Self-Organizing-Map Program for Analyzing Multivariate Data

SOM_VIS is a computer program for analysis and display of multidimensional sets of Earth-image data typified by the data acquired by the Multi-angle Imaging Spectro-Radiometer (MISR (a spaceborne instrument)). In SOM_VIS, an enhanced self-organizing-map (SOM) algorithm is first used to project a multidimensional set of data into a nonuniform three-dimensional lattice structure. The lattice structure is mapped to a color space to obtain a color map for an image. The Voronoi cell-refinement algorithm is used to map the SOM lattice structure to various levels of color resolution. The final result is a false-color image in which similar colors represent similar characteristics across all its data dimensions. SOM_VIS provides a control panel for selection of a subset of suitably preprocessed MISR radiance data, and a control panel for choosing parameters to run SOM training. SOM_VIS also includes a component for displaying the false-color SOM image, a color map for the trained SOM lattice, a plot showing an original input vector in 36 dimensions of a selected pixel from the SOM image, the SOM vector that represents the input vector, and the Euclidean distance between the two images.

This program was developed by Hue-Hsia (Jannivine) Yeh, Cheryl B. Brown, and Frank J. Jeng of Lockheed Martin Corp. for NASA’s Jet Propulsion Laboratory. Further information is contained in a TSP (see page I). This software is available for commercial licensing. Please contact Karina Edmonds of Johnson Technology Transfer Office at (281) 483-3809. For further information, contact the Johnson Technology Transfer Office at (281) 483-3809. MSC-23506

Control Software for a High-Performance Telerobot

A computer program for controlling a high-performance, force-reflecting telerobot has been developed. The goal in designing a telerobot-control system is to make the velocity of the slave match the master velocity, and the environmental force on the master match the force on the slave. Instability can arise from even small delays in propagation of signals between master and slave units. The present software, based on an impedance-shaping algorithm, ensures stability even in the presence of long delays. It implements a real-time algorithm that processes position and force measurements from the master and slave and represents the master/slave communication link as a transmission line. The algorithm also uses the history of the control force and the slave motion to estimate the impedance of the environment. The estimate of the impedance of the environment is used to shape the controlled slave impedance to match the transmission-line impedance. The estimate of the environmental impedance is used to match the master and transmission-line impedances and to estimate the slave/environment force in order to present that force immediately to the operator via the master unit.

This program was written by P. Peggy Li, Joseph C. Jacob, Gary L. Block, and Amy J. Braverman of Caltech for NASA’s Glenn Research Center, Commercial Technology Office, Attn: Steve Fedor, Mail Stop 4–8, 21000 Brookpark Road, Cleveland, Ohio 44135. Refer to LEW-17465-1.