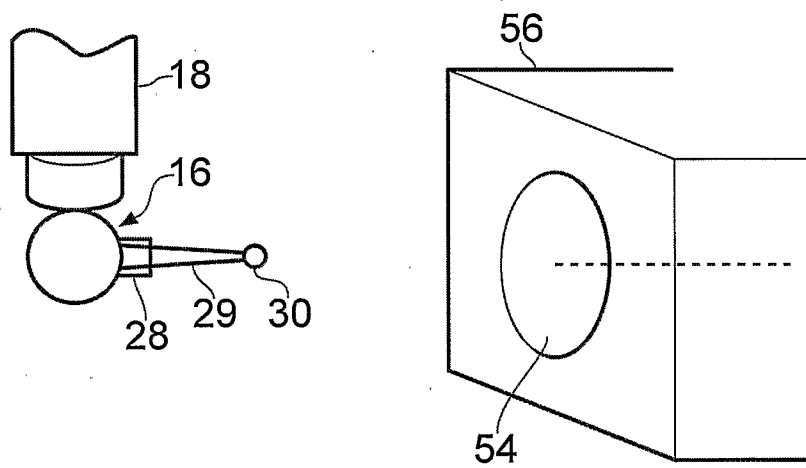


FIG. 4b

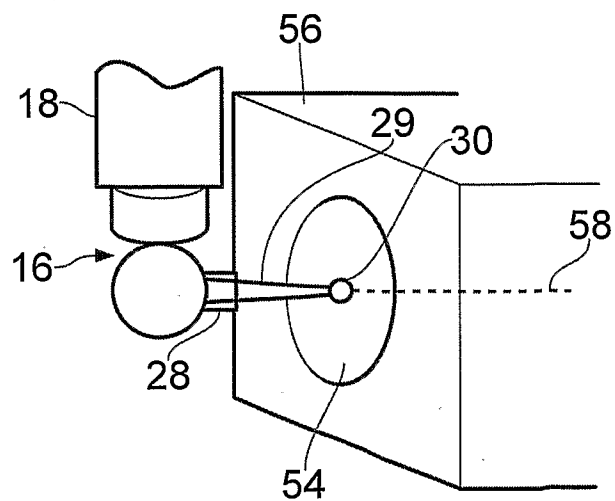


FIG. 4c

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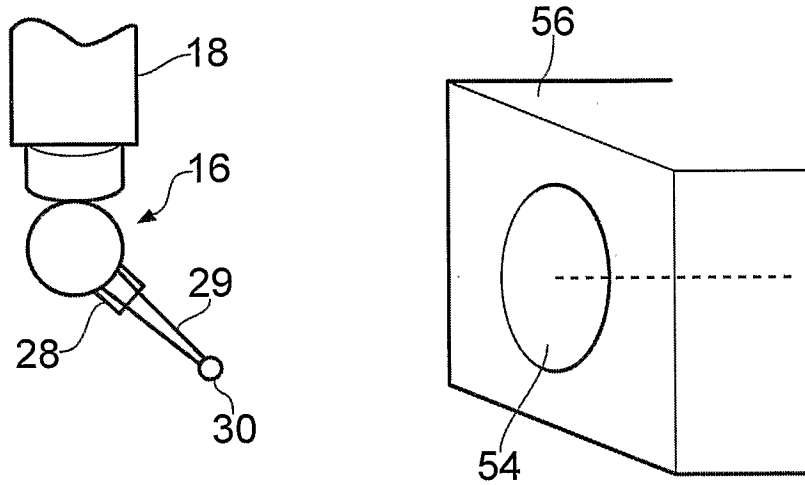


FIG. 5a

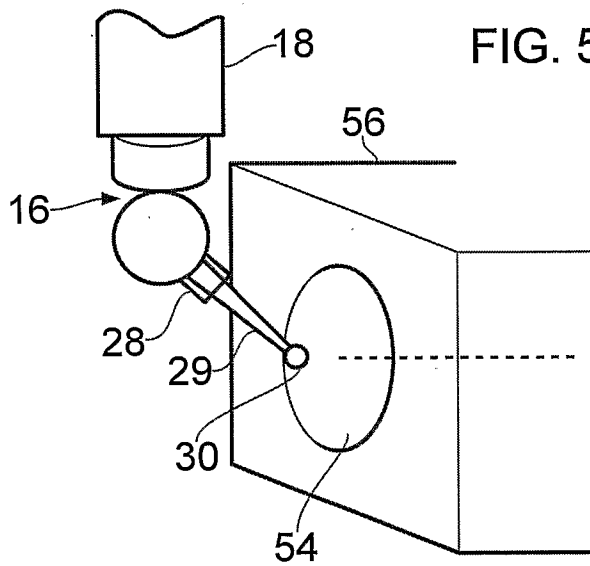


FIG. 5b

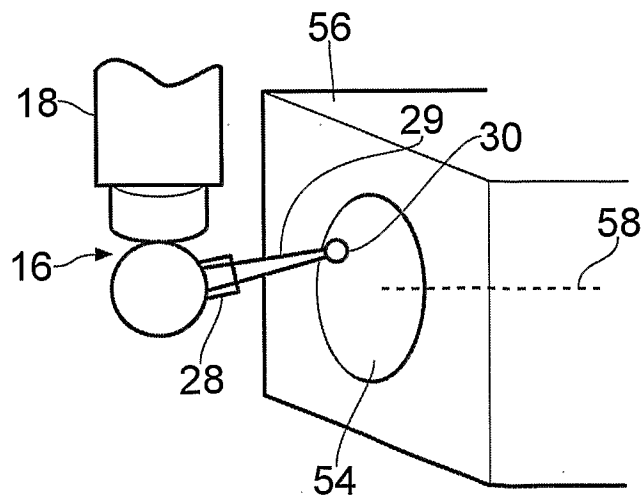


FIG. 5c

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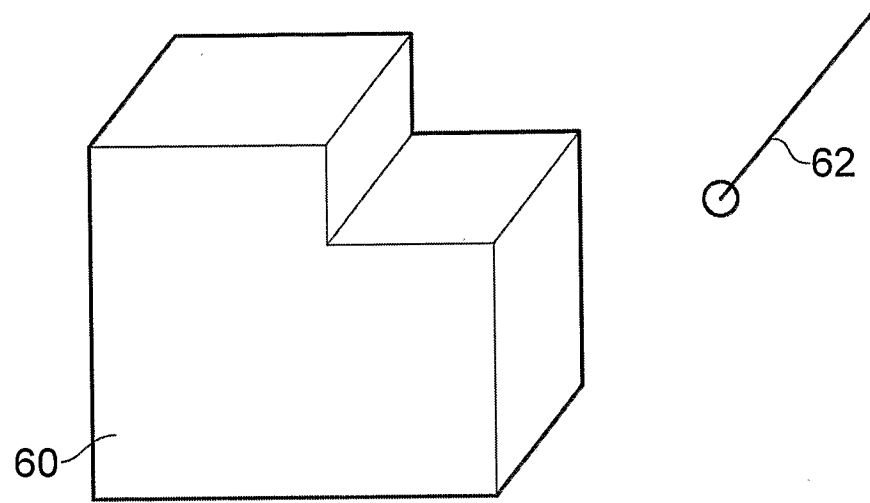


FIG. 6a

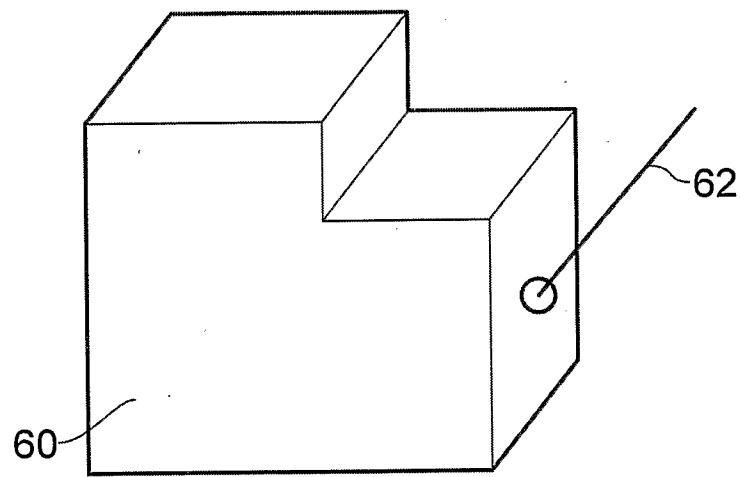


FIG. 6b

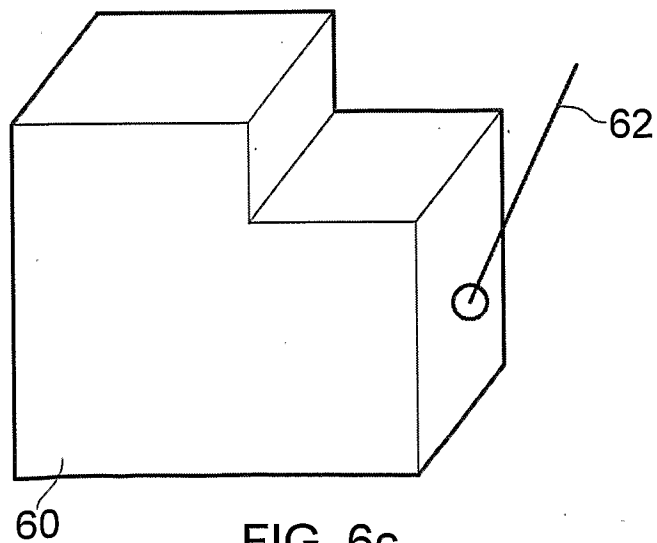


FIG. 6c

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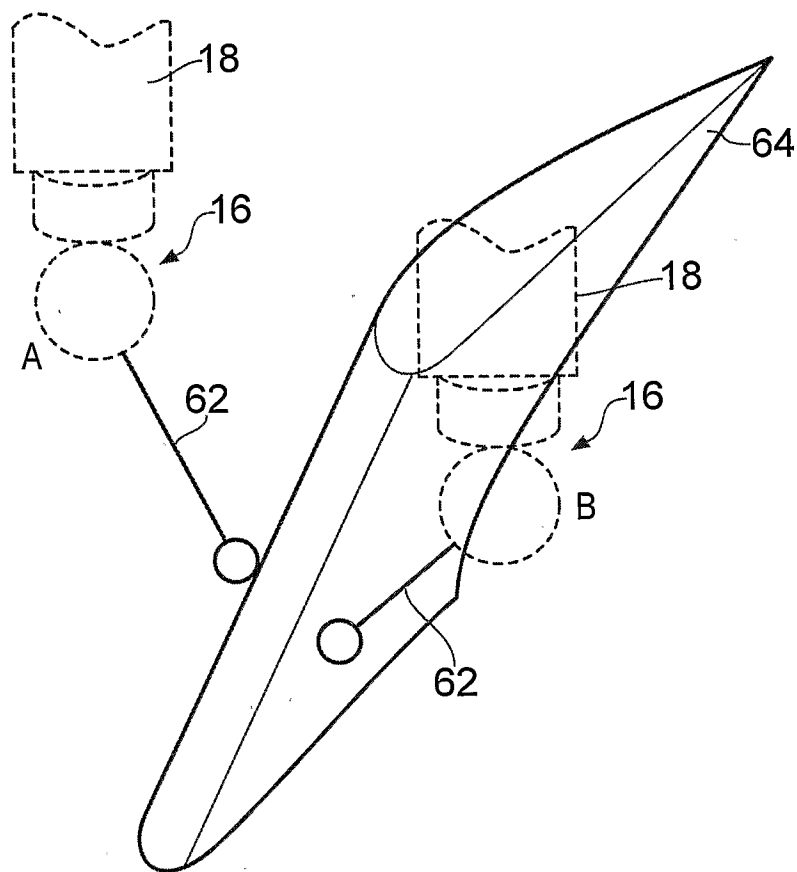


FIG. 7

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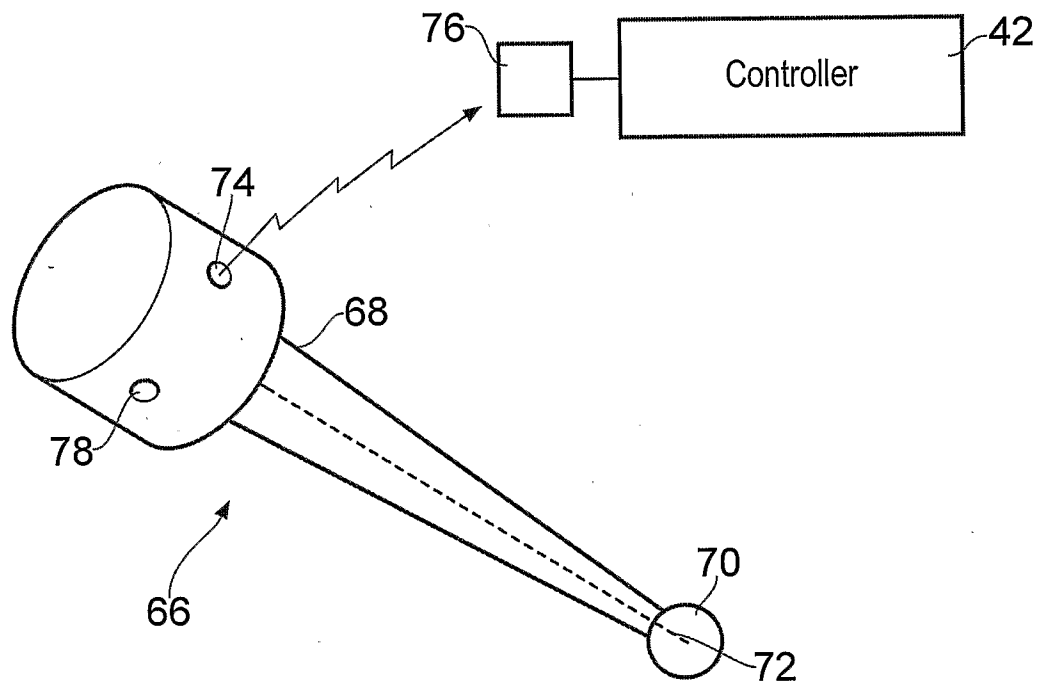


FIG. 8

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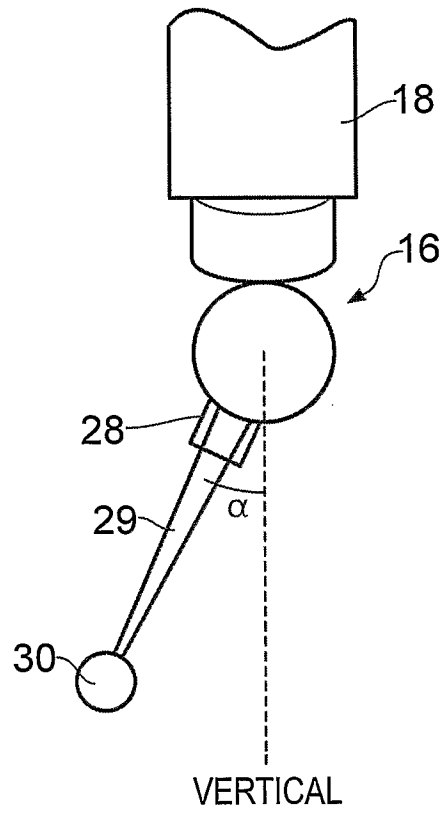


FIG. 9A

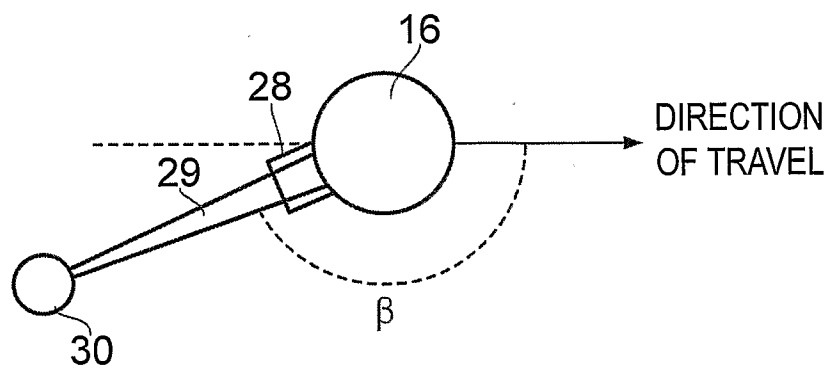


FIG. 9B

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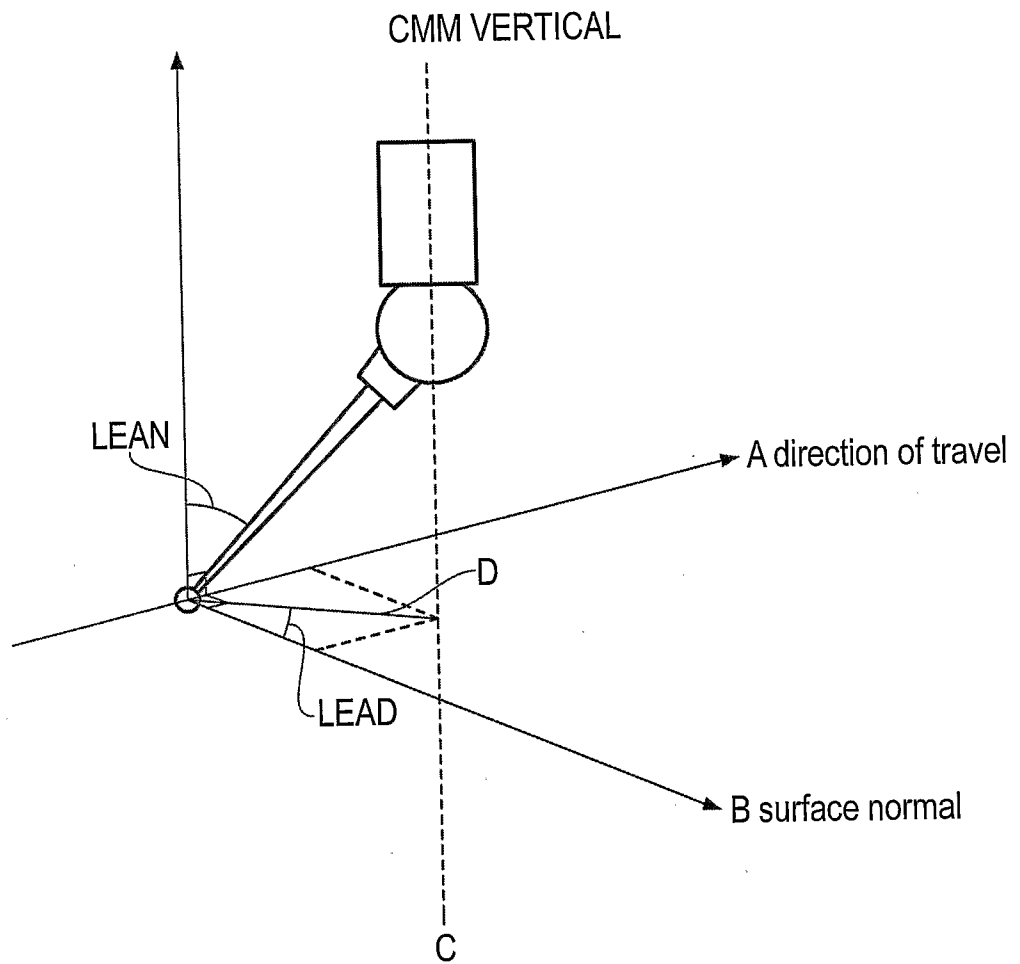


FIG. 10

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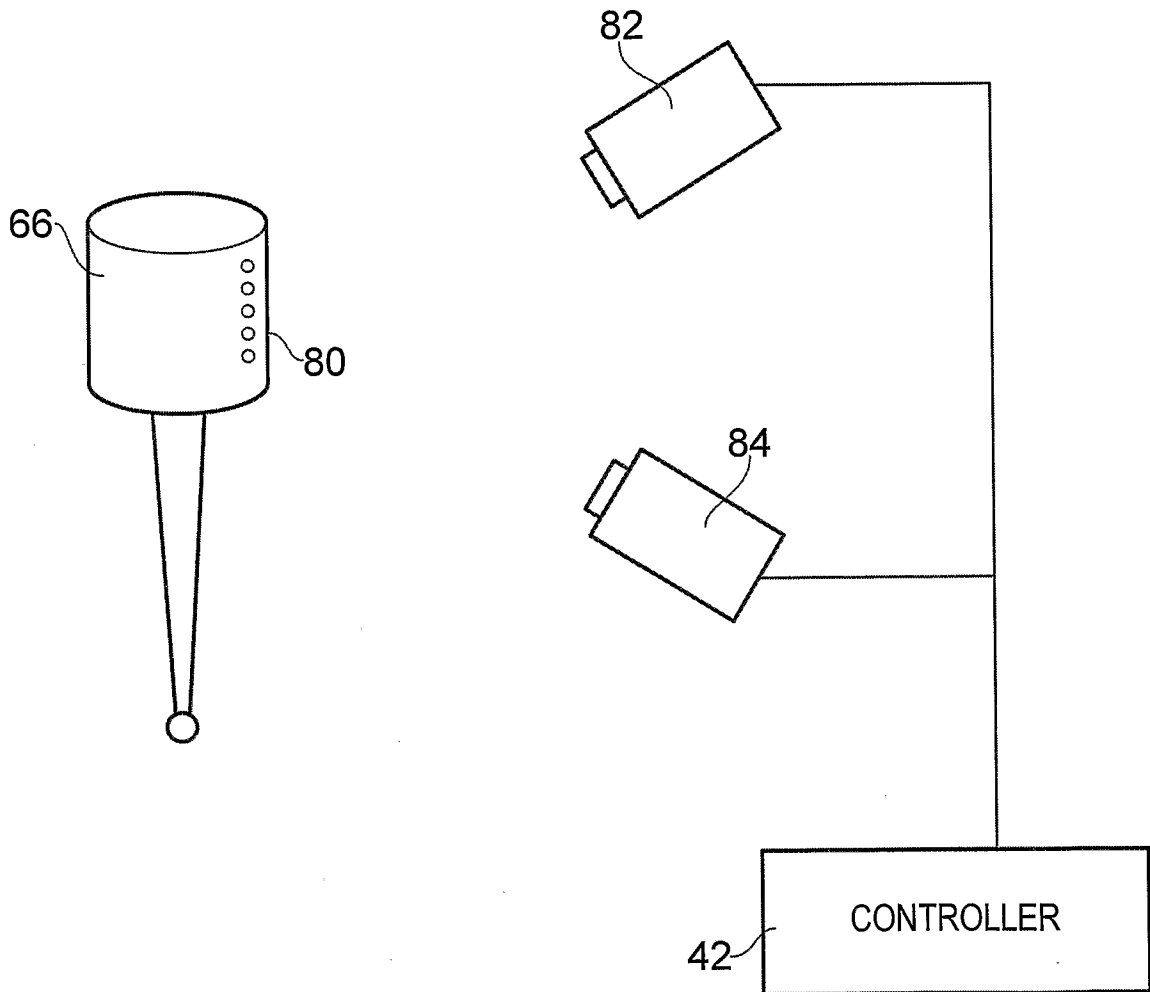


FIG. 11