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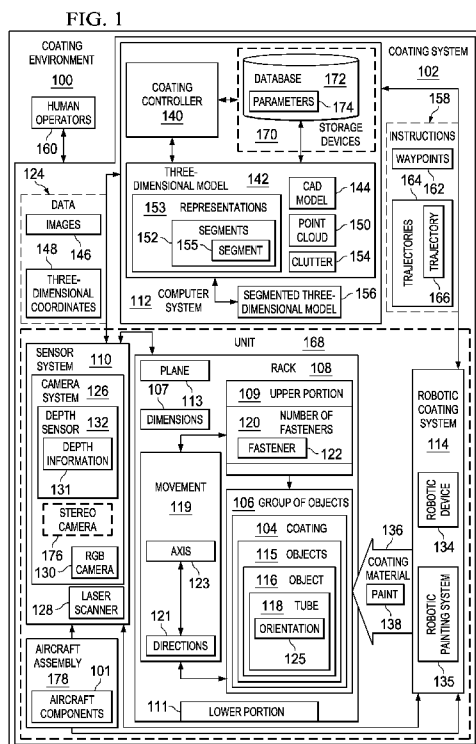
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(54) Title: ROBOTIC OBJECT COATING SYSTEM



(57) **Abstract:** A method and apparatus for coating a group of objects may be provided. A three-dimensional model of the group of objects may be generated. Segments that represent each object in the group of objects in the three-dimensional model may be formed. Instructions for coating the group of objects may be generated based on the segments. The instructions may be configured to cause a robotic coating system to coat the group of objects.

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ROBOTIC OBJECT COATING SYSTEM**BACKGROUND INFORMATION****1. Field:**

The present disclosure relates generally to manufacturing objects, and in particular, to applying a coating to objects. Still more particularly, the present disclosure relates to a method and apparatus for coating objects with a robotic object coating system.

2. Background:

The process for manufacturing components for aircraft and other vehicles may be very complex and time-consuming.

Components may be manufactured in various stages in which different types of components are fabricated, molded, coated, and tested.

These stages may be performed by robotic systems, human operators, or both robotic systems and human operators. For example, a component for a fuel tank may be fabricated, painted, installed, and/or inspected by a human operator, a robotic system, or some combination thereof.

In some cases, an aircraft may have thousands of components that need to be painted. Consequently, paint may be applied to many different components at one time. For instance, five, ten, fifteen or more objects may be painted during the same interval.

When applying paint or other types of coatings, the components may be arranged on a component carrier, cart, or rack. In some cases, more than one type of component may be present on the component carrier at the same time. Different types of components may have the same or different sizes, shapes, weights, or other characteristics from each other.

Currently, component painting may typically be completed by human painters. However, the painting of aircraft components

may be more physically demanding on painters than desired. For example, painters may typically wear head-to-toe protective clothing to limit exposure to toxic chemicals found in the paint. Additionally, painters may carry large reservoirs of paint that may be difficult to maneuver in order to paint the components in a preferred manner. Because these reservoirs may be difficult to maneuver, the painters may become exhausted more quickly than desired.

In some cases, a pre-programmed robotic system may be used to limit exposure by human painters to chemicals in the paint. With robotic painting systems, a controller provides instructions to the robot to paint the objects arranged on the component carrier. However, this type of painting system may not be as accurate as desired. For example, pre-programmed robotic painting systems may have a large margin of error. As a result, a human painter may be needed to inspect and repaint some of the components. This type of process may take more time and effort than desired. Accordingly, there is a need for a method and apparatus which take into account at least some of the issues discussed above, as well as possibly other issues.

SUMMARY

In one illustrative embodiment, a method for coating a group of objects may be presented. A three-dimensional model of the group of objects may be generated. Segments that represent each object in the group of objects in the three-dimensional model may be formed. Instructions for coating the group of objects may be generated based on the segments. The instructions may be configured to cause a robotic coating system to coat the group of objects.

In another illustrative embodiment, a method for painting a group of tubes may be provided. A three-dimensional model of the group of tubes may be generated. Segments for the group of

tubes may be formed in the three-dimensional model.

Instructions for painting the group of tubes may be generated based on the segments. The instructions may be configured to cause a robotic painting system to paint the group of tubes.

5 In yet another illustrative embodiment, an apparatus may comprise a coating controller configured to generate a three-dimensional model of a group of objects. The coating controller may be further configured to form segments for the group of objects in the three-dimensional model and generate instructions
10 for coating the group of objects based on the segments. The instructions may be configured to cause a robotic coating system to coat the group of objects.

 In still another illustrative embodiment, a method for coating a group of objects may be presented. A three-
15 dimensional model of the group of objects comprising at least one of an aircraft part, a tube, a spar, a reservoir, a stringer, a panel, or a barrel may be generated. The three-dimensional model may be generated in real time and selected from one of a point cloud and a computer-aided design model.
20 Generating the three-dimensional model of the group of objects may comprise generating data about the group of objects using a sensor system associated with a robotic coating system. The sensor system may be selected from one of a camera system or a laser scanner and may comprise a depth sensor. The data may be
25 selected from at least one of images or three-dimensional coordinates for a surface of the group of objects. Generating the three-dimensional model may further comprise generating the three-dimensional model of the group of objects from the data generated by the sensor system. Segments may be formed that
30 represent each object in the group of objects in the three-dimensional model. Forming the segments may comprise identifying clutter in the three-dimensional model and separating objects in the group of objects from the clutter to form a segmented three-dimensional model. Instructions may be

generated for coating the group of objects based on the segments. The instructions may be configured to cause a robotic coating system to coat the group of objects. The instructions may comprise at least one of waypoints or trajectories.

5 Generating the instructions may comprise identifying the waypoints along an object in the group of objects and generating a trajectory for movement of the robotic coating system along the object from the waypoints. The robotic coating system may be operated to apply a coating to the group of objects using the
10 instructions. The coating may be selected from one of a paint, an adhesive, a sealant, a lubricant, a wear resistant coating, a corrosion resistant coating, and a scratch resistant coating.

In yet another illustrative embodiment, a method for painting a group of tubes may be provided. A three-dimensional
15 model of the group of tubes may be generated. Segments for the group of tubes may be formed in the three-dimensional model. Instructions may be generated for painting the group of tubes based on the segments. The instructions may be configured to cause a robotic painting system to paint the group of tubes.
20 Generating the instructions may comprise selecting waypoints along a tube in the group of tubes and generating a trajectory for movement of the robotic painting system along the tube from the waypoints. The robotic painting system may then be operated to apply paint to the group of tubes using the instructions.

25 In still another illustrative embodiment, an apparatus includes a coating controller, a sensor system, and a robotic coating system. The coating controller may be configured to generate a three-dimensional model of a group of objects from data about the group of objects. The coating controller may be
30 further configured to form segments for the group of objects in the three-dimensional model and generate instructions for coating the group of objects based on the segments. The instructions may be configured to cause the robotic coating system to coat the group of objects. The coating may be

selected from one of a paint, an adhesive, a sealant, a lubricant, a wear resistant coating, a corrosion resistant coating, and a scratch resistant coating. The group of objects may comprise at least one of an aircraft part, a tube, a spar, a reservoir, a stringer, a panel, or a barrel. The sensor system may be configured to generate the data about the group of objects. The sensor system may comprise a depth sensor and may be selected from one of a camera system and a laser scanner. The robotic coating system may be configured to receive the instructions and use the instructions to apply a coating to the group of objects. The robotic coating system may be configured to be a robotic painting system. The instructions include painting trajectories for the robotic coating system to paint the group of objects.

In summary, according to one aspect of the invention there is provided a method for coating a group of objects, the method including generating a three-dimensional model of the group of objects; forming segments that represent each object in the group of objects in the three-dimensional model; and generating instructions for coating the group of objects based on the segments, in which the instructions are configured to cause a robotic coating system to coat the group of objects.

Advantageously the method wherein the three-dimensional model is generated in real time.

Advantageously the method further including operating the robotic coating system to apply a coating to the group of objects using the instructions.

Advantageously the method wherein the coating is selected from one of a paint, an adhesive, a sealant, a lubricant, a wear resistant coating, a corrosion resistant coating, and a scratch resistant coating.

Advantageously the method wherein generating the three-dimensional model of the group of objects includes generating data about the group of objects using a sensor system; and

generating the three-dimensional model of the group of objects from the data generated by the sensor system.

Advantageously the method wherein the sensor system is selected from one of a camera system or a laser scanner.

5 Advantageously the method wherein the data is selected from at least one of images or three-dimensional coordinates for a surface of the group of objects.

Advantageously the method wherein the sensor system comprises a depth sensor.

10 Advantageously the method wherein the sensor system is associated with the robotic coating system.

Advantageously the method wherein the three-dimensional model is selected from one of a point cloud and a computer-aided design model.

15 Advantageously the method wherein the instructions comprise at least one of waypoints or trajectories.

Advantageously the method wherein generating instructions for coating the group of objects includes identifying waypoints along an object in the group of objects; and generating a
20 trajectory for movement of the robotic coating system along the object from the waypoints.

Advantageously the method wherein forming the segments that represent objects in the group of objects in the three-dimensional model includes identifying representations of the
25 objects and clutter in the three-dimensional model; and separating the representations of the objects from the clutter to form segments in a segmented three-dimensional model.

Advantageously the method wherein the group of objects comprises at least one of an aircraft part, a tube, a spar, a
30 reservoir, a stringer, a panel, or a barrel.

According to another aspect of the invention there is provided a method for painting a group of tubes, the method including generating a three-dimensional model of the group of tubes; forming segments that represent the group of tubes in the

three-dimensional model; and generating instructions for painting the group of tubes based on the segments, in which the instructions are configured to cause a robotic painting system to paint the group of tubes.

5 Advantageously the method further including operating the robotic painting system to apply paint to the group of tubes using the instructions.

 Advantageously the method wherein generating the instructions for painting the group of tubes includes
10 identifying waypoints along a tube in the group of tubes; and generating a trajectory for movement of the robotic painting system along the tube from the waypoints.

 According to yet another aspect of the invention there is provided an apparatus including a coating controller configured
15 to generate a three-dimensional model of a group of objects, form segments for the group of objects in the three-dimensional model, and generate instructions for coating the group of objects based on the segments, in which the instructions are configured to cause a robotic coating system to coat the group
20 of objects.

 Advantageously the apparatus further including a sensor system configured to generate data about the group of objects.

 Advantageously the apparatus wherein the sensor system is selected from one of a camera system and a laser scanner.

25 Advantageously the apparatus wherein the sensor system comprises a depth sensor.

 Advantageously the apparatus wherein the coating controller is further configured to generate the three-dimensional model of the group of objects from the data generated by the sensor
30 system.

 Advantageously the apparatus wherein the robotic coating system is a robotic painting system and wherein the instructions include painting trajectories for the robotic coating system to paint the group of objects.

Advantageously the apparatus wherein the robotic coating system is configured to receive the instructions and use the instructions to apply a coating to the group of objects.

Advantageously the apparatus wherein the coating is
5 selected from one of a paint, an adhesive, a sealant, a lubricant, a wear resistant coating, a corrosion resistant coating, and a scratch resistant coating.

Advantageously the apparatus wherein the group of objects comprises at least one of an aircraft part, a tube, a spar, a
10 reservoir, a stringer, a panel, or a barrel.

According to still another aspect of the invention there is provided a method for coating a group of objects, the method including generating a three-dimensional model of the group of objects comprising at least one of an aircraft part, a tube, a
15 spar, a reservoir, a stringer, panel, or a barrel, in which the three-dimensional model is generated in real time and selected from one of a point cloud and a computer-aided design model, and in which generating the three-dimensional model of the group of objects includes generating data about the group of objects
20 using a sensor system associated with a robotic coating system, in which the sensor system is selected from one of a camera system or a laser scanner and comprises a depth sensor, and in which the data is selected from at least one of images or three-dimensional coordinates for a surface of the group of objects;
25 and generating the three-dimensional model of the group of objects from the data generated by the sensor system; forming segments that represent each object in the group of objects in the three-dimensional model, in which forming the segments includes identifying clutter in the three-dimensional model; and
30 separating objects in the group of objects from the clutter to form a segmented three-dimensional model; generating instructions for coating the group of objects based on the segments, in which the instructions are configured to cause a robotic coating system to coat the group of objects and comprise

at least one of waypoints or trajectories, and in which generating the instructions includes identifying the waypoints along an object in the group of objects; and generating a trajectory for movement of the robotic coating system along the object from the waypoints; and operating the robotic coating system to apply a coating to the group of objects using the instructions, in which the coating is selected from one of a paint, an adhesive, a sealant, a lubricant, a wear resistant coating, a corrosion resistant coating, and a scratch resistant coating.

According to a further aspect of the present invention there is provided a method for painting a group of tubes, the method including generating a three-dimensional model of the group of tubes; forming segments that represent the group of tubes in the three-dimensional model; generating instructions for painting the group of tubes based on the segments, in which the instructions are configured to cause a robotic painting system to paint the group of tubes, and in which generating the instructions includes selecting waypoints along a tube in the group of tubes; and generating a trajectory for movement of the robotic painting system along the tube from the waypoints; and operating the robotic painting system to apply paint to the group of tubes using the instructions.

According to a yet further aspect of the present invention there is provided an apparatus including a coating controller configured to generate a three-dimensional model of a group of objects from data about the group of objects, form segments for the group of objects in the three-dimensional model, and generate instructions for coating the group of objects based on the segments, in which the instructions are configured to cause a robotic coating system to coat the group of objects, in which the coating is selected from one of a paint, an adhesive, a sealant, a lubricant, a wear resistant coating, a corrosion resistant coating, and a scratch resistant coating, and in which

the group of objects comprises at least one of an aircraft part, a tube, a spar, a reservoir, a stringer, a panel, or a barrel; a sensor system configured to generate the data about the group of objects, in which the sensor system comprises a depth sensor and is selected from one of a camera system and a laser scanner; and the robotic coating system configured to receive the instructions and use the instructions to apply a coating to the group of objects, in which the robotic coating system is a robotic painting system and in which the instructions include painting trajectories for the robotic coating system to paint the group of objects.

The features and functions can be achieved independently in various embodiments of the present disclosure or may be combined in yet other embodiments in which further details can be seen with reference to the following description and drawings.

BRIEF DESCRIPTION OF THE DRAWINGS

The novel features believed characteristic of the illustrative embodiments are set forth in the appended claims. The illustrative embodiments, however, as well as a preferred mode of use, further objectives and features thereof, will best be understood by reference to the following detailed description of an illustrative embodiment of the present disclosure when read in conjunction with the accompanying drawings, wherein:

Figure 1 is an illustration of a block diagram of a coating environment in accordance with an illustrative embodiment;

Figure 2 is an illustration of a block diagram of a robotic coating system in accordance with an illustrative embodiment;

Figure 3 is an illustration of a block diagram of a segmented three-dimensional model in accordance with an illustrative embodiment;

Figure 4 is an illustration of a block diagram of instructions for a robotic coating system in accordance with an illustrative embodiment;

Figure 5 is an illustration of a coating environment in accordance with an illustrative embodiment;

Figure 6 is an illustration of a surface reconstruction of a group of objects in accordance with an illustrative embodiment;

Figure 7 is an illustration of segments of a group of tubes in accordance with an illustrative embodiment;

Figure 8 is an illustration of a section of a segmented three-dimensional model in accordance with an illustrative embodiment;

Figure 9 is an illustration of a segment with waypoints in accordance with an illustrative embodiment;

Figure 10 is an illustration of a segment with waypoints and a trajectory in accordance with an illustrative embodiment;

Figure 11 is an illustration of an image of a rack with a group of objects in accordance with an illustrative embodiment;

Figure 12 is an illustration of a flowchart of a process for coating a group of objects in accordance with an illustrative embodiment;

Figure 13 is an illustration of a flowchart of a process for forming segments that represent objects in a three-dimensional model in accordance with an illustrative embodiment;

Figure 14 is an illustration of a flowchart of a process for generating instructions for coating a group of objects in accordance with an illustrative embodiment;

Figure 15 is an illustration of a flowchart of a process for generating a trajectory in accordance with an illustrative embodiment;

Figure 16 is an illustration of an aircraft manufacturing and service method in the form of a flowchart in accordance with an illustrative embodiment;

Figure 17 is an illustration of a block diagram of an aircraft in which an illustrative embodiment may be implemented; and

Figure 18 is an illustration of a block diagram of a data processing system in accordance with an illustrative embodiment.

DETAILED DESCRIPTION

The illustrative embodiments recognize and take into account one or more different considerations. For example, the illustrative embodiments recognize and take into account that a system is needed to provide a desired level of accuracy of trajectories for coating objects, while protecting human painters from potential harm from undesired substances in the coating material. Moreover, the illustrative embodiments recognize and take into account that a group of objects to be painted may include components of the same or different types that may have different configurations in space relative to each other. With thousands of different types of components arranged on the component cart in varying combinations, the illustrative embodiments recognize and take into account that an efficient and cost-effective solution is needed to provide a trajectory for a robotic painting arm that reduces the rework for human operators.

Thus, in one illustrative embodiment, a method for coating a group of objects may be provided. A three-dimensional model of the group of objects may be generated. Segments that represent each object in the group of objects in the three-dimensional model may be formed. Instructions for coating the group of objects may be generated based on the segments. These instructions may be configured to cause a robotic coating system to coat the group of objects.

With reference now to the figures, and in particular, with reference to **Figure 1**, an illustration of a block diagram of a

coating environment is depicted in accordance with an illustrative embodiment. In this illustrative example, coating environment **100** is an example of an environment in which coating system **102** may be used.

5 As depicted, coating environment **100** may include coating system **102**. Coating system **102** may be configured to apply a coating to one or more aircraft components **101**. For example, without limitation, coating system **102** may be used to apply coating **104** to group of objects **106** in this illustrative
10 example.

As used herein, a "group of" items may include one or more items. For example, without limitation, group of objects **106** may be one or more objects **115**.

Coating system **102** may be comprised of a number of
15 different components. As depicted, coating system **102** may include rack **108**, sensor system **110**, computer system **112**, and robotic coating system **114**.

In this illustrative example, rack **108** may have dimensions **107** and may be a physical device configured to hold group of
20 objects **106** in this example. Rack **108** may be arranged such that it may have plane **113**, which may be a y-z plane of rack **108**.

As depicted, group of objects **106** may include one or more aircraft components **101** to be coated by robotic coating system **114**. Group of objects **106** may include, for example, without
25 limitation, at least one of an aircraft part, a tube, a spar, a reservoir, a stringer, a panel, a barrel, or some other suitable type of object. In some examples, group of objects **106** may include objects **115** of the same or different types.

As used herein, the phrase "at least one of," when used
30 with a list of items, means different combinations of one or more of the listed items may be used and only one of each item in the list may be needed. For example, without limitation, "at least one of item A, item B, or item C" may include, without limitation, item A, item A and item B, or item B. This example

also may include item A, item B, and item C or item B and item C. Of course, any combinations of these items may be present.

In other examples, "at least one of" may be, for example, without limitation, without limitation, two of item A, one of
5 item B, and ten of item C; four of item B and seven of item C; and other suitable combinations. The item may be a particular object, thing, or a category. In other words, at least one of means any combination of items and number of items may be used from the list but not all of the items in the list may be
10 required.

In this illustrative example, group of objects **106** may include object **116**. Object **116** may be tube **118** in this instance. As depicted, tube **118** may be rigid, flexible, or both. Tube **118** may be selected from, for example, without
15 limitation, one of a fuel line, a pipe, a hydraulic hose, an air bleed line, and other suitable types of tubes.

Tube **118** may be positioned on rack **108** such that tube **118** may be suspended from rack **108** by number of fasteners **120**. As used herein, "a number of," when used with reference to items,
20 means one or more items. For example, without limitation, number of fasteners **120** may be one or more fasteners.

In this example, tube **118** may be suspended from upper portion **109** of rack **108** by fastener **122**. For example, without limitation, fastener **122** may be selected from one of a clip, a
25 chain, a cable, a cord, and other suitable types of fasteners.

In other illustrative examples, tube **118** may be positioned on rack **108** such that fastener **122** may be unnecessary. For example, without limitation, tube **118** may be laid across lower portion **111** of rack **108** and may not be suspended or otherwise
30 attached to rack **108** by fastener **122** in some other manner.

As illustrated, object **116** may be configured such that movement **119** of object **116** occurs. For example, without limitation, tube **118** may move in one or more directions **121** while suspended from rack **108** by fastener **122**. For instance,

tube **118** may rotate along or about axis **123**. Movement **119** of tube **118** may be caused by changes in coating environment **100**, movement of rack **108**, airflow in coating environment **100**, the weight, shape, or size of tube **118**, or other factors.

5 In some examples, movement of rack **108** may shift orientation **125** of tube **118** relative to other objects **115** in group of objects **106**. Consequently, objects **115** in group of objects **106** may be suspended from number of fasteners **120** differently relative to one another, even if all of objects **115**
10 in group of objects **106** are the same type of object. For instance, tube **118** may rotate about axis **123** such that it overlaps in space or touches another one of objects **115** in group of objects **106**.

As depicted, group of objects **106** may have a variety of
15 shapes, sizes, weights, and configurations. For example, without limitation, group of objects **106** may be one object, five objects, ten objects, twenty objects, or some other suitable number of objects. Group of objects **106** may be of the same type or a different type. As an example, if group of objects **106**
20 includes five objects, then group of objects **106** may include two tubes, two reservoirs, and a spar.

Of course, this example is just one example of group of objects **106** and thousands of other combinations may be possible. As each of the different objects **115** may be suspended from rack
25 **108** by number of fasteners **120**, each of objects **115** may move relative to one another.

In some examples, object **116** in group of objects **106** may be secured by more than one of number of fasteners **120**. As an example, object **116** may be arranged on rack **108** such that one
30 end of object **116** may be fastened to upper portion **109** of rack **108**, while another end of object **116** may be fastened to lower portion **111** of rack **108**. In this case, object **116** may be more stable such that object **116** does not rotate about axis **123**.

In other examples, however, using multiple fasteners in number of fasteners **120** for each of objects **115** in group of objects **106** may not be feasible. For instance, object **116** may have an asymmetrical shape such that only one end of object **116** may be fastened to rack **108**. In other examples, different lengths of objects **115** in group of objects **106** may result in some objects being fastened to rack **108** using only one fastener **122**, while other objects may be fastened to rack **108** using more than one of number of fasteners **120**.

As depicted, sensor system **110** may be configured to generate data **124** about group of objects **106**. In this illustrative example, sensor system **110** may be a motion sensing input device selected from at least one of camera system **126**, laser scanner **128**, or other suitable types of sensor systems. Sensor system **110** may be configured to be lightweight, low cost, and portable compared to some currently used sensor systems.

Camera system **126** may include various types of components in these illustrative examples. For example, without limitation, camera system **126** may include red-green-blue (RGB) camera **130**, depth sensor **132**, and other components.

Depth sensor **132** may be configured to generate depth information **131** about each object in group of objects **106**. In this manner, depth sensor **132** may generate data **124** about orientation **125** of each of group of objects **106** in a space.

In some illustrative examples, depth sensor **132** may include an infrared laser projector and a monochrome complementary metal-oxide-semiconductor (CMOS) sensor (not shown). In other examples, depth sensor **132** may include various other components or configurations of components.

In this illustrative example, sensor system **110** may be configured to capture data **124** about group of objects **106** in various light conditions. As an example, sensor system **110** may be configured to generate data **124** about group of objects **106** under ambient light conditions.

In various illustrative examples, the sensing range of sensor system **110** may be adjustable. For example, without limitation, the sensing range of depth sensor **132** may be about three to about ten meters in some examples. In other examples, the sensing range of depth sensor **132** may be more or less, depending on the particular implementation.

In one illustrative example, sensor system **110** may be configured to operate, for example, without limitation, at a speed of about 60 frames per second. In other examples, sensor system **110** may be configured to operate at higher or lower speeds as well.

When sensor system **110** is laser scanner **128**, various techniques may be employed to generate depth information **131** about group of objects **106**. For example, without limitation, time of flight, triangulation, or other suitable techniques may be used.

As illustrated, robotic coating system **114** may include robotic device **134** and may be configured to move around group of objects **106** to coat group of objects **106** with one or more types of coating material **136**. In some examples, robotic coating system **114** may be robotic painting system **135**.

Coating material **136** may take a number of different forms in this illustrative example. For example, without limitation, coating material **136** may be paint **138**. In other examples, coating material **136** may be selected from at least one of an adhesive, a sealant, a lubricant, a wear resistant coating, a corrosion resistant coating, a scratch resistant coating, or other suitable type of coating. Coating material **136** may be applied to one or more of objects **115** in group of objects **106** to form coating **104** in this illustrative example.

Coating material **136** may be applied to objects **115** in a number of different ways. For example, without limitation, coating material **136** may be applied using airspray, airless spray, electrostatic spraying, powder coating, rotary atomizing,

drip coating, flow coating, curtain coating, roll coating, electro-coating, autodeposition, or applied in another suitable manner using robotic device **134**.

5 With some illustrative examples, robotic device **134** may be configured to apply coating material **136** at a speed of, for example, without limitation, five meters per second. Of course, robotic device **134** may apply coating material **136** faster or slower, depending on the particular implementation.

10 In this illustrative example, coating controller **140** may be located in computer system **112**. Computer system **112** may be comprised of a number of computers. When more than one computer is present in computer system **112**, those computers may communicate with each other through a communications medium such as a network.

15 In some examples, coating controller **140** in computer system **112** may be associated with or remote to one of sensor system **110** and robotic coating system **114**. As used herein, when one component is "associated" with another component, the association may be a physical association in the depicted
20 examples.

For example, without limitation, a first component, such as computer system **112** may be considered to be associated with a second component, such as robotic coating system **114**, by being secured to the second component, bonded to the second component,
25 mounted to the second component, welded to the second component, fastened to the second component, and/or connected or attached to the second component in some other suitable manner. The first component also may be connected to the second component using a third component. Further, the first component may be
30 considered to be associated with the second component by being formed as part of and/or as an extension of the second component.

In other examples, computer system **112** with coating controller **140** may be a remote unit. In this case, coating

controller **140** may communicate with sensor system **110** and robotic coating system **114** through a wired or wireless communications medium.

In this depicted example, coating controller **140** may be configured to generate three-dimensional model **142**. As depicted, coating controller **140** may receive input from sensor system **110** for use in generating three-dimensional model **142** of group of objects **106**. In particular, coating controller **140** may receive data **124** from sensor system **110**.

In this example, sensor system **110** may be configured to stream data **124** for use by coating controller **140** in real time. Data **124** may include, for example, without limitation, images **146**, three-dimensional coordinates **148**, or other suitable types of information.

In these illustrative examples, three-dimensional coordinates **148** in data **124** from sensor system **110** may form point cloud **150**. Three-dimensional model **142** may be constructed from point cloud **150** in some of these examples.

In some illustrative examples, point cloud **150** may be used to create computer-aided design (CAD) model **144** through a surface restructuring process. In other embodiments, point cloud **150** may be used to create other types of three-dimensional models, depending on the particular implementation. In still other illustrative examples, point cloud **150** may be directly rendered and inspected.

As depicted, coating controller **140** may perform image segmentation on three-dimensional model **142**. In other words, coating controller **140** uses image segmentation to form segments **152** that represent objects **115** in group of objects **106**.

As depicted, coating controller **140** may identify segments **152** and clutter **154** in data **124**. Segments **152** may be representations **153** of objects **115** in group of objects **106**. For example, without limitation, data **124** may be segmented to identify segment **155** in segments **152** corresponding to tube **118**.

Coating controller **140** may be further configured to remove clutter **154** from three-dimensional model **142** to form segmented three-dimensional model **156**. In this illustrative example, clutter **154** may be data **124** that may not be needed for representations **153** of group of objects **106**. For example, without limitation, clutter **154** may include data points from rack **108**, a wall behind rack **108**, or other data points that may not be needed for three-dimensional model **142**.

In this depicted example, after separating segments **152** from clutter **154** to form segmented three-dimensional model **156**, coating controller **140** also may identify waypoints **162** along each of segments **152**. For example, without limitation, coating controller **140** may identify waypoints **162** along segments **152** of tube **118**.

A number of trajectories **164** for robotic device **134** may be generated between waypoints **162** in this illustrative example. For instance, trajectory **166** may be generated between two or more of waypoints **162**. Additional trajectories **164** may be generated between waypoints **162** until all of segments **152** have trajectories **164**.

In this example, at least one of waypoints **162** or trajectories **164** may be communicated to robotic coating system **114** by coating controller **140**. This communication may be wired or wireless, depending on the particular implementation.

In various embodiments, instructions **158** may be configured to cause robotic coating system **114** to coat group of objects **106**. For example, without limitation, instructions **158** may be generated by coating controller **140** such that robotic device **134** uses paint **138** to paint each of objects **115** in group of objects **106** according to desired parameters.

In some examples, sensor system **110** may be associated with robotic coating system **114** such that the two components may both be housed in unit **168**. In other embodiments, sensor system **110**

may be a separate component from robotic coating system **114** and communicate through a wired or wireless communications medium.

When sensor system **110** and robotic coating system **114** are housed in unit **168**, robotic device **134** may scan group of objects **106** to form three-dimensional model **142**. Robotic device **134** may then follow the same trajectory **166** to coat group of objects **106**.

When sensor system **110** and robotic coating system **114** are not housed together in unit **168**, one of human operators **160** may operate sensor system **110** to generate data **124**. In other examples, sensor system **110** may be operated automatically.

Turning now to **Figure 2**, an illustration of a block diagram of robotic coating system **114** from **Figure 1** is depicted in accordance with an illustrative embodiment. In this illustrative example, robotic coating system **114** may include a number of different components. For example, without limitation, robotic coating system **114** may include platform **202**, robotic device **204**, reservoir **206**, and applicator **208**.

In this illustrative example, platform **202** may be a structure with which robotic device **204**, reservoir **206**, and applicator **208** may be physically associated. For example, without limitation, robotic device **204** may be secured, bonded, mounted, welded, fastened, and/or connected to platform **202** in some other suitable manner.

In some examples, platform **202** may move or slide along rails, tracks, or other types of movement systems. Of course, in other examples, more than one robotic coating system **114** may be present with multiple other components.

As depicted, robotic device **204** may be arm **210**. Both robotic device **204** and reservoir **206** may be physically associated with platform **202**. In these illustrative examples, robotic device **204** may be configured to move applicator **208** to coat group of objects **106** in **Figure 1**.

Reservoir **206** may store coating material **212** for arm **210** to apply coating material **212** to group of objects **106**. For example, without limitation, reservoir **206** may store fluid **214** or powder **216** for robotic coating system **114** to apply to group of objects **106**. Of course, in other illustrative examples, coating material **212** may be other types of coating materials other than fluid **214** and powder **216**, depending on the particular implementation.

In these illustrative examples, applicator **208** may be associated with robotic device **204**. Applicator **208** may be, for example, without limitation, sprayer **218**, nozzle **220**, or some other suitable type of applicator. One or both of sprayer **218** and nozzle **220** may be used to apply coating material **212** to group of objects **106** in these illustrative examples.

In other examples, more than one applicator **208** may be present in robotic coating system **114**. In still other examples, arm **210** may apply coating material **212** to group of objects **106** using a different type of applicator **208** other than sprayer **218** and nozzle **220**.

In operation, robotic coating system **114** may receive instructions **158** from coating controller **140** in **Figure 1**. In particular, robotic coating system **114** may receive trajectories **164** from **Figure 1** and follow trajectories **164** when coating group of objects **106**.

Robotic coating system **114** may then use robotic device **204** with applicator **208** to coat group of objects **106** using coating material **212** stored in reservoir **206**. For instance, robotic coating system **114** may use sprayer **218** to paint tube **118** from **Figure 1** with fluid **214**. In another example, robotic coating system **114** may use nozzle **220** to dispense powder **216** onto tube **118**.

In these illustrative examples, robotic coating system **114** follows trajectories **164** based on segmented three-dimensional model **156** in **Figure 1**. In some illustrative examples, as sensor

system **110** may acquire new data **124**, robotic coating system **114** may receive additional or updated instructions **158** in real time. These updated instructions **158** may include trajectories **164** that have been adjusted for spatial changes in group of objects **106**.

5 For instance, if movement **119** causes tube **118** to rotate about axis **123** in **Figure 1**, instructions **158** may be altered to provide more accurate trajectories **164** for painting tube **118**.

In alternative examples, instructions **158** may be received by robotic coating system **114** at one time and may not be updated
10 based on additional data **124** from sensor system **110**. In this instance, for example, without limitation, tube **118** may be painted with fluid **214** and then inspected by sensor system **110** to determine whether tube **118** is painted as desired. Accordingly, data **124** may form three-dimensional model **142** in
15 **Figure 1** that may be used to touch up tube **118** with fluid **214** when needed. In this manner, sensor system **110** may provide both data collection and inspection functions.

With reference now to **Figure 3**, an illustration of a block diagram of segmented three-dimensional model **156** from **Figure 1**
20 is depicted in accordance with an illustrative embodiment. In this illustrative example, segmented three-dimensional model **156** includes number of point cloud sets **300**.

A "set," as used herein with reference to items, means zero or more items. For example, without limitation, point cloud set
25 **302** in number of point cloud sets **300** includes zero or more points **304**. In other words, point cloud set **302** in number of point cloud sets **300** may be a null set.

As depicted, each of number of point cloud sets **300** corresponds to one of group of objects **106** in **Figure 1**. For
30 example, without limitation, point cloud set **302** may include points **304** for tube **118** in **Figure 1**.

As illustrated, each of number of point cloud sets **300** has a number of points **304**. Normal vectors **306** correspond to each one of a number of points **304**.

In this example, one of normal vectors **306** may be a vector that is perpendicular to the tangent plane of one of points **304**. In other words, each of normal vectors **306** may be normal to surface normal **308** of each of points **304**.

5 In this illustrative example, number of point cloud sets **300** may be used to generate trajectories **164** for robotic coating system **114** in **Figure 1**. For example, without limitation, point cloud set **302** may be used to generate trajectory **166** for robotic coating system **114** to apply coating material **136** to tube **118** in
10 **Figure 1**.

With reference now to **Figure 4**, an illustration of a block diagram of instructions **158** for robotic coating system **114** from **Figure 1** is depicted in accordance with an illustrative embodiment.

15 As depicted, waypoints **162** may include waypoint **400**. Waypoint **400** may be start point **402** or end point **404** in some examples. In other examples, waypoint **400** may be one of waypoints **162** other than start point **402** and end point **404**.

In this illustrative example, start point **402** may be one of
20 waypoints **162** identified for robotic coating system **114** to begin coating tube **118** in **Figure 1**. End point **404** may be one of waypoints **162** identified for robotic coating system **114** to stop coating tube **118**. In some illustrative examples, end point **404** may signify the end of a particular portion of painting tube
25 **118**. For example, without limitation, robotic coating system **114** may switch the type of coating material **136** used on tube **118** in some examples.

As depicted, trajectory **166** in trajectories **164** may include number of components **406**. Each of number of components **406**
30 corresponds to a portion of trajectory **166** between two of waypoints **162**. In other words, number of components **406** may be put together to form a complete trajectory **166** in these examples.

In this illustrative example, each of components **406** may include ordered sequence **408** of degree of freedom points **410** for robotic coating system **114**. Degree of freedom points **410** may be points with six degrees of freedom in these examples. Ordered
5 sequence **408** of degree of freedom points **410** may be executed by arm **210** to apply fluid **214** in **Figure 2** to tube **118**.

The illustration of coating environment **100** in **Figure 1** and the different components of coating environment **100** shown in **Figures 2-4** are not meant to imply physical or architectural
10 limitations to the manner in which an illustrative embodiment may be implemented. Other components in addition to, or in place of, the ones illustrated may be used. Some components may be optional. Also, the blocks are presented to illustrate some functional components. One or more of these blocks may be
15 combined, divided, or combined and divided into different blocks when implemented in an illustrative embodiment.

For example, without limitation, a number of storage devices **170** may be included in coating controller **140**. Storage devices **170** may be, for example, without limitation, a random
20 access memory, a read only memory, a hard disk drive, a solid state disk drive, and/or any other suitable storage device capable of storing program code in a functional form.

In this case, storage devices **170** may include database **172** that may store parameters **174** for different types of objects **115**
25 in group of objects **106**. Parameters **174** may include computer-aided design model **144** for previously painted objects **115**, colors of paint **138** for each of objects **115**, desired cycle time, painting method, or other information to add to instructions **158** sent to robotic coating system **114**.

For example, without limitation, different types of coating material **136** may be applied to tube **118** than may be applied to another of objects **115**. With the use of database **172**, coating controller **140** may use parameters **174** to apply the desired type
30

of coating material **136** more accurately to each of objects **115** in group of objects **106**.

In other illustrative examples, camera system **126** may be stereo camera **176**. In this example, stereo camera **176** may have
5 two or more lenses with a separate image sensor for each lens. This configuration allows stereo camera **176** to capture data **124** for three-dimensional rendering.

In still other examples, aircraft assembly **178** may be present in coating environment **100** in addition to or in place of
10 rack **108**. In other words, aircraft components **101** may already be installed in aircraft assembly **178** before painting. With the use of an illustrative embodiment, whole assemblies or combinations of components may be coated by robotic coating system **114** quickly and easily, without risk of undesired effects
15 for human operators **160**.

Although the illustrative examples are shown with one sensor system **110**, robotic coating system **114**, and coating controller **140**, various examples may include more than one
20 sensor system **110**, robotic coating system **114**, and coating controller **140**. In this instance, the components in coating environment **100** may be arranged to provide the desired level of accuracy for data **124** and instructions **158**.

One or more of the components in coating system **102** may also be implemented in different stages of manufacturing using a
25 conveyer belt. For example, without limitation, sensor system **110** may continuously scan a number of group of objects **106** on more than one rack **108** that move along a conveyor belt. In this example, coating controller **140** continuously streams data **124** and converts point cloud **150** into instructions **158** with usable
30 trajectories **164** for each group of objects **106** on each rack **108**. Each rack **108** may then enter coating environment **100** where robotic coating system **114** coats group of objects **106** according to instructions **158** for that group of objects **106**. As yet another illustrative example, robotic coating system **114** may

include one or more additional robotic devices in addition to or in place of robotic device **204**.

Although coating controller **140** is described as being located in computer system **112**, coating controller **140** may be implemented in some other manner. Coating controller **140** may be implemented in software, hardware, firmware or a combination thereof. When software is used, the operations performed by coating controller **140** may be implemented in program code configured to run on a processor unit.

When firmware is used, the operations performed by coating controller **140** may be implemented in program code and data and stored in persistent memory to run on a processor unit. When hardware is employed, the hardware may include circuits that operate to perform the operations in coating controller **140**.

In the illustrative examples, the hardware may take the form of a circuit system, an integrated circuit, an application specific integrated circuit (ASIC), a programmable logic device, or some other suitable type of hardware configured to perform a number of operations. With a programmable logic device, the device may be configured to perform the number of operations.

The device may be reconfigured at a later time or may be permanently configured to perform the number of operations.

Examples of programmable logic devices may include, for example, without limitation, a programmable logic array, a programmable array logic, a field programmable logic array, a field programmable gate array, and other suitable hardware devices. Additionally, the processes may be implemented in organic components integrated with inorganic components and/or may be comprised entirely of organic components excluding a human being. For example, without limitation, the processes may be implemented as circuits in organic semiconductors.

In **Figure 5**, an illustration of a coating environment is depicted in accordance with an illustrative embodiment. Coating

environment **500** may be an example of coating environment **100** shown in block form in **Figure 1**.

As depicted, coating environment **500** includes rack **502**, sensor system **504**, robotic coating system **506**, and human operator **508**. Rack **502** may be one implementation for rack **108**, while sensor system **504** and robotic coating system **506** may be implementations for sensor system **110** and robotic coating system **114** in **Figure 1**, respectively.

In this illustrative example, rack **502** may have upper portion **503** and lower portion **505** and supports **507**, **509**, and **511**. A number of fasteners **510** may be arranged along upper portion **503** of rack **502**.

In this illustrative example, group of objects **512** may be associated with rack **502** and may include group of tubes **514**. In other illustrative examples, group of objects **512** may include at least one of tubes, spars, stringers, reservoirs, barrels, or other aircraft components **101**.

In this illustrative example, group of tubes **514** may be fastened to rack **502** using number of fasteners **510**. In some illustrative examples, fasteners **510** may be part of rack **502**.

As illustrated, each of group of tubes **514** may hang from rack **502** by one end of each tube. In other illustrative examples, group of tubes **514** may be held in place by two or more of fasteners **510** arranged along group of tubes **514**.

As illustrated, group of tubes **514** hang from fasteners **510**. In particular, group of tubes **514** includes tube **516**, **518**, **520**, **522**, **524**, **526**, and **528** hanging from fastener **530**, **532**, **534**, **536**, **538**, **540**, and **542**, respectively.

In this example, tube **516** may have bend **515** and straight portion **517**. In other examples, each of group of tubes **514** may have one or more of bend **515**, depending on the implementation.

In this depicted example, fasteners **510** may be clips **544**. In other illustrative examples, fasteners **510** may be chains, cables, cords, or other suitable types of fasteners. Clips **544**

may be arranged along upper portion **503** of rack **502** such that clips **544** and group of tubes **514** may move. For example, without limitation, clips **544** may be configured such that group of tubes **514** may move along upper portion **503** of rack **502** in the direction of arrow **546** or arrow **548**. Clips **544** also may lock in place as desired.

In this example, tube **516** may rotate relative to tube **518**. For example, without limitation, tube **516** may rotate about axis **550** in the direction of arrow **552**. Each of tube **518**, **520**, **522**, **524**, **526**, and **528** may also rotate relative to one another in these illustrative examples. In other illustrative examples, a number of additional fasteners may be provided on lower portion **505** of rack **502**. When group of tubes **514** are straight, tubes **516**, **518**, **520**, **522**, **524**, **526**, and **528** may be attached to fasteners on lower portion **505** as well as fasteners **510** on upper portion **503** of rack **502**.

As depicted, rack **502** may include wheels **554** extending from lower portion **505**. Wheels **554** may be configured to move rack **502** into painting booth **556**. In other examples, rack **502** may be positioned on a conveyor belt or other automatic device such that wheels **554** may not be present to move rack **502** from one stage in the manufacturing process to another stage in the manufacturing process.

As illustrated, sensor system **504** may include camera system **558**. Camera system **558** may include various components such as, for example, without limitation, one or more sensors, a camera, processing components, or other suitable components.

In some illustrative examples, camera system **558** may be operated by human operator **508**. In other examples, camera system **558** may be operated automatically to perform a scan of group of tubes **514** hanging from rack **502**. In this example, camera system **558** is associated with robotic device **557** which may be configured to automatically scan group of tubes **514** hanging from rack **502**. As camera system **558** automatically scans

group of objects **512**, human operator **508** may oversee the scan and modify camera system **558** as needed.

In some examples, rack **502**, sensor system **504**, and robotic coating system **506** may be associated with painting booth **556**.

5 Human operator **508** may or may not be present in painting booth **556**.

In other examples, human operator **508** may scan group of objects **512** outside painting booth **556** and move rack **502** into painting booth **556** for coating by robotic coating system **506**.

10 In some examples, the movement of rack **502** with group of objects **512** may be done by an automated system. In this example, coating system **506** may include robotic device **559**. Robotic device **559** may be an example for one implementation for robotic device **134** shown in block form in **Figure 1**.

15 The illustration of coating environment **500** is not meant to limit the manner in which different illustrative embodiments may be implemented. For example, without limitation, sensor system **504** may be implemented within robotic coating system **506** such that human operator **508** may not be needed in coating environment
20 **500**.

In other examples, sensor system **504** may include more than one camera system **558**. In still other illustrative examples, group of objects **512** may include objects other than group of tubes **514** or may include more or fewer group of tubes **514** than
25 shown in rack **502**.

In **Figure 6**, an illustration of a surface reconstruction of group of objects **512** in **Figure 5** is depicted in accordance with an illustrative embodiment. Surface reconstruction **600** may be one example of an implementation of three-dimensional model **142**
30 of segments **152** from point cloud **150** for segmented three-dimensional model **156** shown in block form in **Figure 1**. In this illustrative example, surface reconstruction **600** may be a linear approximation of the surface of group of objects **512** in **Figure 5**.

In this depicted example, reconstruction algorithms may be used to generate surface reconstruction **600** from a point cloud (not shown) of group of objects **512** generated by coating controller **140** in **Figure 1**. These reconstruction algorithms may be any suitable reconstruction algorithms available to generate surface reconstruction **600** from a point cloud of group of objects **512**. In one example, a Delaunay tetrahedralization of the points may be computed and labeled. In other examples, other suitable reconstruction algorithms known in the art may be used.

Surface reconstruction **600** may include data points **602**. Data points **602** may be an example of surface normals for three-dimensional coordinates **148** of rack **502** and group of tubes **514** shown in **Figure 5** after surface reconstruction has taken place.

As depicted, surface reconstruction **600** may include representations **604** of group of tubes **514** and clutter **606**. Representations **604** may be data **124** from **Figure 1** about tubes **608**. In this illustrative example, tubes **608** may be part of group of tubes **514**. Clutter **606** may be data **124** about other portions of coating environment **500** such as a background, upper portion **503** and supports **507**, **509**, and **511** of rack **502**, among others.

In this depicted example, portion **610** of surface reconstruction **600** may include representations **604** of tubes **608** that may be processed. In particular, portion **610** may include three-dimensional coordinates **148** for surface reconstruction **600** that may be sent to coating controller **140** in **Figure 1**. Coating controller **140** may then process surface reconstruction **600** and subsequently generate instructions **158** for robotic coating system **114**.

Turning to **Figure 7**, an illustration of segments of group of tubes **514** from **Figure 5** using surface reconstruction **600** from **Figure 6** is depicted in accordance with an illustrative embodiment. In **Figure 7**, segments **700** formed from portion **610**

of surface reconstruction **600** in **Figure 6** are shown in **Figure 7**. Segments **700** may be one example of an implementation for segments **152** in **Figure 1**. In this example, segments **152** may be formed by coating controller **140** in **Figure 1**.

5 In this illustrative example, coating controller **140** may have formed segments **700** of surface reconstruction **600** in **Figure 6**. In particular, segment **704**, segment **706**, and segment **708** may be shown.

As depicted, segments **700** may be formed and clutter **606** may
10 be removed from surface reconstruction **600** in **Figure 6**. In this illustrative example, segments **700** may form segmented three-dimensional model **702**. Segmented three-dimensional model **702** may be an example of segmented three-dimensional model **156** shown in block form in **Figure 1**. Segmented three-dimensional model
15 **702** may then be analyzed and may be used by coating controller **140** to generate instructions **158** for robotic coating system **114**. Section **710** with segment **704** may also be shown in this illustrative example.

Turning next to **Figure 8**, an illustration of section **710** of
20 segmented three-dimensional model **702** from **Figure 7** is depicted in accordance with an illustrative embodiment. In this example, segment **704** in section **710** of segmented three-dimensional model **702** is shown. Segment **704** may correspond to a three-dimensional rendering of tube **118** in group of objects **106** in **Figure 1**.

25 In **Figure 9**, an illustration of segment **704** from **Figure 8** with waypoints is depicted in accordance with an illustrative embodiment. In this example, waypoints **900** may be an example of waypoints **162** generated by coating controller **140** in **Figure 1**.

In this illustrative example, eight waypoints **900** are
30 shown. In other examples, more or fewer waypoints **900** may be generated by coating controller **140**, depending on the particular implementation.

As illustrated, waypoints **900** may include waypoint **902**, **904**, **906**, **908**, **910**, **912**, **914**, and **916**. In this example,

waypoint **902** may be start point **918**, which may indicate where robotic coating system **114** in **Figure 1** may begin painting segment **704**.

Waypoint **916** may be end point **920**, which may indicate where robotic coating system **114** may end painting segment **704**. After identifying waypoints **900** along segment **704** of segmented three-dimensional model **702**, coating controller **140** may generate trajectory **166** from **Figure 1** between one or more of waypoints **900**.

In **Figure 10**, an illustration of segment **704** with waypoints **900** from **Figure 10** and a trajectory is depicted in accordance with an illustrative embodiment. In this example, segment **704** in section **710** of segmented three-dimensional model **702** is shown with waypoints **900** and trajectory **1000**.

Trajectory **1000** may be an example of trajectory **166** generated by coating controller **140** in **Figure 1**. In this particular example, trajectory **1000** may be comprised of component **1002**, **1004**, **1006**, **1008**, **1010**, **1012**, and **1014**.

As illustrated, component **1002** may be generated between waypoint **902** and waypoint **904**, component **1004** may be generated between waypoint **904** and waypoint **906**, component **1006** may be generated between waypoint **906** and waypoint **908**, component **1008** may be generated between waypoint **908** and waypoint **910**, component **1010** may be generated between waypoint **910** and waypoint **912**, component **1012** may be generated between waypoint **912** and waypoint **914**, and component **1014** may be generated between waypoint **914** and waypoint **916**. Together, components **1002**, **1004**, **1006**, **1008**, **1010**, **1012**, and **1014** may form trajectory **1000** for use by robotic coating system **114** in **Figure 1**.

In this example, coating controller **140** may generate waypoints **900** and trajectory **1000** for segment **704** of segmented three-dimensional model **702** and send one of waypoints **900** and trajectory **1000** in instructions **158** to robotic coating system **114** for further use. Robotic coating system **114** may then use

trajectory **1000** to paint tube **118**. In particular, robotic coating system **114** may follow trajectory **1000** to paint tube **118**.

Although **Figures 8-10** have been shown with respect to segment **704** corresponding to tube **118** in **Figure 1**, other
5 segments **152** corresponding to other objects **115** in group of objects **106** may be processed in a similar manner. Each of segments **152** may then be used to generate trajectories **164** for coating group of objects **106** in these illustrative examples.

In **Figure 11**, an illustration of an image of a rack with a
10 group of objects is depicted in accordance with an illustrative embodiment. In this example, image **1100** with rack **1102** may be one of images **146** of rack **108** with group of objects **106** shown in block form in **Figure 1**. Rack **1102** also may be an alternative implementation for rack **502** shown in **Figure 5**.

15 As depicted, rack **1102** may have upper portion **1104** and lower portion **1106** and supports **1108**, **1110**, and **1112**. Number of fasteners **1114** may be arranged along one or both of upper portion **1104** and lower portion **1106** of rack **1102**. For example, without limitation, fastener **1132**, **1134**, **1136**, **1138**, **1140**, **1142**,
20 and **1144** may be arranged along upper portion **1104**, while fastener **1146**, **1148**, **1150**, and **1152** may be arranged along lower portion **1106**.

As illustrated, group of objects **1116** hang from number of fasteners **1114**. In particular, group of objects **1116** may
25 include tube **1118**, reservoir **1120**, reservoir **1122**, spar **1124**, barrel **1126**, panel **1128**, and tube **1130** hanging from fastener **1132**, **1134**, **1336**, **1338**, **1140**, **1142**, and **1144**, respectively. Reservoir **1120**, reservoir **1122**, spar **1124**, and panel **1128** also may be attached to fastener **1146**, **1148**, **1150**, and **1152**,
30 respectively.

In this depicted example, one or more of group of objects **1116** may move relative to one another. In some examples, less movement of reservoir **1120**, reservoir **1122**, spar **1124**, and panel **1128** may occur relative to tube **1118**, barrel **1126**, and tube **1130**

because reservoir **1120**, reservoir **1122**, spar **1124**, and panel **1128** may be secured by two of number of fasteners **1114**. For example, without limitation, reservoir **1122** may move slightly in the direction of arrow **1154** and arrow **1156**, while tube **1118** hanging from fastener **1132** may have a larger range of motion such that tube **1118** may move about axis **1158** in the direction of arrow **1160**.

As depicted, rack **1102** may be positioned on movement system **1162**. Movement system **1162** may be conveyor belt **1164** in this example. In other illustrative examples, movement system **1162** may be a moveable platform, rails, wheels, or other suitable type of movement system configured to transport rack **1102** from one location to another location.

For example, without limitation, sensor system **504** in **Figure 5** may scan rack **1102** with group of objects **1116** and send data **124** to coating controller **140**. Movement system **1162** may then move rack **1102** into a painting booth, such as painting booth **556** in **Figure 5**. In painting booth **556**, robotic coating system **506** in **Figure 5** may paint group of objects **1116** according to instructions **158** generated by coating controller **140** in real time.

The different components shown in **Figures 5-11** may be illustrative examples of how components shown in block form in **Figures 1-4** can be implemented as physical structures.

Additionally, some of the components in **Figures 5-13** may be combined with components in **Figures 1-4**, used with components in **Figures 1-4**, or a combination of the two.

Turning next to **Figure 12**, a flowchart of a process for coating group of objects **106** from **Figure 1** is depicted in accordance with an illustrative embodiment. The process shown in **Figure 12** may be implemented by coating controller **140** in computer system **112** shown in block form in **Figure 1**.

The process begins by receiving data **124** from sensor system **110** about group of objects **106** (operation **1200**). Next, three-

dimensional model **142** of group of objects **106** may be generated (operation **1202**). Three-dimensional model **142** may be point cloud **150** or may be another type of three-dimensional rendering. For example, without limitation, point cloud **150** of group of tubes **514** in **Figure 5** may be generated by coating controller **140**.

The process then may form segments **152** that represent each object in group of objects **106** in three-dimensional model **142** (operation **1204**). Segments **152** may represent group of objects **106** that may be coated by robotic coating system **114**. For example, without limitation, coating controller **140** may form segments **152** for group of tubes **514**.

Instructions **158** for coating group of objects **106** may then be generated based on segments **152** (operation **1206**). In this illustrative example, instructions **158** may be configured to cause robotic coating system **114** to apply coating material **136** to group of objects **106**. For example, without limitation, coating controller **140** may generate instructions **158** to cause robotic coating system **114** to paint group of tubes **514**.

Next, instructions **158** may be sent to robotic coating system **114** (operation **1208**), with the process terminating thereafter.

In **Figure 13**, an illustration of a flowchart of a process for forming segments **152** that represent objects **115** in three-dimensional model **156** from **Figure 1** is depicted in accordance with an illustrative embodiment. The process illustrated in **Figure 13** may be implemented in operation **1204** in **Figure 12** by coating controller **140** in **Figure 1**.

The process begins by identifying representations **153** of objects **115** and clutter **154** in three-dimensional model **142** (operation **1300**). For example, without limitation, coating controller **140** may identify representations **153** for tube **118** in **Figure 1**.

In this illustrative example, dimensions **107** of rack **108** may be known. Clutter **154** may include all data points that may not be within dimensions **107** of rack **108**.

Next, representations **153** of objects **115** may be separated
5 from clutter **154** to form segments **152** in segmented three-dimensional model **156** (operation **1302**), with the process terminating thereafter. In this example, the mount positions of objects **115** may be known. The topmost point of each of objects **115** may be identified and labeled. In some examples, a nearest
10 neighbors grouping algorithm may be run to finish the segmentation process by generating segments **152**. Of course, other algorithms may be used, depending on the particular implementation. A variety of currently used segmentation techniques may be employed to generate segments **152**, the details
15 of which are omitted.

With reference next to **Figure 14**, an illustration of a flowchart of a process for generating instructions **158** for coating group of objects **106** from **Figure 1** is depicted in accordance with an illustrative embodiment. The process
20 illustrated in **Figure 14** may be implemented in operation **1206** in **Figure 12** by coating controller **140** in **Figure 1**.

The process begins by identifying waypoints **162** along object **116** in group of objects **106** (operation **1400**). For example, without limitation, coating controller **140** may identify
25 waypoints **162** along tube **118** in group of objects **106**.

Next, trajectory **166** for movement **119** of robotic coating system **114** along object **116** may be generated from waypoints **162** (operation **1402**). For example, without limitation, coating controller **140** may generate trajectory **166** for robotic coating
30 system **114** to apply paint **138** to tube **118** from waypoints **162**.

The process then may send instructions **158** including trajectory **166** to robotic coating system **114** (operation **1404**). Next, robotic coating system **114** may apply coating **104** to object **116** in group of objects **106** based on instructions **158** (operation

1406), with the process terminating thereafter. For example, without limitation, robotic coating system **114** may apply paint **138** to group of tubes **514**. In particular, robotic coating system **114** may apply paint **138** to tube **118**. In other

5 illustrative examples, robotic coating system **114** may apply another coating material **136** to group of objects **106**, depending on the particular implementation.

Turning next to **Figure 15**, an illustration of a flowchart of a process for generating trajectory **166** from **Figure 1** is depicted in accordance with an illustrative embodiment. In particular, this process may be implemented by coating controller **140** in **Figure 1** during operation **1402** in **Figure 14**. In this figure, the process for generating six-degree-of-freedom points for robotic coating system **114** is described in detail.

15 The process begins by selecting point cloud set **302** (operation **1500**). In this example, point cloud set **302** may include points **304** for tube **516** in **Figure 5**. Waypoints **162** may be identified from points **304** for each point cloud set **302**.

20 Next, the process selects straight portion **517** between a top of tube **516** and a desired distance below the top of tube **516** (operation **1502**). Waypoint **400** in waypoints **162** is selected with an associated surface normal **308** that is most perpendicular to plane **113** (operation **1504**). Plane **113** may be a y-z plane of rack **108** in **Figure 1**. Waypoint **400** may be start point **402**.

25 Another of waypoints **162** with a most similar surface normal **308** to waypoint **400** is then chosen (operation **1506**). A determination may then be made as to whether next surface normal **308** for the next one of waypoints **162** is similar (operation **1508**).

30 If surface normal **308** for the next one of waypoints **162** is similar, the process returns to operation **1506**. If surface normal **308** for the next one of waypoints **162** is not similar, the process identifies bend **515** in tube **516** from computer-aided design model **144** (operation **1510**). In other words, if surface

normal **308** of the next one of waypoints **162** is not the same as that of the previous one of waypoints **162**, the process has reached bend **515** in tube **516**. No waypoints **162** in **Figure 1** may be used for the bends.

5 In this illustrative example, the size of bend **515** may be known from computer-aided design model **144** associated with tube **516**. Computer-aided design model **144** may be an original computer-aided design model from the design of tube **516**, or a computer-aided design model generated by sensor system **110** in
10 **Figure 1**.

 The process then continues through bend **515** to identify the next straight portion **517** of tube **516** (operation **1512**). Next, surface normal **308** with the largest dot product to the one of waypoints **162** just previous to bend **515** is identified (operation
15 **1514**).

 A determination is then made as to whether this one of waypoints **162** is end point **404** of tube **516** (operation **1516**). If this one of waypoints **162** is end point **404** of tube **516**, the process terminates. If this one of waypoints **162** is not end
20 point **404** of tube **516**, the process returns to operation **1506**, as described above.

 In this manner, the process repeats operations **1506-1516** until trajectory **166** may be generated for robotic coating system **114**. For example, without limitation, each of number of
25 components **406** of trajectory **166** is generated between two of waypoints **162**. In this manner, each of number of components **406** of trajectory **166** correspond to straight portions **517** of tube **516**.

 Illustrative embodiments of the disclosure may be described
30 in the context of aircraft manufacturing and service method **1600** as shown in **Figure 16** and aircraft **1700** as shown in **Figure 17**. In particular, coating system **102** in **Figure 1** may be implemented in various stages of aircraft manufacturing and service method **1600** to form parts for aircraft **1700**.

Turning first to **Figure 16**, an illustration of an aircraft manufacturing and service method is depicted in the form of a flowchart in accordance with an illustrative embodiment. During pre-production, aircraft manufacturing and service method **1600** may include specification and design **1602** of aircraft **1700** in **Figure 17** and material procurement **1604**.

During production, component and subassembly manufacturing **1606** and system integration **1608** of aircraft **1700** in **Figure 17** takes place. During this stage, coating system **102** may be used to apply coating material **136** to components or assemblies for aircraft **1700**.

Thereafter, aircraft **1700** in **Figure 17** may go through certification and delivery **1610** in order to be placed in service **1612**. While in service **1612** by a customer, aircraft **1700** in **Figure 17** may be scheduled for routine maintenance and service **1614**, which may include modification, reconfiguration, refurbishment, and other maintenance or service. One or more of the components in coating system **102** may be employed during rework to apply coating material **136** to objects in aircraft **1700**.

Each of the processes of aircraft manufacturing and service method **1600** may be performed or carried out by a system integrator, a third party, and/or an operator. In these examples, the operator may be a customer. For the purposes of this description, a system integrator may include, without limitation, any number of aircraft manufacturers and major-system subcontractors; a third party may include, without limitation, any number of vendors, subcontractors, and suppliers; and an operator may be an airline, a leasing company, a military entity, a service organization, and so on.

With reference now to **Figure 17**, an illustration of a block diagram of an aircraft is depicted in which an illustrative embodiment may be implemented. In this example, aircraft **1700** may be produced by aircraft manufacturing and service method

1600 in **Figure 16** and may include airframe 1702 with plurality of systems 1704 and interior 1706. Examples of systems 1704 include one or more of propulsion system 1708, electrical system 1710, hydraulic system 1712, and environmental system 1714. Any
5 number of other systems may be included. Although an aerospace example is shown, different illustrative embodiments may be applied to other industries, such as the automotive industry.

Apparatuses and methods embodied herein may be employed during at least one of the stages of aircraft manufacturing and
10 service method 1600 in **Figure 16**. For example, without limitation, coating system 102 may be used to coat the surfaces of different aircraft components during any one of component and subassembly manufacturing 1606, system integration 1608,
certification and delivery 1610, in service 1612, and
15 maintenance and service 1614 in **Figure 16**. In particular, it may be used to coat components of, for example, airframe 1702, systems 1704, and interior 1706 of aircraft 1700, among others.

In one illustrative example, components or subassemblies produced in component and subassembly manufacturing 1606 in
20 **Figure 16** may be fabricated or manufactured in a manner similar to components or subassemblies produced while aircraft 1700 may be in service 1612 in **Figure 16**. As yet another example, one or more apparatus embodiments, method embodiments, or a combination thereof may be utilized during production stages, such as
25 component and subassembly manufacturing 1606 and system integration 1608 in **Figure 16**.

One or more apparatus embodiments, method embodiments, or a combination thereof may be utilized while aircraft 1700 is in component and subassembly manufacturing 1606, system integration
30 1608, and maintenance and service 1614 in **Figure 16**. For instance, coating system 102 may be used during component and subassembly manufacturing 1606 and system integration 1608 to apply coating material 136 to components or assemblies for aircraft 1700. During maintenance and service 1614, coating

system **102** may be used to coat components that need to be reworked for upgrades, refurbishment, or other operations that may be performed during maintenance and service **1614**. The use of a number of the different illustrative embodiments may substantially expedite the assembly and maintenance of and/or reduce the cost of aircraft **1700**.

Turning now to **Figure 18**, an illustration of a block diagram of a data processing system is depicted in accordance with an illustrative embodiment. Data processing system **1800** may be used to implement coating controller **140** in computer system **112** in **Figure 1**.

In this illustrative example, data processing system **1800** includes communications framework **1802**, which provides communications between processor unit **1804**, memory **1806**, persistent storage **1808**, communications unit **1810**, input/output (I/O) unit **1812**, and display **1814**. In this example, communication framework may take the form of a bus system.

Processor unit **1804** serves to execute instructions for software that may be loaded into memory **1806**. Processor unit **1804** may be a number of processors, a multi-processor core, or some other type of processor, depending on the particular implementation.

Memory **1806** and persistent storage **1808** may be examples of storage devices **1816**. A storage device may be any piece of hardware that may be capable of storing information, such as, for example, without limitation, without limitation, data, program code in functional form, and/or other suitable information either on a temporary basis and/or a permanent basis. Storage devices **1816** may also be referred to as computer readable storage devices in these illustrative examples. Memory **1806**, in these examples, may be, for example, without limitation, a random access memory or any other suitable volatile or non-volatile storage device. Persistent storage

1808 may take various forms, depending on the particular implementation.

For example, without limitation, persistent storage **1808** may contain one or more components or devices. For example, without limitation, persistent storage **1808** may be a hard drive, a flash memory, a rewritable optical disk, a rewritable magnetic tape, or some combination of the above. The media used by persistent storage **1808** also may be removable. For example, without limitation, a removable hard drive may be used for persistent storage **1808**.

Communications unit **1810**, in these illustrative examples, provides for communications with other data processing systems or devices. In these illustrative examples, communications unit **1810** may be a network interface card.

Input/output unit **1812** allows for input and output of data with other devices that may be connected to data processing system **1800**. For example, without limitation, input/output unit **1812** may provide a connection for user input through a keyboard, a mouse, and/or some other suitable input device. Further, input/output unit **1812** may send output to a printer. Display **1814** provides a mechanism to display information to a user.

Instructions for the operating system, applications, and/or programs may be located in storage devices **1816**, which may be in communication with processor unit **1804** through communications framework **1802**. The processes of the different embodiments may be performed by processor unit **1804** using computer-implemented instructions, which may be located in a memory, such as memory **1806**.

These instructions may be referred to as program code, computer usable program code, or computer readable program code that may be read and executed by a processor in processor unit **1804**. The program code in the different embodiments may be embodied on different physical or computer readable storage media, such as memory **1806** or persistent storage **1808**.

Program code **1818** may be located in a functional form on computer readable media **1820** that may be selectively removable and may be loaded onto or transferred to data processing system **1800** for execution by processor unit **1804**. Program code **1818** and computer readable media **1820** form computer program product **1822** in these illustrative examples. In one example, computer readable media **1820** may be computer readable storage media **1824** or computer readable signal media **1826**.

In these illustrative examples, computer readable storage media **1824** may be a physical or tangible storage device used to store program code **1818** rather than a medium that propagates or transmits program code **1818**.

Alternatively, program code **1818** may be transferred to data processing system **1800** using computer readable signal media **1826**. Computer readable signal media **1826** may be, for example, without limitation, a propagated data signal containing program code **1818**. For example, without limitation, computer readable signal media **1826** may be an electromagnetic signal, an optical signal, and/or any other suitable type of signal. These signals may be transmitted over communications links, such as wireless communications links, optical fiber cable, coaxial cable, a wire, and/or any other suitable type of communications link.

The different components illustrated for data processing system **1800** are not meant to provide architectural limitations to the manner in which different embodiments may be implemented. The different illustrative embodiments may be implemented in a data processing system including components in addition to and/or in place of those illustrated for data processing system **1800**. Other components shown in **Figure 18** can be varied from the illustrative examples shown. The different embodiments may be implemented using any hardware device or system capable of running program code **1818**.

The flowcharts and block diagrams in the different depicted embodiments illustrate the architecture, functionality, and

operation of some possible implementations of apparatuses and methods in an illustrative embodiment. In this regard, each block in the flowcharts or block diagrams may represent a module, a segment, a function, and/or a portion of an operation or step.

In some alternative implementations of an illustrative embodiment, the function or functions noted in the blocks may occur out of the order noted in the figures. For example, without limitation, in some cases, two blocks shown in succession may be executed substantially concurrently, or the blocks may sometimes be performed in the reverse order, depending upon the functionality involved. Also, other blocks may be added in addition to the illustrated blocks in a flowchart or block diagram.

Thus, one or more illustrative embodiments provide a method and apparatus for coating an object using a robotic object coating system. In one illustrative embodiment, a coating controller may be configured to generate a three-dimensional model of a group of objects and form segments from the group of objects in the three-dimensional model. The coating controller may be further configured to generate instructions for coating the group of objects based on the segments. These instructions may be configured to cause a robotic coating system to coat the group of objects.

In the illustrative examples, a sensor system provides real-time input to the coating controller. The sensor system may be operated automatically or by a human operator prior to the coating process. In this manner, the coating system may provide real time information regarding the orientation of each of the objects in the group of objects to be coated. The process may be automated and may not expose human operators to undesirable conditions. Accordingly, the process of coating groups of objects may be completed more efficiently, accurately, and safely than with some currently used systems.

The description of the different illustrative embodiments has been presented for purposes of illustration and description, and is not intended to be exhaustive or limited to the embodiments in the form disclosed. Many modifications and variations will be apparent to those of ordinary skill in the art. Further, different illustrative embodiments may provide different features as compared to other illustrative embodiments. The embodiment or embodiments selected are chosen and described in order to best explain the principles of the embodiments, the practical application, and to enable others of ordinary skill in the art to understand the disclosure for various embodiments with various modifications as are suited to the particular use contemplated.

CLAIMS:

What is claimed is:

- 5 1. A method for coating a group of objects, the method comprising:
- generating a three-dimensional model of the group of objects;
- forming segments that represent each object in the group of
- 10 objects in the three-dimensional model; and
- generating instructions for coating the group of objects based on the segments, in which the instructions are configured to cause a robotic coating system to coat the group of objects.
- 15 2. The method of claim 1, wherein the three-dimensional model is generated in real time.
3. The method of claim 1, further comprising:
- operating the robotic coating system to apply a coating to
- 20 the group of objects using the instructions.
4. The method of claim 3, wherein the coating is selected from one of a paint, an adhesive, a sealant, a lubricant, a wear resistant coating, a corrosion resistant coating, and a scratch
- 25 resistant coating.
5. The method of claim 1, wherein generating the three-dimensional model of the group of objects comprises:
- generating data about the group of objects using a sensor
- 30 system; and
- generating the three-dimensional model of the group of objects from the data generated by the sensor system.

6. The method of claim 5, wherein the sensor system is selected from one of a camera system or a laser scanner.

7. The method of claim 5, wherein the data is selected from at least one of images or three-dimensional coordinates for a surface of the group of objects.

8. The method of claim 5, wherein the sensor system comprises a depth sensor.

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9. The method of claim 5, wherein the sensor system is associated with the robotic coating system.

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10. The method of claim 1, wherein the three-dimensional model is selected from one of a point cloud and a computer-aided design model.

11. The method of claim 1, wherein the instructions comprise at least one of waypoints or trajectories.

20

12. The method of claim 1, wherein generating instructions for coating the group of objects comprises:

identifying waypoints along an object in the group of objects; and

25

generating a trajectory for movement of the robotic coating system along the object from the waypoints.

13. The method of claim 1, wherein forming the segments that represent objects in the group of objects in the three-

30

dimensional model comprises:

identifying representations of the objects and clutter in the three-dimensional model; and

separating the representations of the objects from the clutter to form segments in a segmented three-dimensional model.

14. The method of claim 1, wherein the group of objects comprises at least one of an aircraft part, a tube, a spar, a reservoir, a stringer, a panel, or a barrel.

5

15. An apparatus comprising:

a coating controller configured to generate a three-dimensional model of a group of objects, form segments for the group of objects in the three-dimensional model, and generate instructions for coating the group of objects based on the segments, in which the instructions are configured to cause a robotic coating system to coat the group of objects.

10

16. The apparatus of claim 15, further comprising:

15

a sensor system configured to generate data about the group of objects.

17. The apparatus of claim 16, wherein the sensor system is selected from one of a camera system and a laser scanner.

20

18. The apparatus of claim 17, wherein the sensor system comprises a depth sensor.

19. The apparatus of claim 17, wherein the coating controller is further configured to generate the three-dimensional model of the group of objects from the data generated by the sensor system.

25

20. The apparatus of claim 17, wherein the robotic coating system is a robotic painting system and wherein the instructions include painting trajectories for the robotic coating system to paint the group of objects.

30

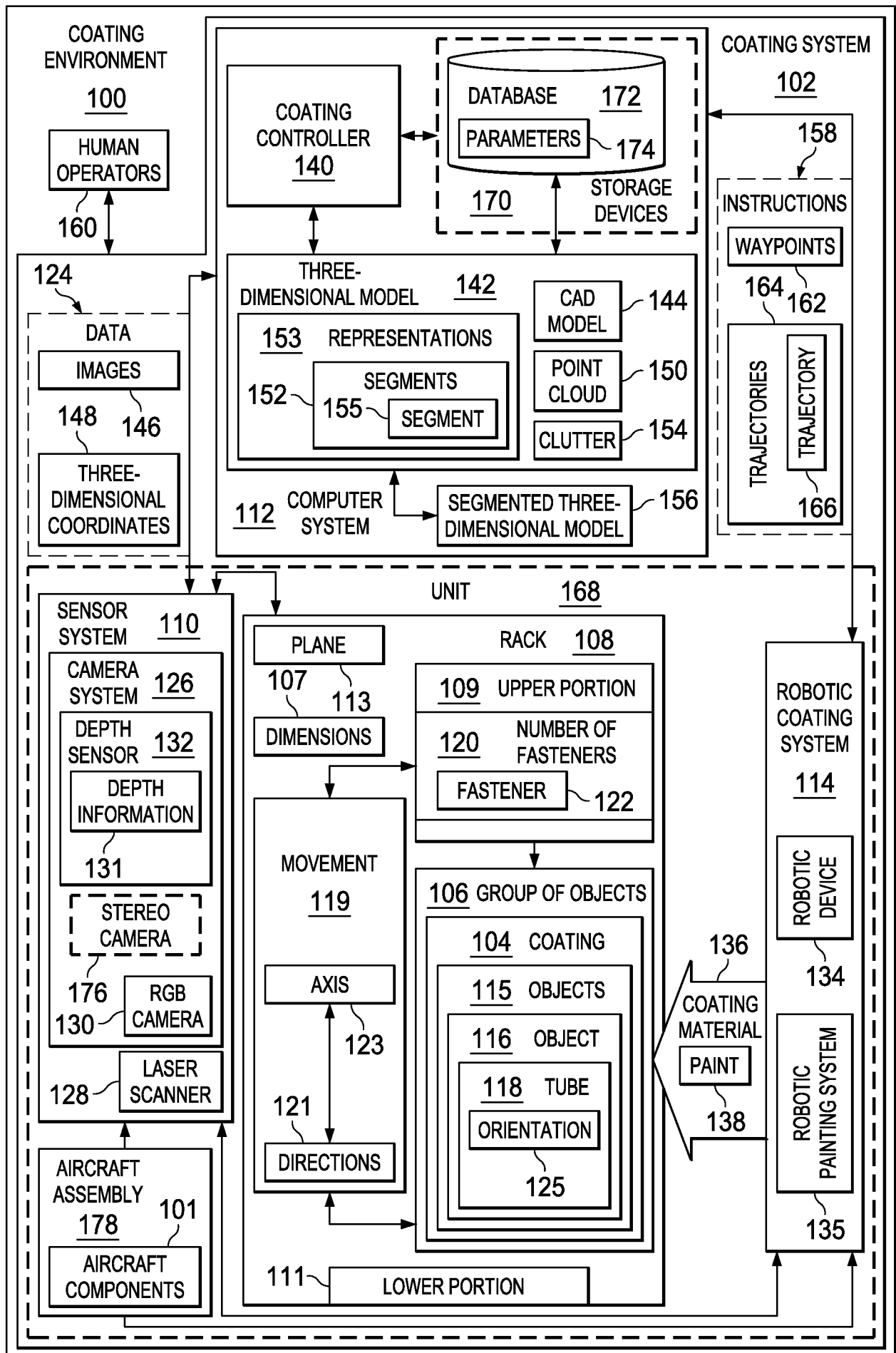
21. The apparatus of claim 15, wherein the robotic coating system is configured to receive the instructions and use the instructions to apply a coating to the group of objects.

5 22. The apparatus of claim 21, wherein the coating is selected from one of a paint, an adhesive, a sealant, a lubricant, a wear resistant coating, a corrosion resistant coating, and a scratch resistant coating.

10 23. The apparatus of claim 15, wherein the group of objects comprises at least one of an aircraft part, a tube, a spar, a reservoir, a stringer, a panel, or a barrel.

FIG. 1

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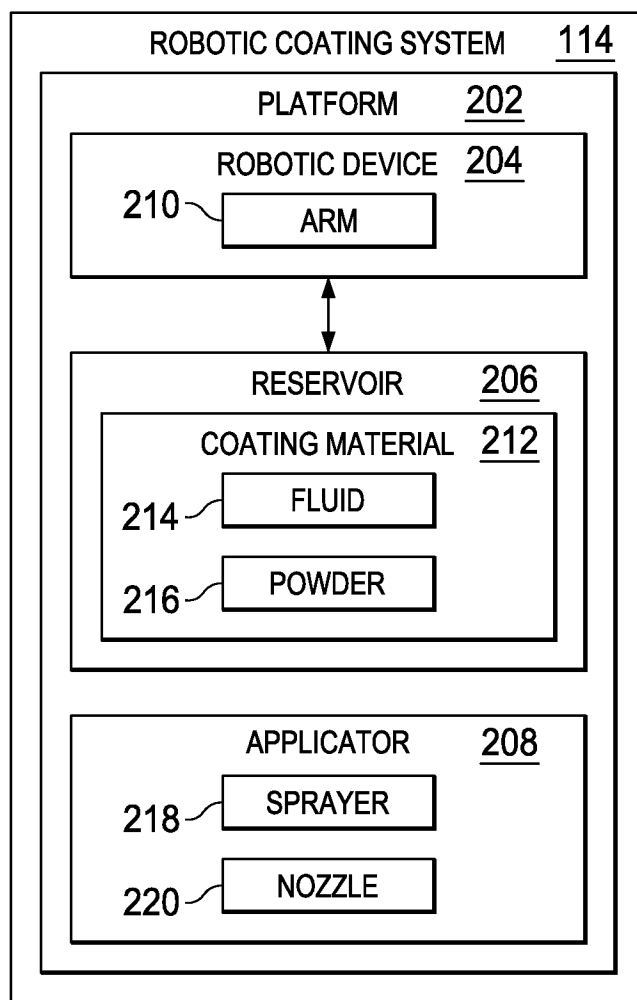


FIG. 2

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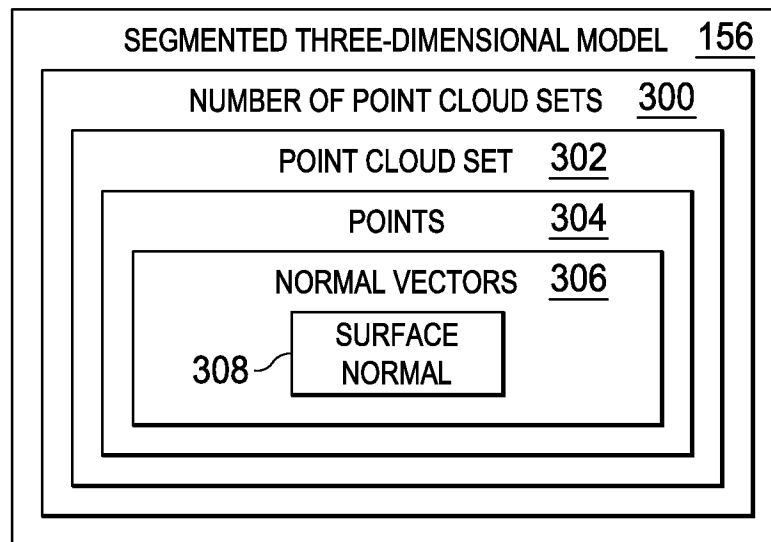


FIG. 3

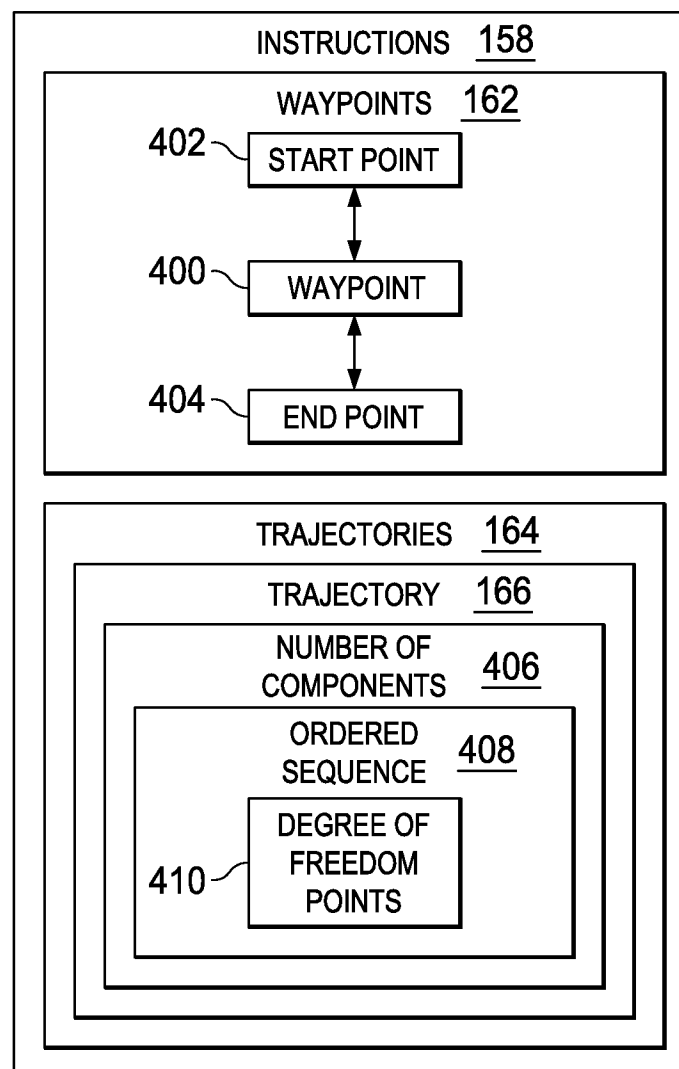


FIG. 4

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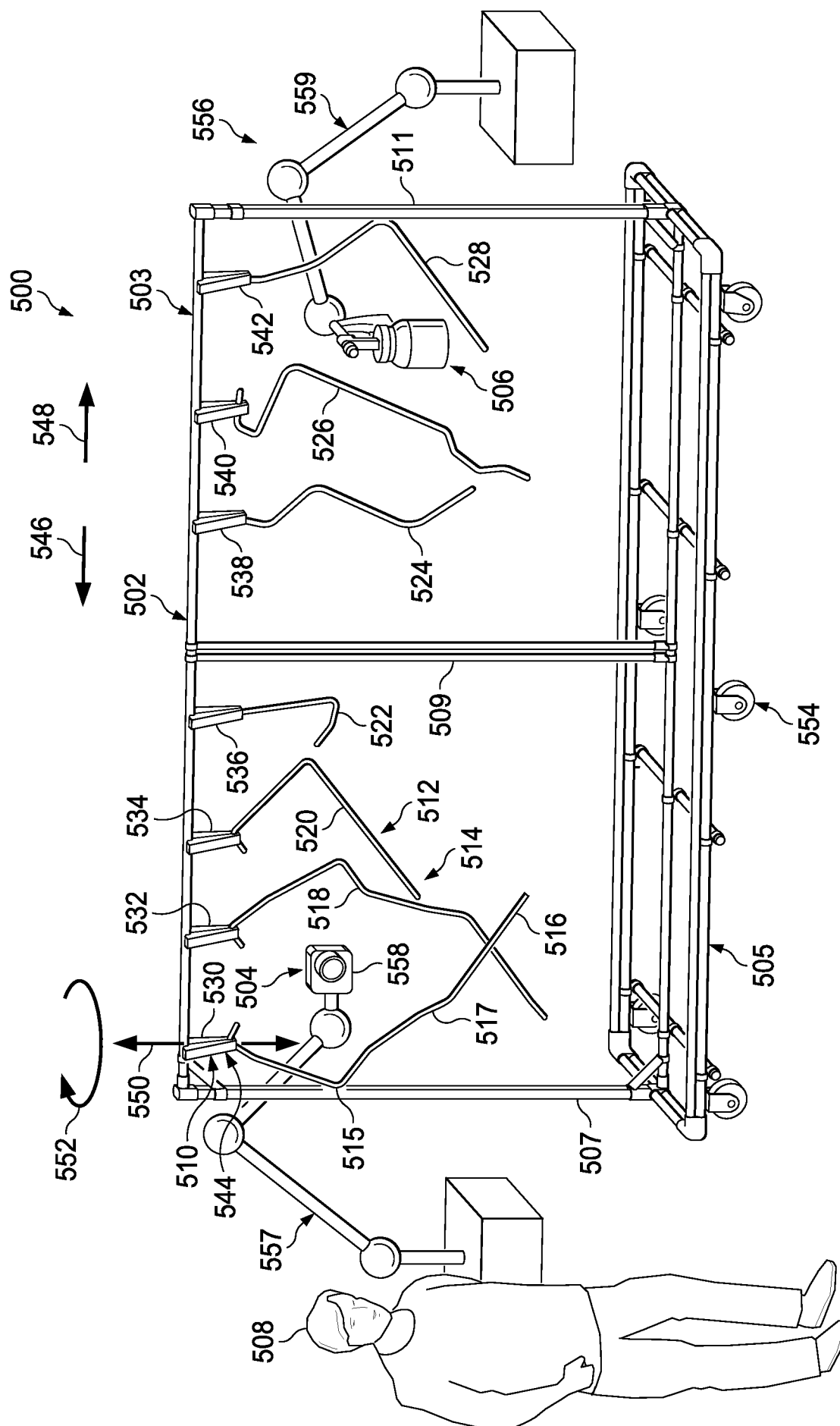


FIG. 5

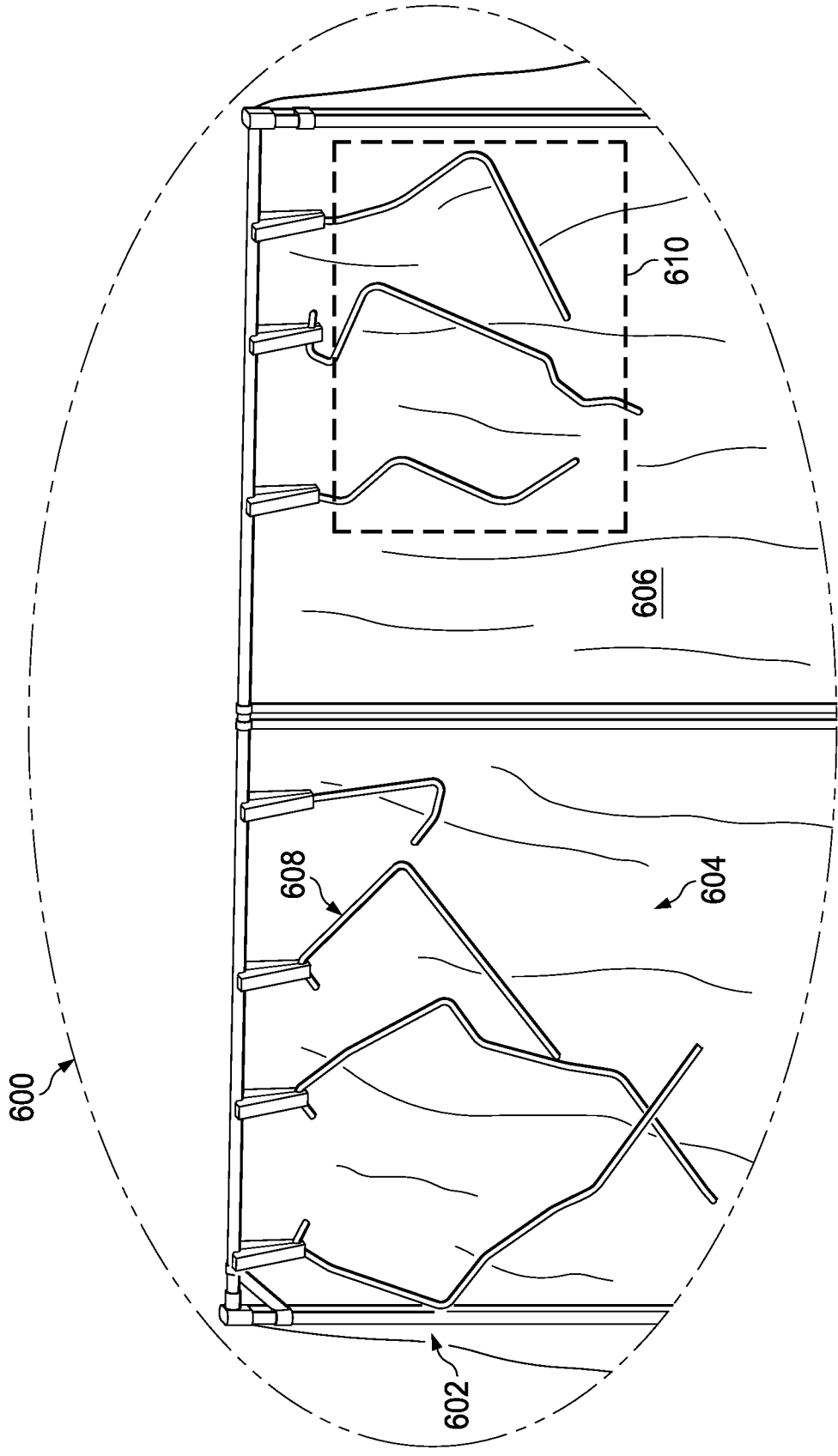


FIG. 6

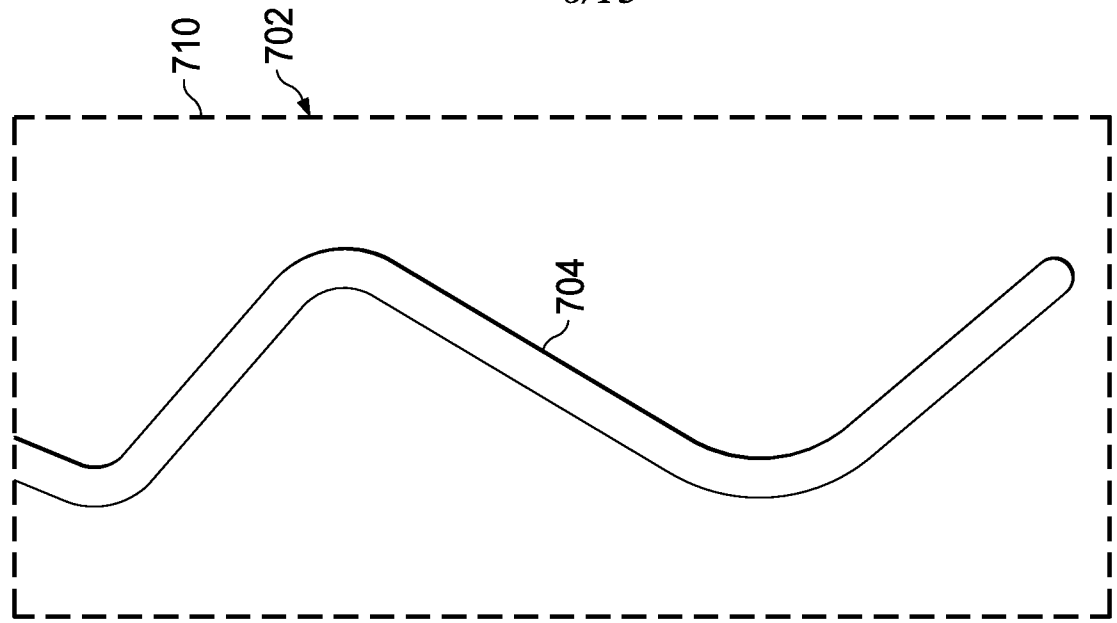


FIG. 8

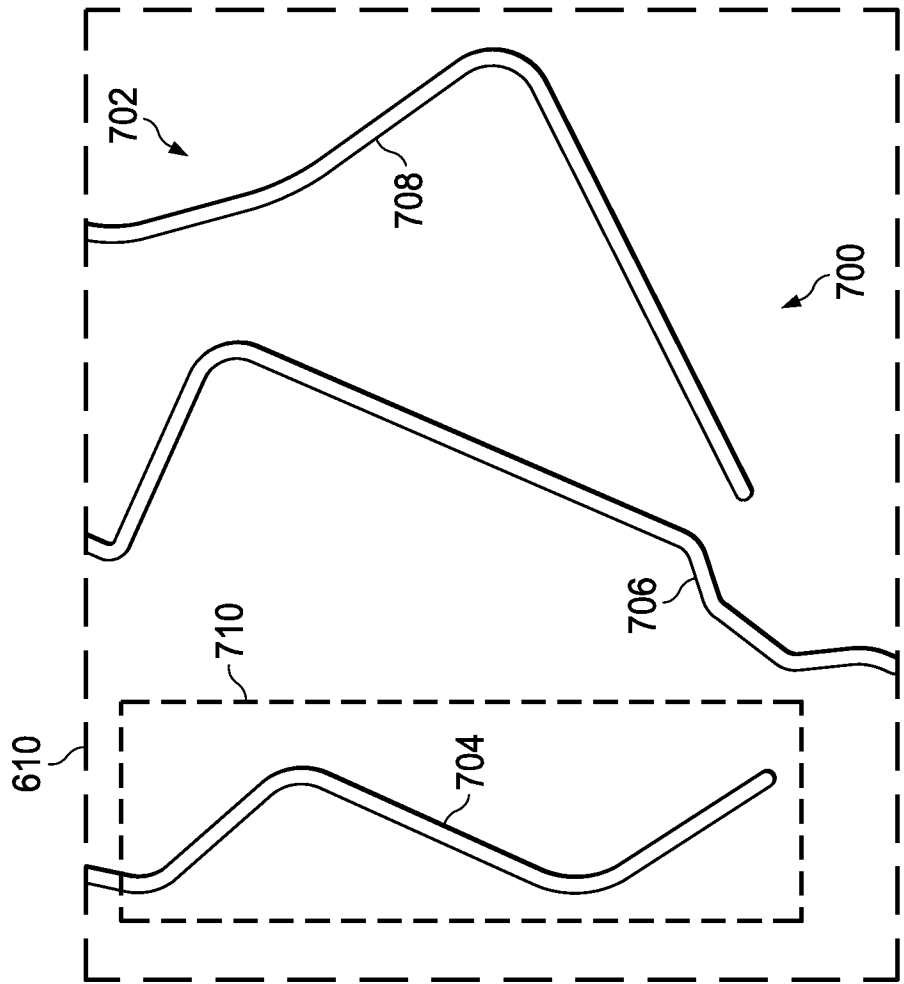


FIG. 7

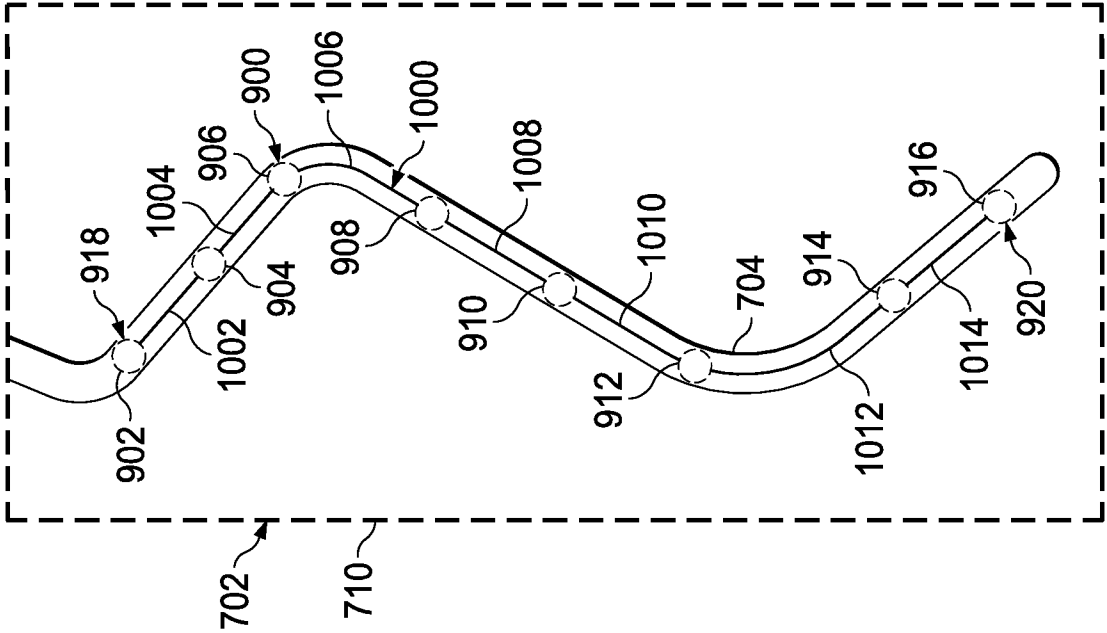


FIG. 9

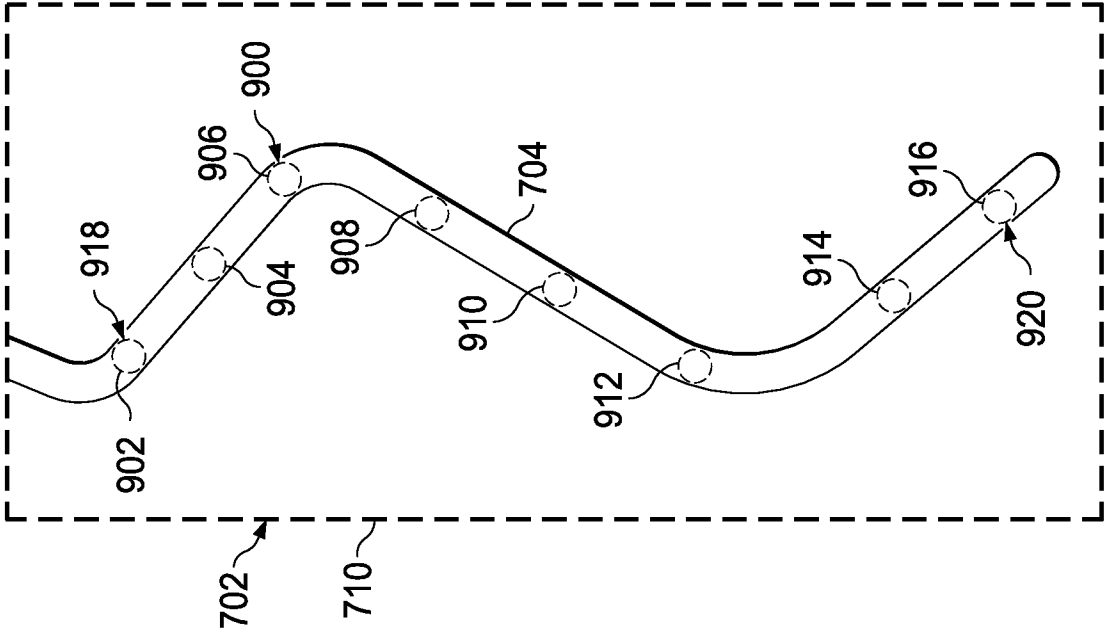


FIG. 10

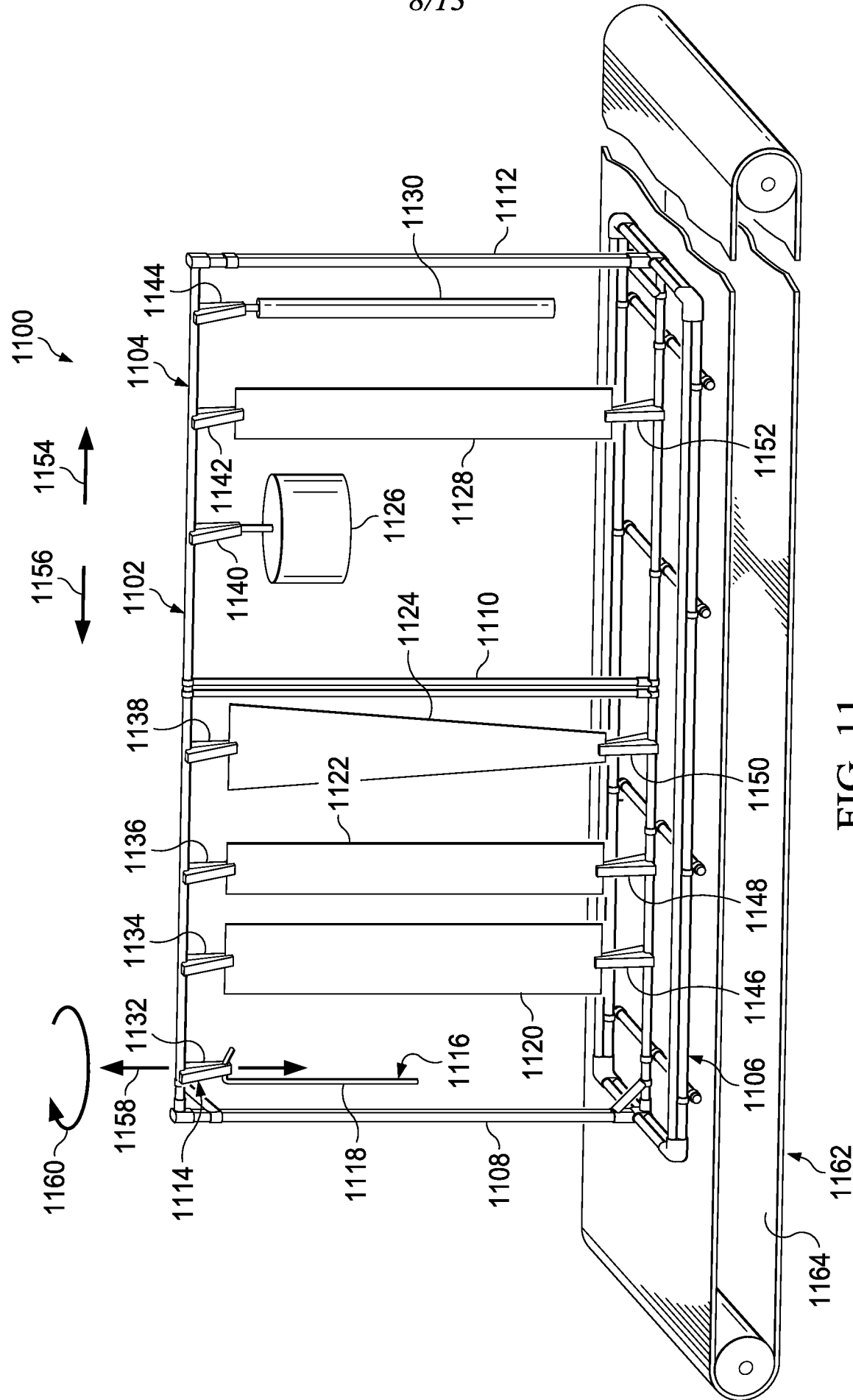


FIG. 11

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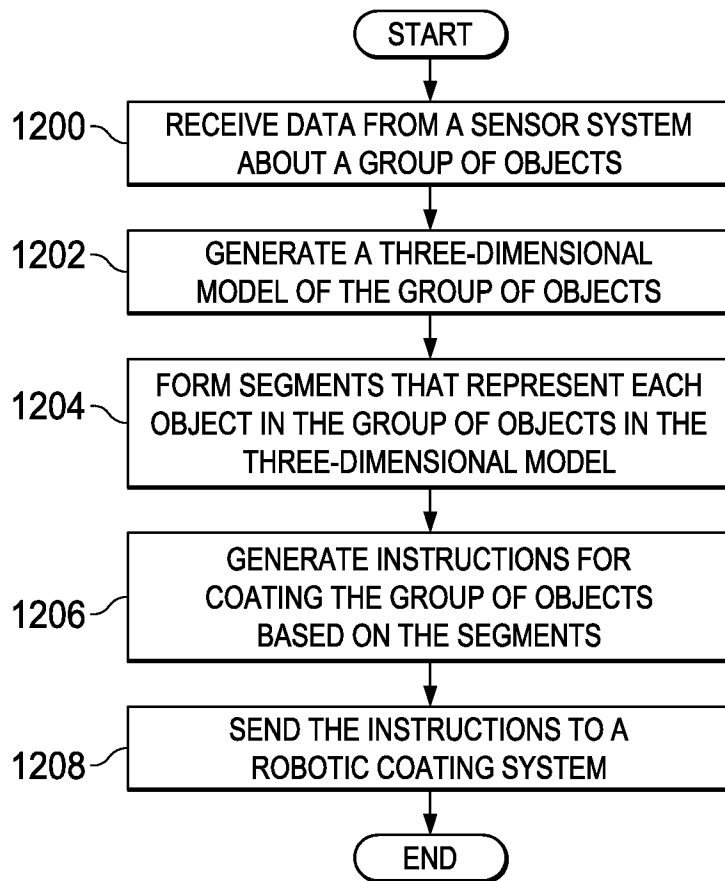


FIG. 12

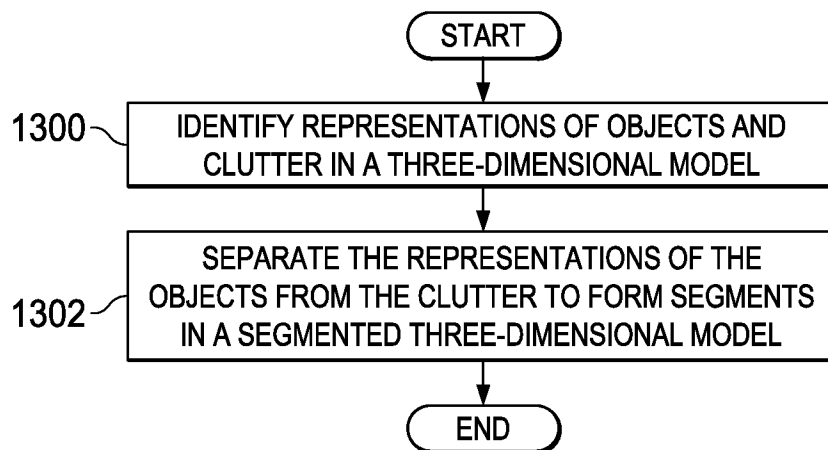


FIG. 13

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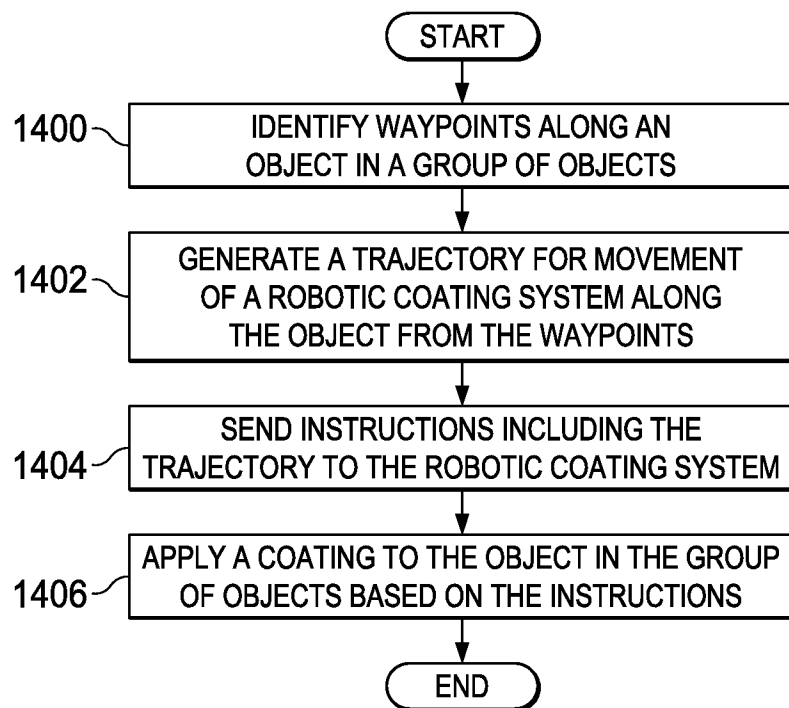


FIG. 14

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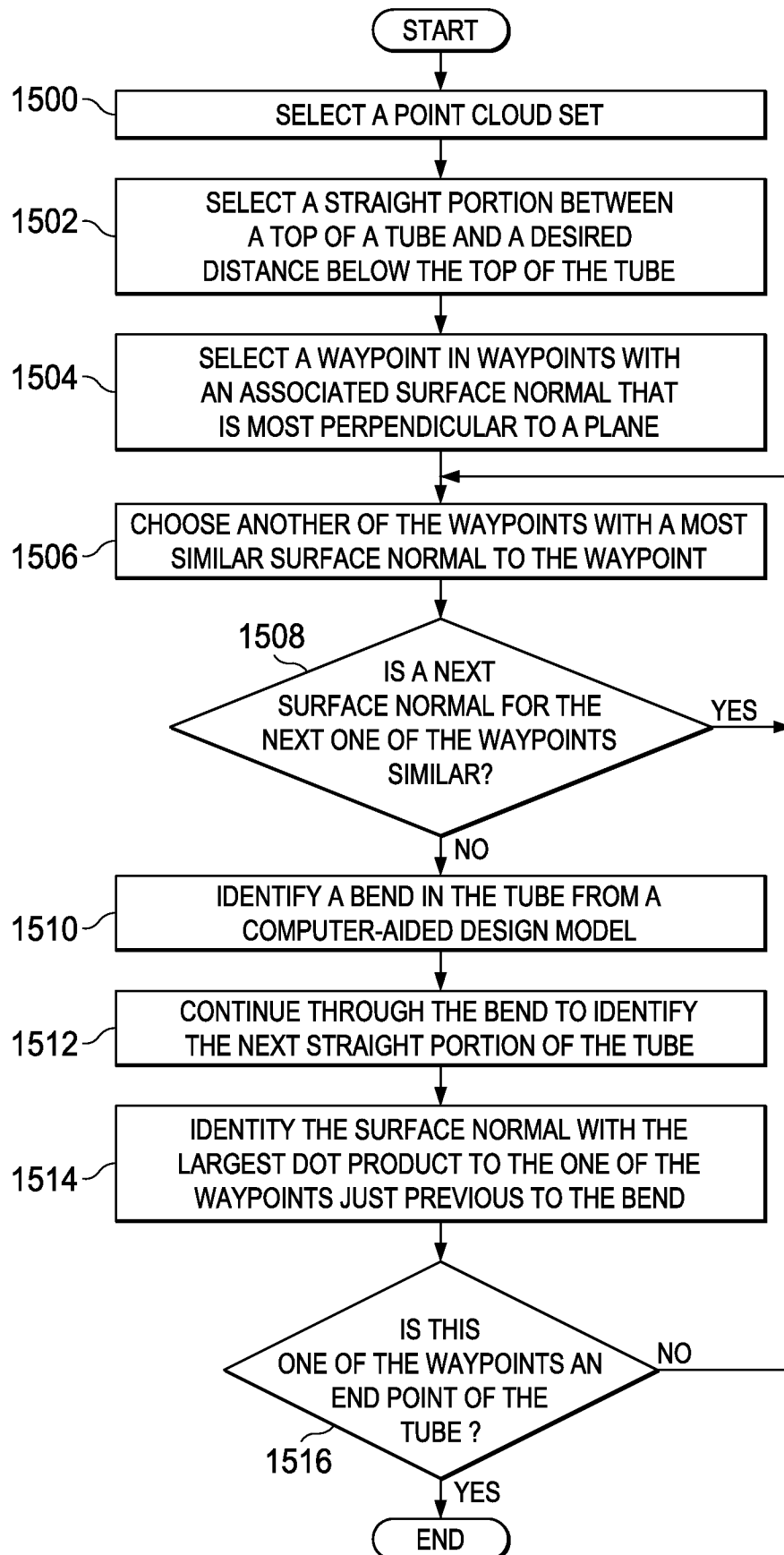
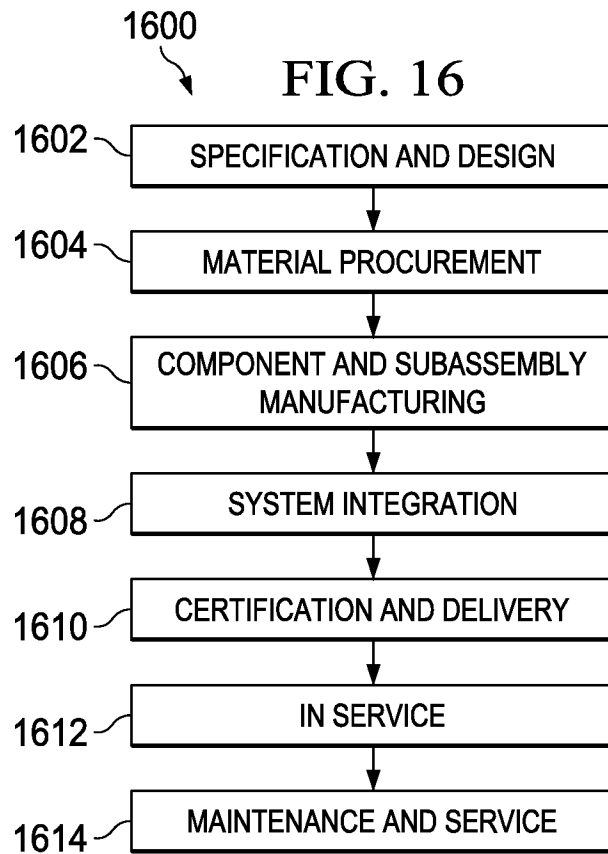
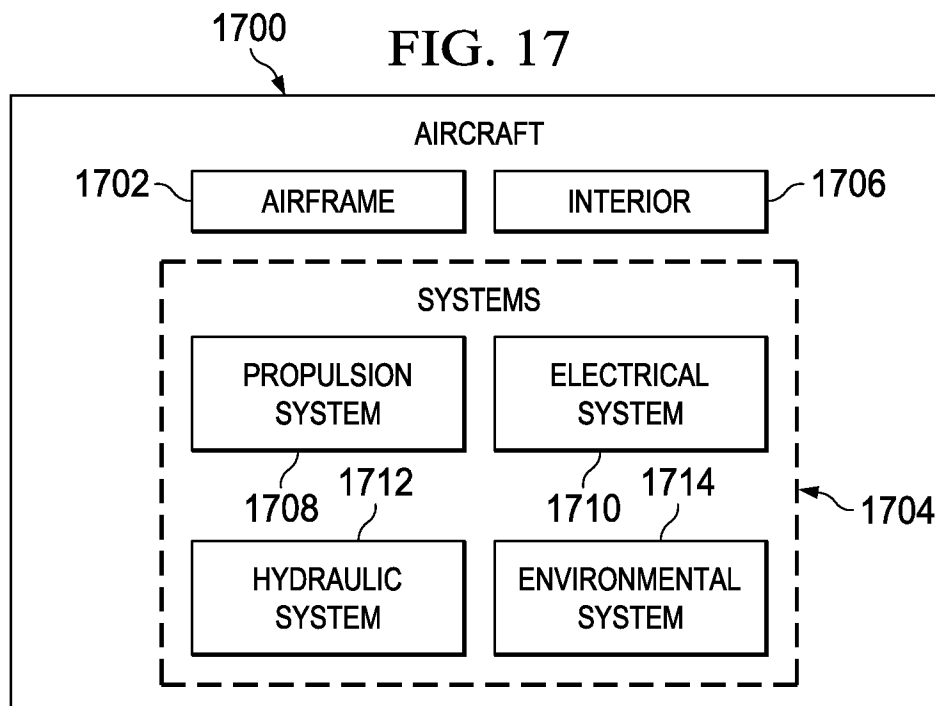
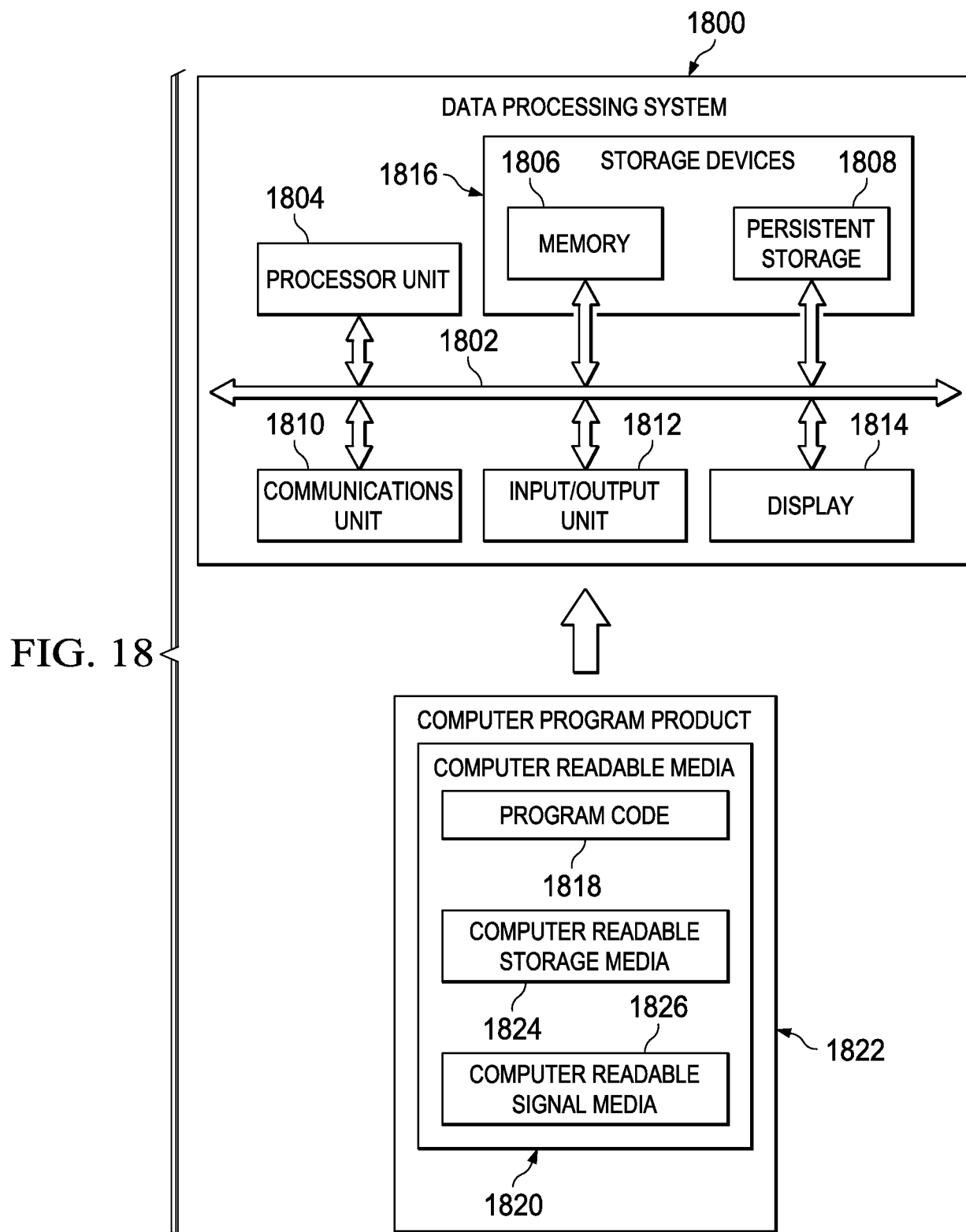


FIG. 15

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INTERNATIONAL SEARCH REPORT

International application No
PCT/US2014/049599

A. CLASSIFICATION OF SUBJECT MATTER
INV. B05B12/12 B05B13/04
ADD.

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)
B05B G06F G05B

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched

Electronic data base consulted during the international search (name of data base and, where practicable, search terms used)

EPO-Internal, WPI Data

C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
Y	EP 1 712 294 A1 (ABB SERVICE SRL [IT]) 18 October 2006 (2006-10-18) paragraph [0018] - paragraph [0038]; figures	1-23
Y	----- MIAN, AJMAL S.; BENNAMOUN, MOHAMMED; OWENS, ROBYN: "Three-Dimensional Model-Based Object Recognition and Segmentation in Cluttered Scenes", IEEE TRANSACTIONS ON PATTERN ANALYSIS AND MACHINE INTELLIGENCE, vol. 28, no. 10, 11 August 2006 (2006-08-11), pages 1584-1601, XP002731731, paragraph [07.1] - paragraph [08.3] ----- -/-	1-23



Further documents are listed in the continuation of Box C.



See patent family annex.

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"A" document defining the general state of the art which is not considered to be of particular relevance

"E" earlier application or patent but published on or after the international filing date

"L" document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified)

"O" document referring to an oral disclosure, use, exhibition or other means

"P" document published prior to the international filing date but later than the priority date claimed

"T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention

"X" document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone

"Y" document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art

"&" document member of the same patent family

Date of the actual completion of the international search

28 October 2014

Date of mailing of the international search report

10/11/2014

Name and mailing address of the ISA/

European Patent Office, P.B. 5818 Patentlaan 2
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Authorized officer

Innecken, Axel

INTERNATIONAL SEARCH REPORT

International application No
PCT/US2014/049599

C(Continuation). DOCUMENTS CONSIDERED TO BE RELEVANT		
Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
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