



Being safe around collaborative and versatile robots in shared spaces

## Protocol

### Test prevention of spatial overreaching for the subject – Human in (shared) control testing with optical measurement system

(ROB-LRM-3)

The purpose of this protocol is to validate the safety skill “limit range of movement” for rehabilitation robots, where a limb of a subject has a connection point with the robot (either free or restrained) and the robot can move that point within a 3D volume. The range of motion is assessed using opto-electronic 3D marker tracking.

Readiness Level	Description
7	Protocol in published over the toolkit, under evaluation, and open for community feedback.

COVER is a community effort and values any honest feedback to our services. Please feel free to express your opinion about this protocol. [The feedback form is only one click away.](#) Thanks for making COVER even better!

Disclaimer: This protocol reflects the current and collectively developed state of the art in the validation of a specific safety skill for a collaborative robot. However, you may have to adapt the described validation procedure to be feasible for your particular application, circumstances and applicable regulations. Neither the COVER project consortium as a whole nor any individual partner of the consortium takes, therefore, any responsibility for the correctness and completeness of the validation procedure described here.



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## CONTENTS

1	Introduction .....	2
1.1	Scope and limitation .....	2
1.2	Definitions and Terms .....	3
2	Concept and Objectives .....	5
2.1	Hazardous Situations .....	5
2.2	Target Behavior and Metrics of the Safety Skill .....	6
3	Conditions .....	6
3.1	System .....	6
3.2	Environment .....	7
4	Setup .....	7
4.1	Sensing devices .....	7
4.2	Method .....	7
5	Procedure .....	9
5.1	Test Plan .....	9
5.2	Preparation .....	9
5.2.1	Test Arrangement .....	9
5.2.2	System Conditions .....	10
5.2.3	Environmental Conditions .....	11
5.3	Test Execution .....	11
5.4	Data Analysis .....	11
5.5	Report .....	12
6	Bibliography .....	13
7	Annexes .....	14
7.1	Annex A – Test form Protocol ROB-LRM-3 .....	14

# 1 Introduction

The purpose of this protocol is to validate the safety skill “limiting a range of movement” (LRM) in 3D of a RACA robot\*<sup>1</sup> by restricting spatial range of motion for both its end-effector as well as any other part of the RACA robot\*, in order to avoid physical damage to the patient connected to this RACA robot\*.

The primary hazardous situation considered here is an over stretching of the subject/user limbs, where the distance between a proximal and a distal joint is too large.

A secondary hazardous situation that can be observed during execution of this protocol, is that parts of a robotic arm type RACA robot\* may collide with parts of the body of the subject. Whether these collisions are within acceptable limits, should be validated using a suitable protocol, e.g. ROB-LIE-1.




Figure 1: Example of ROM\* related RACA robot\* in a rehabilitation application (left) and LRM\*-skill test setup (right)

## 1.1 Scope and limitation

This protocol is specifically limited to the following profile:

<b>Skill</b>	limit range of movement
<b>System</b>	robotic arm (RACA robot*)
<b>Domain</b>	Healthcare
<b>Conditions</b>	3D movement Co-controlled human/robot driven (so for the human it is an active movement)
<b>Measurement Device(s)</b>	Optoelectronic measurement system / motion tracking system

	<p><b>Warning</b></p> <p>This protocol supports users only to validate the effectiveness of the skill listed in the profile above. The skill should be a technical measure for the robot system to mitigate the risk of <u>one</u> potentially hazardous situation as identified in the mandatory risk assessment. Consequently, the risk assessment must be done before using this protocol.</p>
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<sup>1</sup> All terms followed by an asterisk \* are defined in section §Error! Reference source not found.

## 1.2 Definitions and Terms

**Active movement** (source: local to the document)

A movement of parts of a human body, produced by muscles of that human, not by external forces applied to these parts of the human body.

**Direct path** (source: local to the document)

A movement trajectory between two points, where the path is depending on robot path planning (can be linear in space or not if interpolation is done on joint coordinate)

**Emergency stop** (source IEC 80601-2-78)

Manually initiated interruption of operation intended to stop the RACA\* robot to prevent harm

**End-effector** (source: ISO 8373)

Device specifically designed for attachment to the mechanical interface to enable the robot to perform its task. For RACA\* robots this is also described as the (actuated) applied part (IEC 80601-2-78).

**Human Tester** (source: local to the document)

Qualified person who executes the test

**LRM (source: local to document)**

Limit Range of Movement

**Monitored point** (source: local to the document)

Either a point on the robot or defined as a point in space in relation to a specific point on the robot. For example, if the monitored point is to be represented by the subjects' hand, it might be defined as a point in a fixed distance from the arm splint.

**Marker** (source: local to the document)

Active or passive spatial element used by an optoelectronic measurement system to determine a spatial position within a predefined volume.

**Motion tracking system** (source: local to the document)

A system used to detect spatial coordinates of objects in a restricted volume as a function of time

**Optoelectronic measurement system** (source: local to the document)

A system used to detect spatial coordinates of objects in a restricted volume by camera like sensors.

**Overreaching** (source: local to the document)

A movement that results in the Monitored point exceeding the range of motion. Can be harmful to the subject as the movement can exert an excessive strain on joints.

**Passive movement** (source: local to the document)

A movement resulting from an external force working on parts of a human body (e.g. limb), without any voluntary contribution to that motion by that human. So, the passive aspect is viewed from the human perspective.

**Predefined path** (source: local to the document)

A movement trajectory that is specified with more parameters, possibly a set of spatial coordinates.

**Protective stop** (source: IEC 80601-2-78)

interruption of operation automatically initiated by the RACA\* robot, that allows a cessation of motion for basic safety and essential performance purposes, which could allow the programmable electrical medical system (PEMS)/programmable electronic subsystem (PESS) to facilitate a restart

**RACA robot** (source: IEC 80601-2-78:2019 – clause 201.3.212)

Medical robot intended to perform Rehabilitation, Assessment, Compensation and Alleviation robot, comprising an actuated applied part.

**Range of Motion (ROM)** (source: local to the document)

A combination of linear and angular distance that a defined monitored point\* may move in relation to a defined reference point. The monitored point\* can be either a point on the robot, or a point on the body of a human subject defined relatively to a point on the robot. The ROM can be limited to a straight line (one-dimensional ROM), a plane (two-dimensional ROM) or a space (three-dimensional ROM) in any shape. Has to be defined in relation to a reference point.

**Reference point** (source: local to the document)

Either a point on the robot or defined as a point in space in relation to a specific point on the robot. For example, if the reference point shall represent the expected location of the subjects' shoulder joint center, it might be set at a fixed distance from the robot surface. Please note that the reference point has to be a spatial location, which keeps a known position in relation to proximal parts of the robot.

**Rehabilitation robot** (source: local to the document)

RACA robot used in rehabilitation

**S.F.C. / Single fault condition** (source: IEC 60601-1 definition 3.116)

A condition of Medical Electrical equipment in which a single means for reducing a risk is defective or a single abnormal condition is present

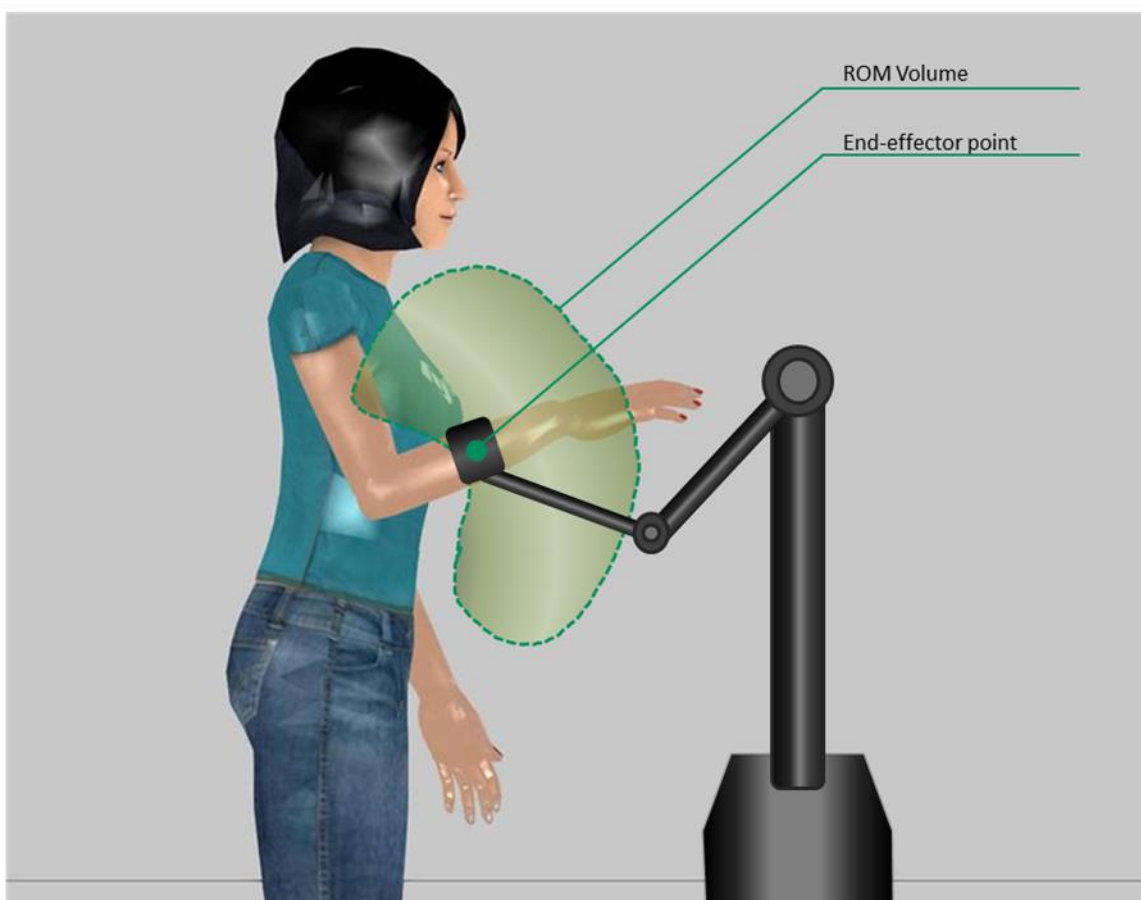
**Target point** (source: local to the document)

Location of a point in a certain volume, relative to the reference point, the robot will be instructed to move the monitored point\* to.

## 2 Concept and Objectives

### 2.1 Hazardous Situations

During rehabilitation, the RACA robot\* will be attached to a patient, in order to mobilize a limb or to assist the use of the impaired limb in daily life. Based on the initiated movement by the patient, the robot will support that movement with a support level that can be set either during installation or by a therapist to suit the required levels during a rehabilitation session. Based on anthropometric properties and physical restraints of the subject as well as the required movement types, the therapist will set some specific boundaries to the movements of the robot arm, in order to make sure the distance between a proximal joint center (e.g. shoulder or hip) and a distal joint center (e.g. wrist or ankle) stays within a certain area.



*Figure 2: Example of an application scenario - subject may also be seated*

The hazardous situations considered in this protocol are:

- over stretching of the subject/user joints/limbs, where the distance between a proximal and a distal joint is too large.
- the robot arm moving through a space where a subject's body parts are located.

## 2.2 Target Behavior and Metrics of the Safety Skill

The target behavior of the skill to be validated is to validate whether the rehabilitation robot keeps the relative displacement between a reference point\* and the monitored point\* within the specified ROM\*.

The movements of a RACA robot\* with shared control are mainly defined by the input of the human and the shared control settings for this robot, i.e. the range of motion restrictions and possible support levels set for the robot controller. The movements carried out can usually be described by a Direct path\* between 2 points or, more likely, a more variable trajectory between 2 points

The shape of the ROM\* for which this test needs to be performed has to be based on the use specifications of the robot, so it represents a proper normal use situation. During defining a representative ROM\* description for the tests it should be considered that:

- The ROM\* can take any shape and does not have to be symmetrical to the reference point\*.
- The shape and size of the volume will have a large impact on the validation results. Therefore a matching description of the ROM\* volume used by the robot should be used during data analysis.

The target metrics are based on physical and measurable quantities. These quantities are the output variables for the validation. The values of the target metrics indicate if the validated skill is effective enough to achieve the specified level of risk reduction. They represent a threshold that the output values of the test must not exceed for considering the test as passed. These values for the ROM\* in a 3D space can be variable during intended use and may be determined by a therapist for the individual user. Therefore, the systems' ability to keep the end-point within the set safe area needs to be validated using different settings for both the endpoint setting and the area where the other parts of the body would be.

It may also be possible that other parts of the RACA robot\* move through spatial areas where other body parts of the patient are. Please note during this test whether parts of the RACA robot\* are kept clear from other body parts of the subject.

For this validation protocol, the target metrics are:

- Does the monitored point\* move outside the defined ROM\*? (YES/NO)
- Does any part of the robot enter an area where it may collide with any part of the body? (YES/NO)

Please report the values of the target metrics for each test using the form in Annex A (§7.1).

## 3 Conditions

In case the conditions under which the hazardous situation may occur can change, the user of this protocol shall develop a test plan containing all their reasonable and relevant combinations. The user must test the applied skill for each combination of this list. Therefore, it is important to know the conditions with the most significant influence on the target metrics. Please report all conditions, represented by values, for each test using the form from Annex A (§7.1).

### 3.1 System

The term system refers to the rehabilitation robot consisting of:

- a robot arm, that is intended to move a body part within a specified workspace (ROM\*)
- a base the robot is mounted on, which is also connected to the support base for the subject

- optionally a cuff or splint attached to the end-effector\* of the robot arm to fixate a single body part.

Apply this protocol for the complete system as it is normally used. Perform the tests both under normal use conditions as well as relevant S.F.C.\* which may influence the safety skill, like:

- When an emergency stop\* or a protective stop\* is initiated.
- A S.F.C.\* where an Invalid sensor data that may influence the controller behavior or the applied risk reduction measure (RRM)
- A S.F.C.\* where failure of an actuator that may influence the behavior of the controller or the RRM

During the risk assessment special attention should be paid to properly identify relevant S.F.C.'s\*.

- This protocol can also be applied with an applied part connected to the end-effector of the robot, e.g. a splint, which, in normal use, is connected to a body part of the subject with the intention to move that body part, as long as the movements of this subsystem are predictable in relation to the motions of the robot arm.
- This protocol does not consider a robot arm with other kinds of sub-systems where the relation between the robot arm and the subject is not fixed.

### 3.2 Environment

Environmental conditions may influence the safety skill, depending on the implementation. When applicable the validation tests should be performed under various environmental conditions, that are considered normal use conditions and that may have an influence on the performance of the safety skill. Examples of this could be:

- Inclination angle of the total robot (e.g. when the robot arm is mounted on a mobile robot)
- Externally induced motions/accelerations of the total combination of RACA robot\* and the human (e.g. when both the RACA\* robot and the human are on the same moving platform e.g. wheelchair), since these may have a significant influence on the inertia of the entire system.

## 4 Setup

### 4.1 Sensing devices

For the validation of this safety skill, a motion tracking system is used. With this system, it is possible to measure spatial coordinates of multiple markers over time.

The required accuracy of the motion tracking is determined by the required accuracy of the measurements that is derived from the risk assessment. As a guideline: An acceptable accuracy can be about 10 mm, but other values can be acceptable if based on a proper risk assessment.

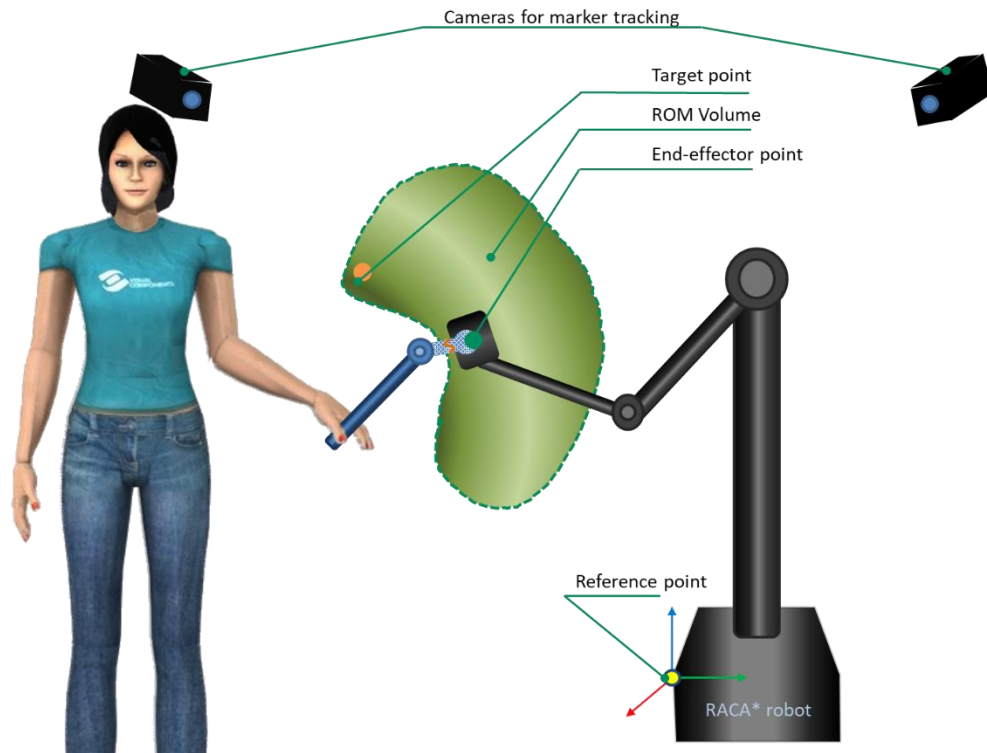
The acquisition rate used by the motion tracking system should be at least a factor 10 higher than the highest expected frequency component of principal motion of the robot during the test. For normal human movements an acquisition rate of 100 fps will usually suffice.

### 4.2 Method

The RACA robot\* must be positioned in such a manner that all robot movements can be properly detected with the measurement system (see Figure 3).



Markers will be placed on the RACA robot\* at the monitored point\* and the reference point\* or, should this not be feasible, markers should be placed at locations on the RACA robot\* from which, during any movement of this robot, the location of the monitored point\* and the reference point\* can be reconstructed



*Figure 3: General structure of the test arrangement with a (3D) motion tracking system and a Human Tester\**

Since the robot arm uses shared control, when safely possible, the movements can be applied by a Human Tester\*.

However, a proper risk analysis should be performed on the entire test setup before the decision can be made that the test movements can be performed by a Human Tester\*. Main criteria will be:

- The Human Tester\* should be able to remain out of reach of the robot arm during the test
- During the execution of the test, the Human Tester\* should hold a 3-stage enabling switch, which should be connected to the RACA robot\* as an emergency stop so the robot can be stopped immediately when a dangerous situation would arise.

After data acquisition the data has to be processed to determine whether during the test the monitored point\* was located outside the predefined ROM\* volume. The measured location data may be filtered to remove high frequency measurement inaccuracies, but this filter may not use a cut-off frequency lower than 5 times the highest expected frequency component of the principal motion of the robot during the test. For normal human movements a cut-off frequency for filtering the marker data of about 10Hz., using a zero lag filter, will usually suffice.

The shape and size of the volume will have a large impact on the validation results. Therefore, a clear definition of the ROM\* volume used by the RACA robot\* during the tests should be available and used during data analysis.

## 5 Procedure

### 5.1 Test Plan

The test plan is a summary of all situations, which the risk assessment identified as hazardous due to moving the monitored point\* outside a predefined ROM\* volume, including all combinations of applicable conditions. Therefore, the test plan provides a detailed summary of the necessary tests to validate the skill for the considered application.

The test plan should at least cover the motion paths identified by the risk assessment as potentially hazardous. This means that by moving the arm of the RACA robot\*, it should be provoked to move the monitored point\* into or through a spatial area that is outside of the predefined ROM\* volume. The purpose of the test is to validate whether the RACA\* robot exceeds this volume or not.

According to Chapter 3, the protocol must consider the following conditions:

- For defining the motion trajectories, consider that motions should at least cover
  - Trajectories of the monitored point\* to locations outside the specified ROM\*
  - Trajectories of the monitored point\* to either locations inside or outside of the specified ROM\* volume, where a part of the direct path\* could cross an area outside of the specified ROM\* volume, should this be the shortest route
  - Trajectories where parts of the RACA robot\* may collide with parts of the subject's body during normal operation.
- Tests must be run as much as possible at maximum speed with specified maximum allowed payload for the RACA\* robot and under otherwise normal use conditions. This load should be positioned in such a way that its center of mass would be close to the end-effector of the RACA\* robot, unless another location is more conform to normal use conditions.
- If ROM\* settings can be modified by the user, these tests have to be performed with a selection of different ROM\* settings, that are a proper representation of the range of different settings.
- If applicable, these tests also have to be performed under system inclinations that may affect the safety skill.
- Repeat the tests mentioned above also under S.F.C.'s\* that may have an effect on the safety skill.

### 5.2 Preparation

Before executing a particular test from the test plan, it is necessary to prepare the setup and the conditions properly. The following sections give instructions to prepare each part of the setup and all conditions with a significant influence on the target metrics.

#### 5.2.1 Test Arrangement

For preparing the test arrangement:

- Make sure that the environmental conditions such as lighting are appropriate for the measurement technique you are using.
- Calibrate the motion tracking system as described in its user manual or check existing calibration where applicable. Make sure the calibration accuracy meets the required accuracy.
- The RACA robot\* is positioned within the capture range of the motion tracking (e.g. 3D electro-optical measurement) system.

The reference point\* and monitored point\* as defined by target behavior (section §Error! Reference source not found.) need to be tracked by the (3D) motion tracking system. The tracking of the reference point\* can be achieved by one of the following

- by placing a marker on a stand so that it is positioned in the reference point\*;
- by defining points in the environment, either on the RACA robot\* or in the room, from which the location of the reference point can be accurately reconstructed;
- by reconstructing the reference point from marker points placed on the RACA robot\* (this has to be done if the reference point can move due to movements of the RACA robot\*).

Optionally, for the detection of the possibility of undesired collisions with other body parts by any part of the robot:

- Position an object representing the relevant artificial body parts so potential, undesired contact between the RACA robot\* and a human can be easily detected. Make sure these objects do not obstruct visibility of relevant optical markers.

The tracking of the monitored point\* can be achieved in a number of ways, i.e.:

- by attaching a marker directly on the RACA robot\*, if the monitored point\* is defined as a point on the RACA robot\*.
- Or, if the monitored point\* is not defined as a point on the RACA robot\*, either by attaching a marker on a clamp or dummy limb segment attached to the RACA robot\*, or by defining points on the robot arm from which the location of the monitored point\* can be accurately reconstructed.

### 5.2.2 System Conditions

Please report the system composition for each single test using the form in Annex A.

- If possible tests should be performed with the device in “passive”/”hand guiding” mode, where the RACA robot\* only supports its own inertia.
  - Perform this test both without added load as well as with the maximum normal use payload which should be positioned at the end-effector\* (unless another location is more usual during normal use)
- Next tests should be performed under normal use condition, with the RACA robots’\* typical normal use “shared control” settings, e.g. support level for compensation for weight of the relevant body parts of a user
  - The tests should be performed with the maximum normal use payload that should be positioned at the end-effector\* (unless another location is more usual during normal use)
  - The tests should be performed at the maximum safe velocity as set within the RACA robot\* safety settings. If that is not specified, the tests should be performed at the maximum velocity that the robot can achieve
- In both modes also test the RACA robot\* under the S.F.C.\*(’s) identified in the risk analysis that may influence the safety skill and perform these test under these S.F.C.\*(’s).
- In case of an emergency stop\* or a protective stop, a system may behave differently. When a robot may actively move the monitored point\* back to a predefined location, and if it might be possible that the monitored point\* moves through an area that is not allowed by the ROM area setting, this situation should be validated as well.

- In case during movements, if other parts of the robot may also move through an area that is potentially hazardous, these situations should be noted. The safety of these impacts should be validated, e.g. via a suitable protocol, which validates a limited interaction energy (e.g. ROB-LIE-1).

### 5.2.3 Environmental Conditions

The validation tests should be performed under conditions similar to the normal use conditions.

However, if the risk analysis indicates that environmental conditions could have an effect on the safety skill, the test should be performed under these relevant environmental conditions, or simulated versions of these conditions as well.

## 5.3 Test Execution

Activate the measurement equipment

- Make sure the measurement equipment is calibrated (if calibration is required)
- Make sure data logging is ready for recording on all recording devices.
- Make sure all sensors are attached properly, especially when a previous execution of the protocol resulted in a collision or sudden stop of the RACA robot\*

Apply the following test procedure for each specified test case separately.

- Move the monitored point\* to a predefined starting position.
- Make sure the monitored point\* of the RACA robot\* is stationary for at least 1 second.
- Move the monitored point\* either via a direct or an indirect path or a target point, which is either inside or outside the predefined ROM.
- After a successful motion, make sure that the monitored point\* on the RACA robot\* is stationary for at least 1 second before continuing.

Repeat this with various start and target point combinations. Make sure that during these tests, attempts are made to move the RACA robot\* in areas where it isn't allowed to move.

Repeat these tests under the conditions mentioned in §5.2.3 and §5.2.2 and those identified during the risk analysis that may affect the safety skill.

## 5.4 Data Analysis

To determine whether the system passed this test:

- During data analysis the 3D locations of the markers can be used to calculate the 3D positions and orientations of the robot segments and the "virtual" subject segment, which will provide the required information about the imposed spatial ROM\*.
- Results from the data analysis will result in a pass or no-pass. A pass will be when the results of the validation tests show that at no instant the monitored point\* moved outside of the ROM\* volume. During the data analysis the ROM\* limitation settings should be known.
- A no-pass will occur when the monitored point\* moves outside the ROM\* volume, taking the accuracy of the measurement system into account.
- Very short and limited "overshoots" in movement may be allowable. However, these acceptability criteria should be specified and properly documented by the manufacturer. These criteria should consist of a maximum overshoot magnitude, combined with a maximum duration of the overshoot as well as a supporting rationale. As a guideline an overshoot with a magnitude of 10mm and a duration of 1 second could be acceptable.

## 5.5 Report

The following data needs to be present in the documentation:

- Description of the support settings of the RACA robot\*
- Descriptions of the various test sequences executed
- Start/end point + direct path / prescribed path
- Robot speed under which the tests were performed
- Load applied to the RACA robot\*
- System conditions (e.g. normal use, S.F.C.\*, or even functional stop/reset, emergency stop)
- Pass or no pass result derived from analyzed data (yes/no)
  - Within ROM\*:  
Provide logging/tracking information information about the motion path used, to determine the RACA robot\* hasn't moved outside of the allowed ROM\*.

## 6 Bibliography

EN IEC 60601-1:2006

EN IEC 80601-2-78:2020

## 7 Annexes

### 7.1 Annex A – Test form Protocol ROB-LRM-3

*Avoid single axis rotation beyond pre-set limits for individual PATIENT movement*

Test form - Protocol ROB-LRM-3			
Test date		ID of tester:	
Sequence ID (Seq#)		Hazard ID	
Description of RACA* robot under validation			
Measurement system used:			
Measurement system Calibration date:		Measurement accuracy:	
Condition	Normal/S.F.C.*	Description (S.F.C.*):	
		Functional stop?	
		Emergency stop?	
		Max velocity (m/s)	
		Applied load (kg)	
		Inclination angle (°)	
		Total system acc (m/s <sup>2</sup> )	
Reference point location* (relative to RACA robot* position)			
X			
Y			
Z			
Support level settings of the RACA robot*			
Support level:			
ROM description:			
Location of ROM description file / description of ROM limits:			

Test ID (Seq#-id)	Start point	End point		Stayed in ROM* (Y/N)	Collisions (Y/N)	Pass? (Y/N)
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					



<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					
<b>Seq#-ID</b>	<b>Start</b>	<b>End</b>		<b>In ROM*</b>	<b>collisions</b>	<b>Pass?</b>
	Motion path datafile:					

**Final Information about test**

<b>Date of testing</b>	
<b>Name of tester</b>	
<b>Overall conclusion</b>	
<b>Signature</b>	