

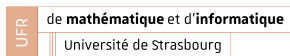
Reactive Trajectory Planning for Robotic Operations in an Unstructured Environment

Simulated by Tecnomatix Process Simulate

Giulio Carpi Lapi

Université de Strasbourg

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The SIEMENS logo in a bold, teal, sans-serif font.

Outline

- 1 Context
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- 3 Project Objectives
- 4 Process Simulate
- 5 Implementation
 - Virtual Camera Configuration
 - Point Cloud Generation
 - Robot Geometries Filtering
 - Object Flow and Custom Simulator
 - Static Environment Filtering
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- **Industry 4.0:** AI, IoT, and data analytics.
- **Digital Twins & Simulation:** Virtual testing, process optimization, and reducing costs.
- **Automation:** Competitiveness, precision, and safety.

- **Advanced Robotic Kinematics** team.
- **Kineo** department.
- **Siemens Digital Industries Software**, Toulouse.

- Founded in **2001** as a spin-off from **LAAS-CNRS**.
- Acquired by **Siemens PLM Software** in **2012**.
- **Automatic motion planning** and **collision detection**.
- **Software Development Kits** to be **integrated** into **third-party software**.

KineoWorks: Collision-free trajectories

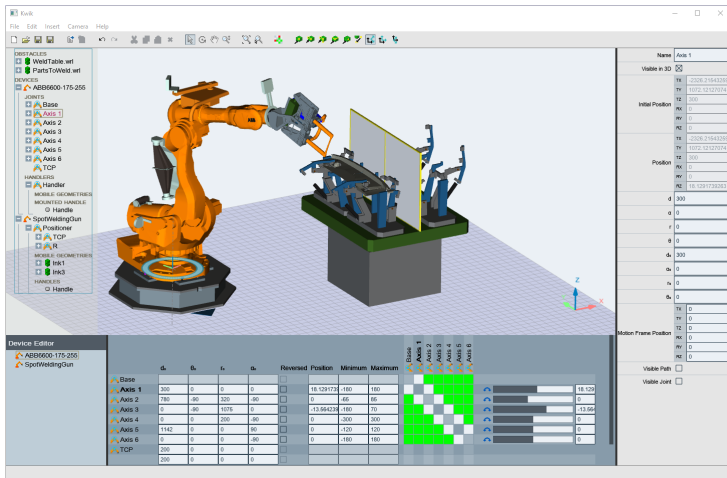


Figure: KineoWorks interface which computes collision-free trajectories [1]

Kineo Collision Detector: Collision detection

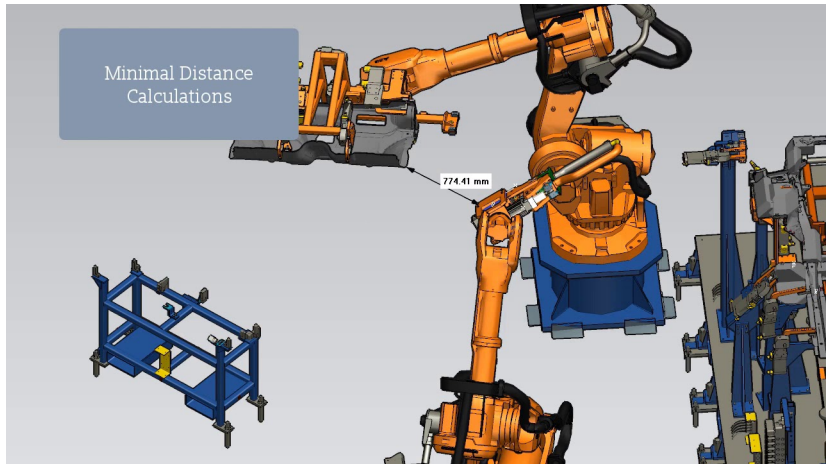


Figure: Kineo Collision Detector which performs collision detection [2]

Kineo Flexible Cables: Deformable cables simulation

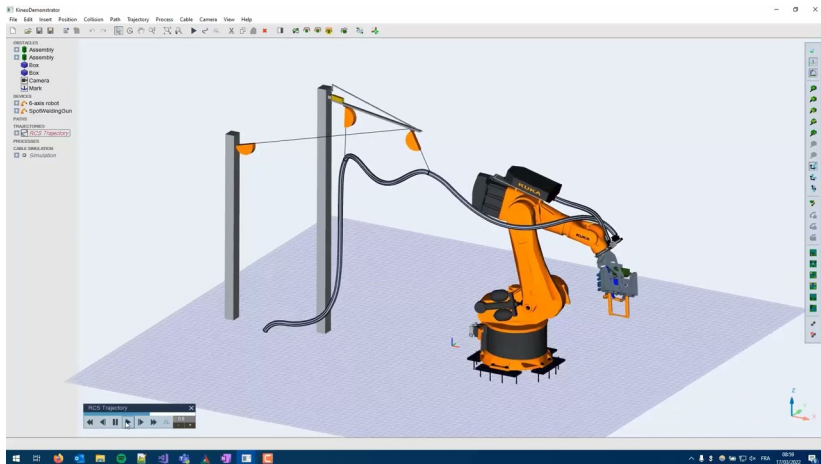


Figure: Kineo Flexible Cables which simulates the behavior of deformable cables [3]

Kineo 3D Nesting: Parts arrangement optimization

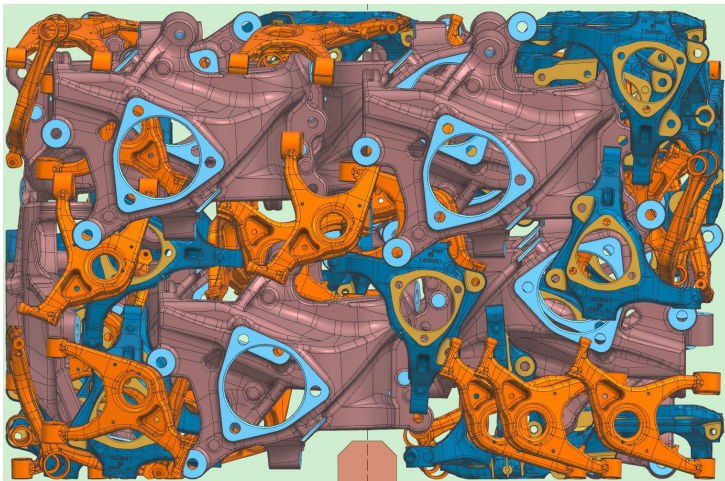


Figure: Kineo 3D Nesting which optimizes the arrangement of parts within a defined space [4]

- **Scrum** methodology.
- **2-3 week sprints** with **daily stand-up meetings**.
- **Polarion** application lifecycle management.
- **Git, Git Extensions** for version control.

- **Proof-of-concept** of **reactive trajectory planner** for **Tecnomatix Process Simulate**.
- Reactive **dynamic obstacles avoidance** based on real-time virtual **camera data**.
- Safe collaboration between **robots, inspection drones, and AGVs**.

- Siemens **digital manufacturing** software.
- **Design, simulate, and validate manufacturing processes.**
- Test **control logic** in a **virtual setting** before **physical deployment.**

The Environment: A robotic workcell

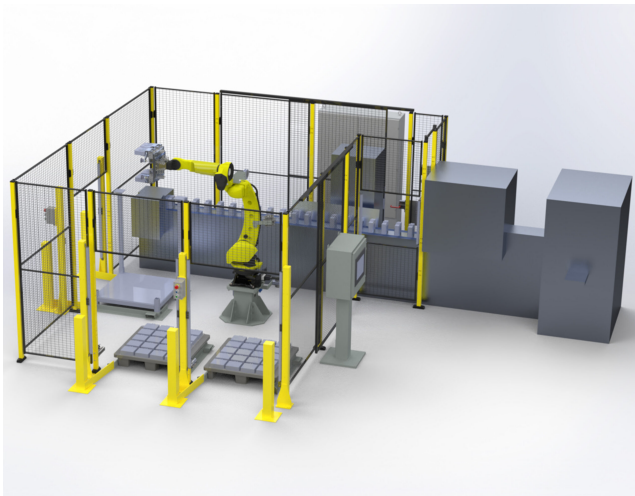


Figure: A typical robotic workcell [5]

The Environment: 3D bin picking

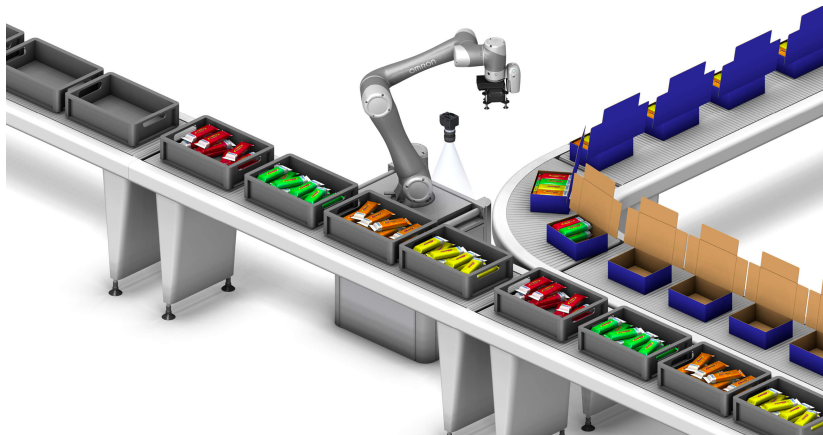


Figure: A bin picking scenario [6]

**Video demonstration of a bin-picking operation in
Tecnomatix Process Simulate.**

Reactive Control Loop: The perception pipeline

- ① **Capture & Generate**: From **depth data** from virtual cameras to **3D point cloud**.
- ② **Filter Stage 1**: Filter robot's geometries.
- ③ **Filter Stage 2**: Filter static environment.
- ④ **Detect Collisions**: between **robot** and **point cloud**.
- ⑤ **Path Planning**: Generate a **collision-free path**.

Reactive Control Loop: State machine

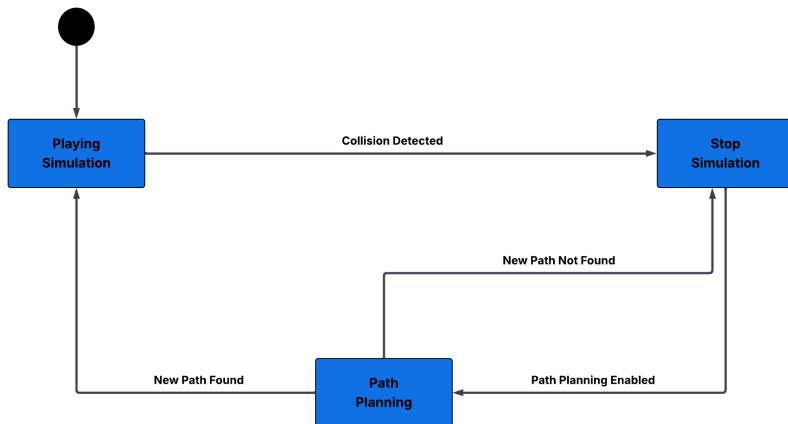


Figure: State machine for the complete reactive control loop.

- My work extends the core **Automatic Path Planning** functionality.
- **Integration of Kineo's core technologies in Tecnomatix Process Simulate.**

- **Presentation (C#/WPF):** The User Interface.
- **Application (C#):** Orchestrates the workflow.
- **Bridge (C++/CLI):** Connects managed C# to native C++.
- **Core Engine (C++):** High-performance simulation and algorithms.

Test Scenario: Bin picking operation

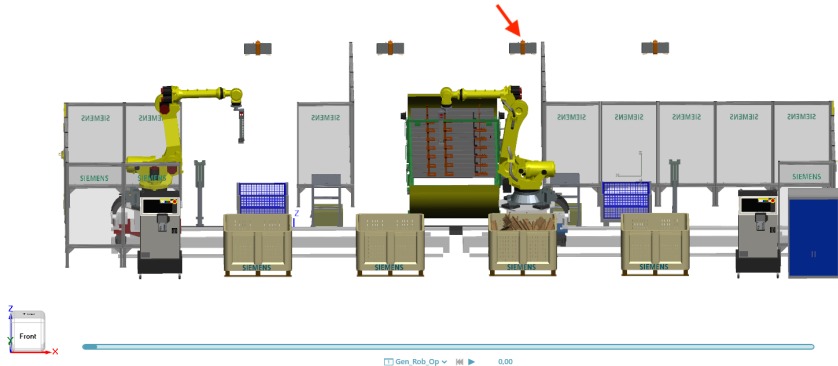


Figure: Initial state before the operation begins.

Virtual Camera Output: RGB image

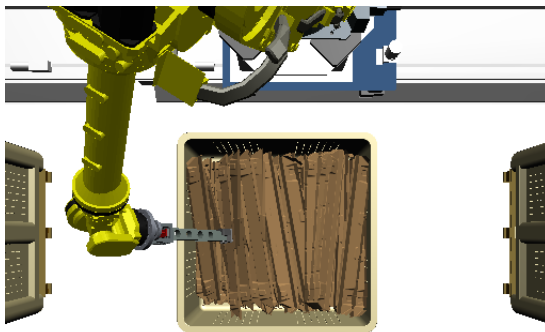


Figure: RGB virtual camera output at initial state.

Virtual Camera Output: Depth map

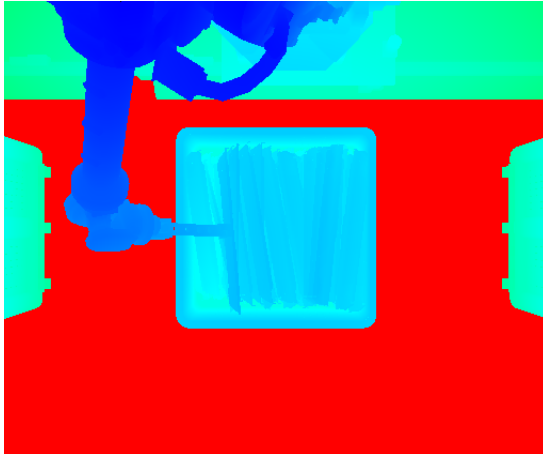


Figure: RGB-D virtual camera output at initial state.

Tecnomatix Snapshot API Benchmark

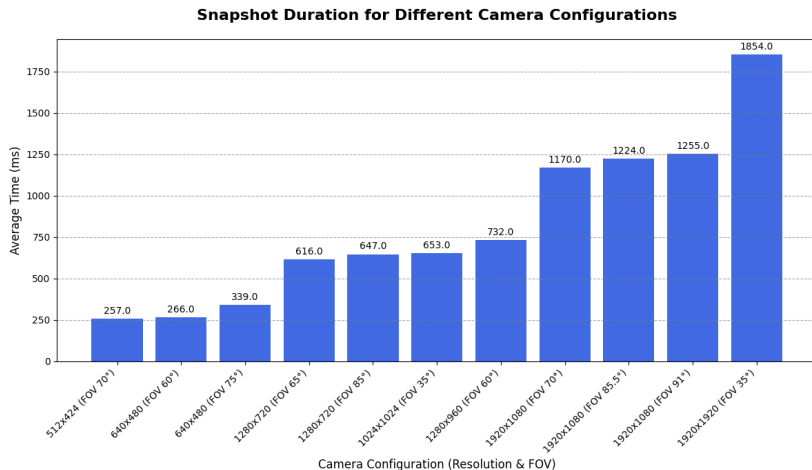


Figure: Snapshot duration vs. camera configuration.

- 512×424 and 70° FOV (Microsoft Kinect v2).
- **Depth buffer:** 217,088 values.
- Snapshot operation averaged 250 ms.

- **Depth buffer**: 2D array stored as 1D float list in row-major order.
- Each value represents the **distance** from the **camera** to an **object** at **pixel (u, v)**.
- Access **pixel (u, v)** at index: $v \times \text{width} + u$.

- **Focal Length (f):** Derived from field of view (FOV) and image dimensions.

$$f = \frac{\sqrt{\text{width}^2 + \text{height}^2}}{2 \tan\left(\frac{\text{FOV}}{2}\right)}$$

- **Principal Points (c_x, c_y):** Define the **optical center** of the image.

$$c_x = \frac{\text{width} - 1}{2}, \quad c_y = \frac{\text{height} - 1}{2}$$

① **Depth:** $d = \text{depthBuffer}[v \times \text{width} + u]$

② **Normalization factor:**

$$t = \sqrt{\left(\frac{u - c_x}{f}\right)^2 + \left(\frac{v - c_y}{f}\right)^2 + 1}$$

③ **3D coordinates** in camera space:

$$X = \frac{(v - c_y) \times d}{f \times t}, \quad Y = \frac{(c_x - u) \times d}{f \times t}, \quad Z = \frac{d}{t}$$

Apply the **transformation matrix**:

$$P_{world} = T_{camera \rightarrow world} \times P_{camera}$$

Point Cloud Generation: Generated point cloud

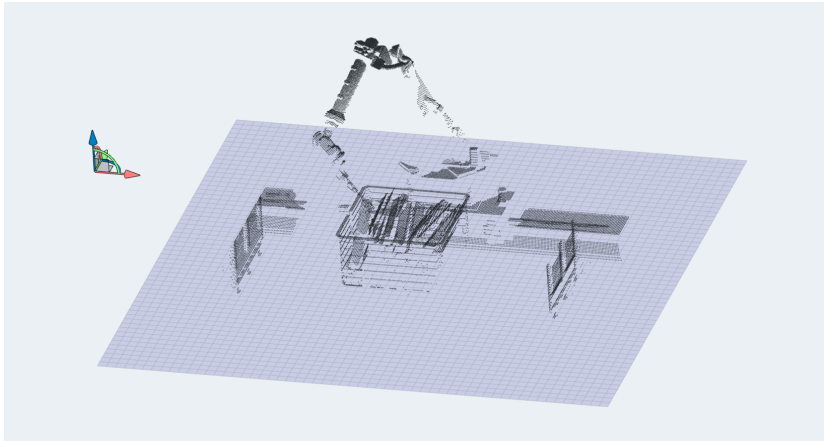


Figure: Generated point cloud (includes robot).

Robot's Geometries Filtering: Robot's geometry

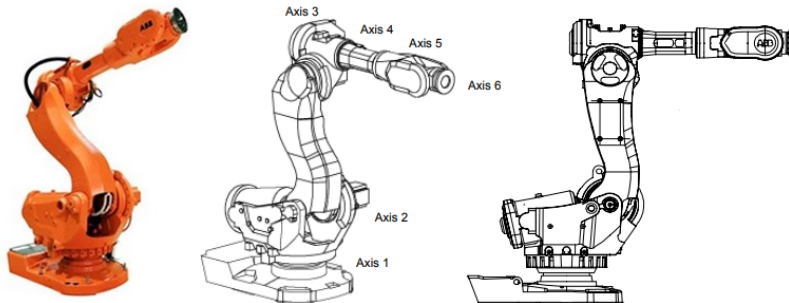


Figure: Robot's geometries [7].

Robot's Geometries Filtering: Oriented bounding boxes

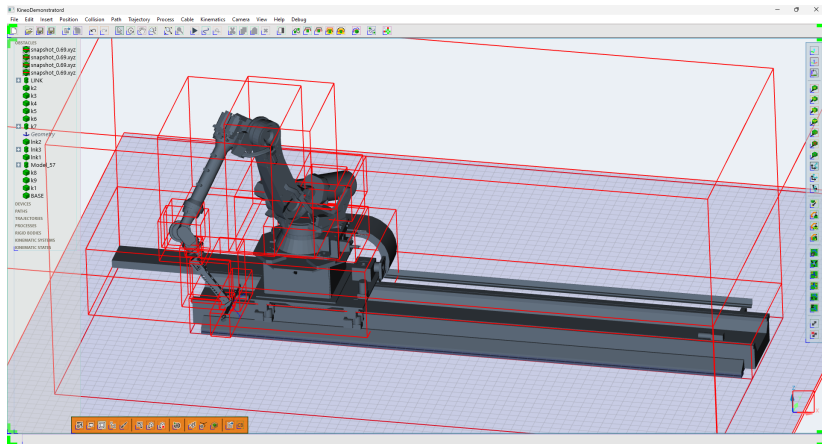


Figure: Device's Oriented Bounding Box.

- 1 Retrieve **current robot's kinematic configuration**.
- 2 Get **oriented bounding boxes**.
- 3 Discard any point inside the OBBs.

Prevents from **detecting** the robotic system as an obstacle.

Filtered Point Cloud

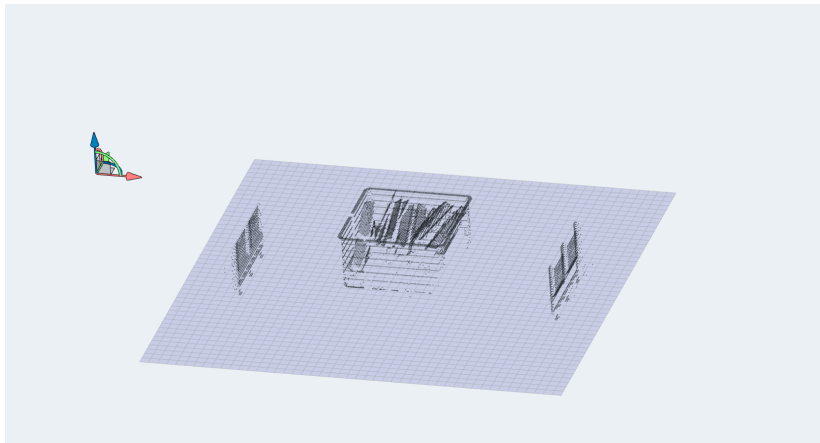


Figure: Filtered point cloud (After robot points are removed).

- Box representing **dynamic obstacle**
- **Object flow operation** moves the **box** to **collide** with **robotic system**.
- Simulates **automated guided vehicle** or **inspection drone** entering the **robot's workspace**.

Object Flow Operation

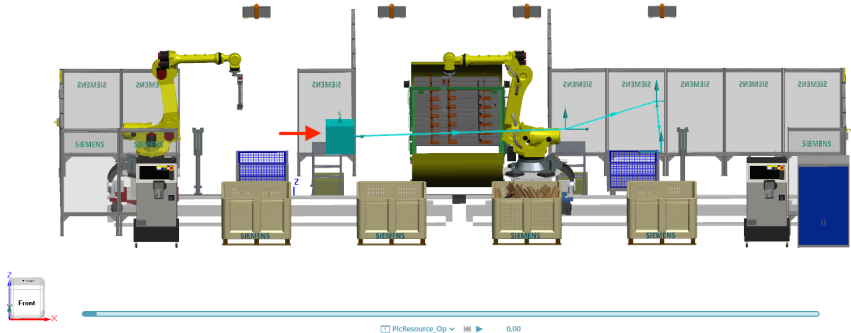


Figure: The dynamic obstacle (box) and its planned trajectory (blue).

Virtual Camera Output: RGB image

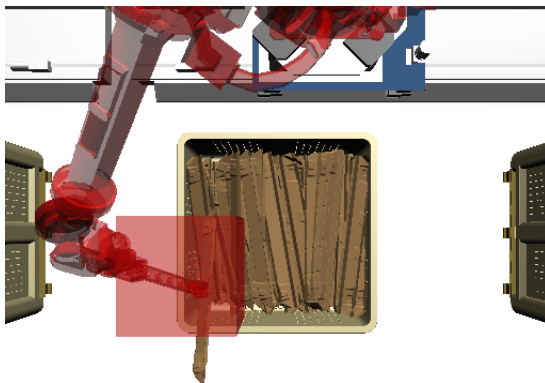


Figure: RGB virtual camera output at the moment of detected collision.

Virtual Camera Output: Depth map

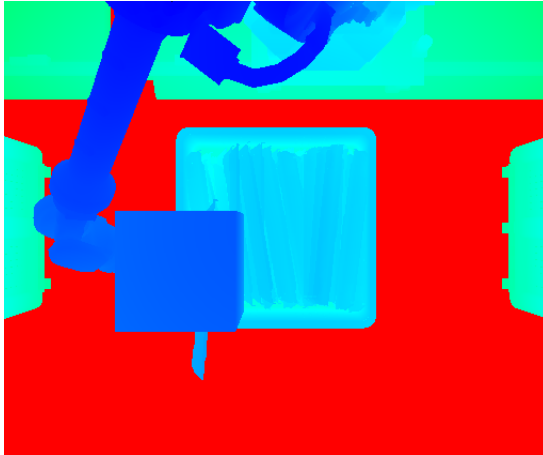


Figure: RGB-D virtual camera output at the moment of detected collision.

- **Tecnomatix Process Simulate's** graphics engine.
- Advances simulation time in **discrete steps**.
- Calculates and **updates the poses** of the **robot** and the **box**.
- Creates **synchronized, dynamic test environment**.

- 1 Save **static baseline** point cloud.
- 2 **Compare** each subsequent **point cloud** to **baseline**.
- 3 **Discard** any point that is **close** to a point in the baseline.

Result: Point cloud containing only **dynamic** objects.

- 1 Point cloud **wrapped** in custom **Kineo PointCloud** geometry object.
- 2 **Collision Set** with **robotic system** and **point cloud**.
- 3 **Kineo Collision Detector** runs **query** with the **collision set**.
- 4 **Collision** or **near-miss** stops the custom simulator.

WPF Dialog Box (C#/WPF)

The image shows a WPF dialog box titled "APP Kineo Commands". It features a teal header bar with standard window controls (minimize, maximize, close). The main content area is titled "Point Cloud Generation:" and contains several interactive elements:

- Three text input fields labeled "Select robotic operation:", "Select object flow operation:", and "Select camera:". The "Select camera:" field has an "Add" button to its right.
- A "Camera List:" section containing a table with two columns: "Camera" and "Remove". The table is currently empty.
- A "Take snapshot:" label and a "Run" button.
- A "Status: Ready" label at the bottom left.

The dialog box is styled with a light gray background and rounded corners.

Figure: WPF dialog box for user interaction.

Video demonstration of a Robotic Simulation being stopped in **Tecnomatix Process Simulate**.

- **Integrated a reactive trajectory planner** into **Tecnomatix Process Simulate**.
- **Validated** in a bin picking scenario.
- **Key achievements:** Custom simulation loop, depth data capture and processing, two-stage filtering algorithm, collision detection and response.

- **Limitation** posed by **Tecnomatix snapshot API**.
- **Bottleneck** not important with **physical hardware**.

- 1 **Feed** point cloud to **KineoWorks**.
- 2 Compute **collision-free** path to **target**.
- 3 **Resume motion**.

- **Robot Geometry Filtering:**

- **Current:** Checks each point against every robot geometry ($O(N \times M)$).
- **Future:** Use spatial structure (**Octree**).

- **Static Environment Filtering:**

- **Current:** Compares each new point to every baseline point ($O(N \times M)$).
- **Future:** Store baseline points (**k-d tree, voxel grid**) efficient **nearest-neighbor search** ($O(N \log M)$).

Thank you for your attention!

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KineoWorks Version 7.0 Highlights, 2019.

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Kineo components in robot simulation, 2018.

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Introducing the new Kineo 2D and 3D Nesting software components from Siemens, 2025.

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3D Bin picking: Pick up objects with random overlapping positions, 2025.

 [Kineo Wiki.](#)

Robot's geometries, 2025.

Internal documentation, not publicly accessible. Accessed August 2025.