US 20220307225A1

(19) United States
(12) Patent Application Publication
Taylor et al.
(10) Pub. No.: US 2022/0307225 A1
(43) Pub. Date: Sep. 29, 2022

(54) SYSTEMS AND METHODS FOR MITIGATING COLLISIONS BETWEEN A MINING MACHINE AND AN EXCLUSIONARY ZONE

(71) Applicant: **Joy Global Surface Mining Inc**, Milwaukee, WI (US)

(72) Inventors: **Wesley P. Taylor**, Glendale, WI (US); **Megan M. Scheppa**, Brookfield, WI (US)

(21) Appl. No.: **17/216,218**

(22) Filed: **Mar. 29, 2021**

Publication Classification

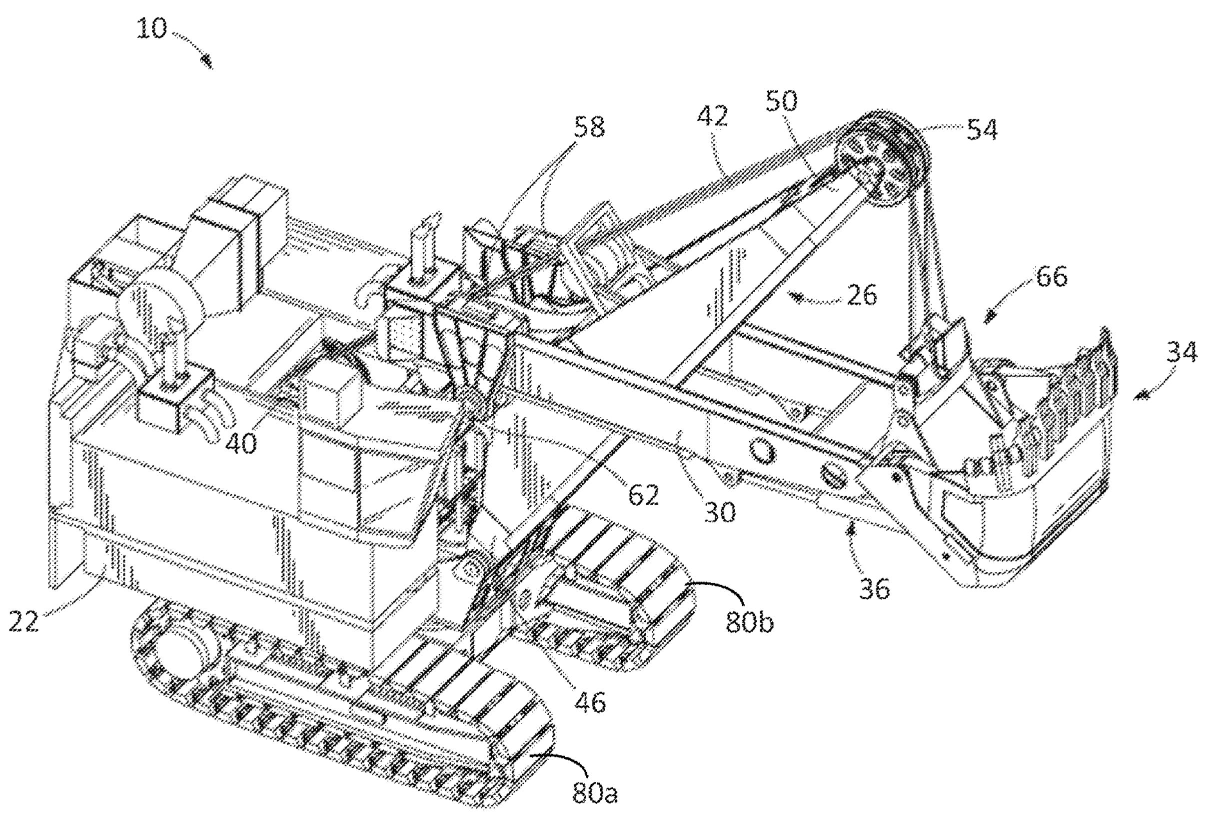
(51) **Int. Cl.**

E02F 9/20	(2006.01)
E02F 3/43	(2006.01)
E02F 3/46	(2006.01)

(52) **U.S. Cl.**
CPC ***E02F 9/2033*** (2013.01); ***E02F 3/435*** (2013.01); ***E02F 3/46*** (2013.01)

(57) **ABSTRACT**

Embodiments described herein provide systems and methods for preventing and mitigating collisions between components of an industrial machine. The industrial machine includes an electronic controller, having an electronic processor and a memory, that is configured to generate a virtual model of an exclusionary zone located on or near the industrial machine. The electronic controller is further configured to receive dipper position data indicative of a position of the dipper and determine a distance between the dipper the exclusionary zone based on the dipper position data. The electronic controller is further configured to set a motion command limit for a dipper motion based on the distance, the dipper motion being selected from a group of a swing motion, a crowd motion, and a hoist motion and control the dipper motion according to a dipper motion command limited by the motion command limit.



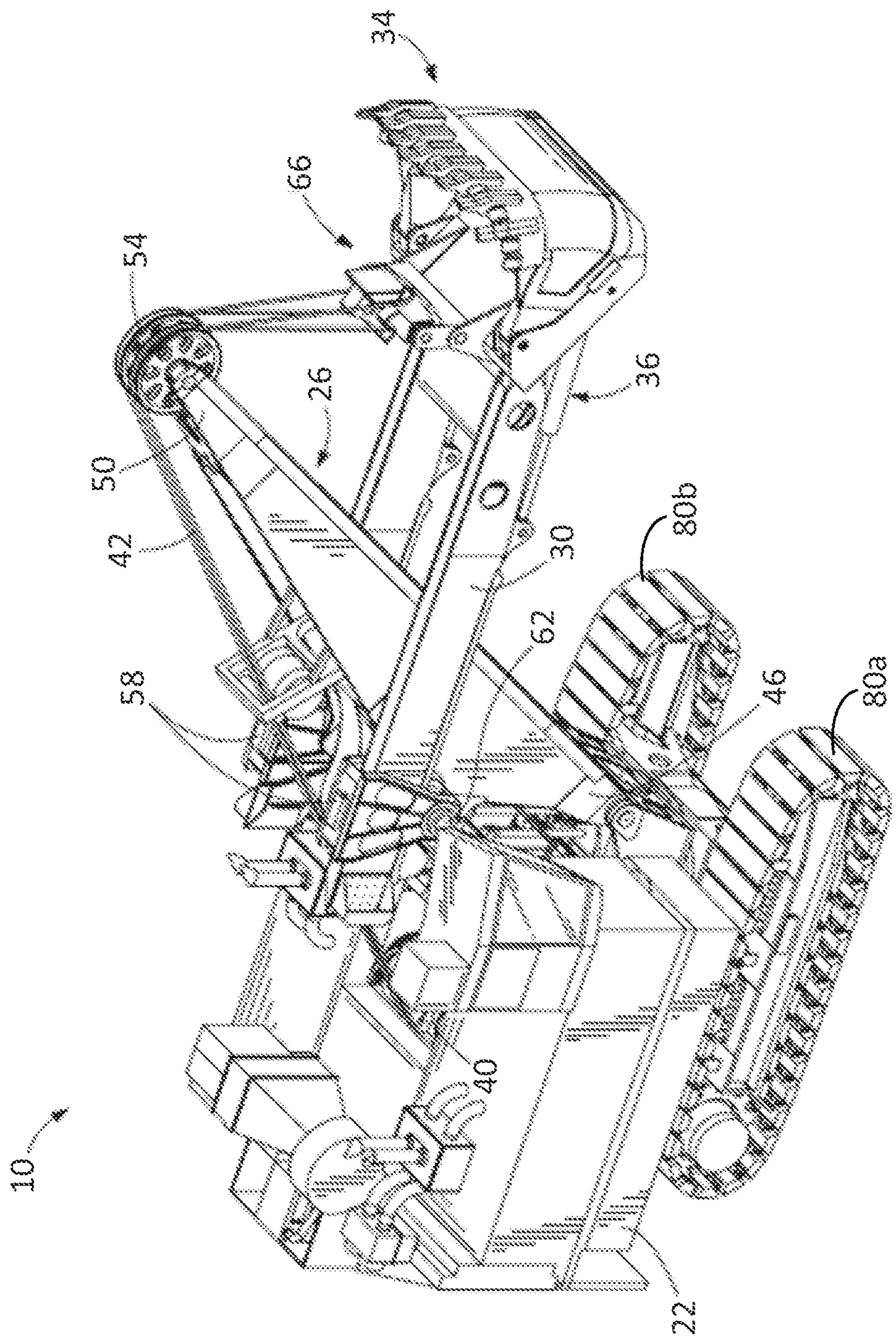


FIG. 1

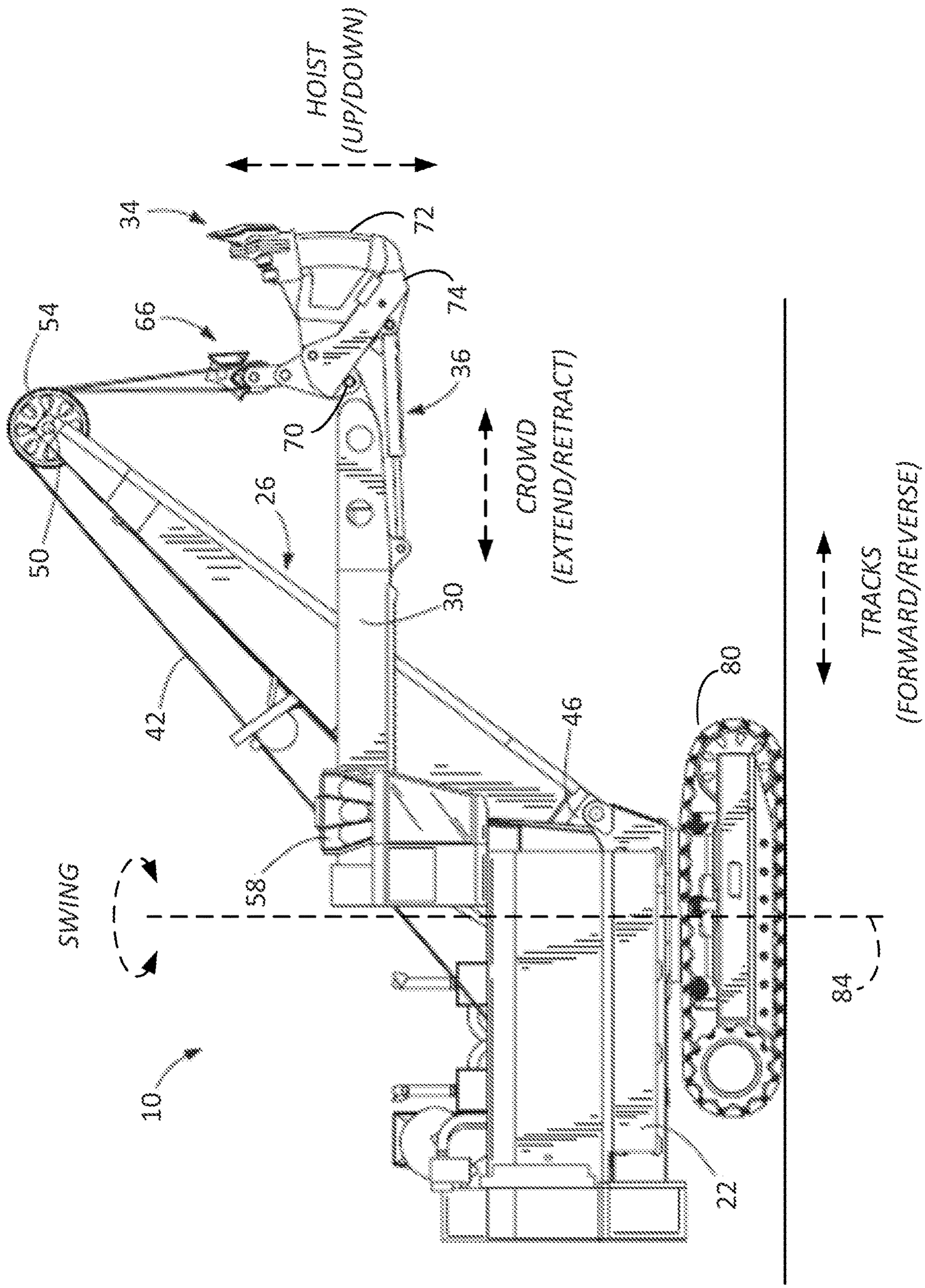

HOIST
(UP/DOWN)
CROWD
(EXTEND/RETRACT)
TRACKS
(FORWARD/REVERSE)
SWING
10
22
26
30
34
36
42
46
50
54
58
66
70
72
74
80
84

FIG. 2

FIG. 3

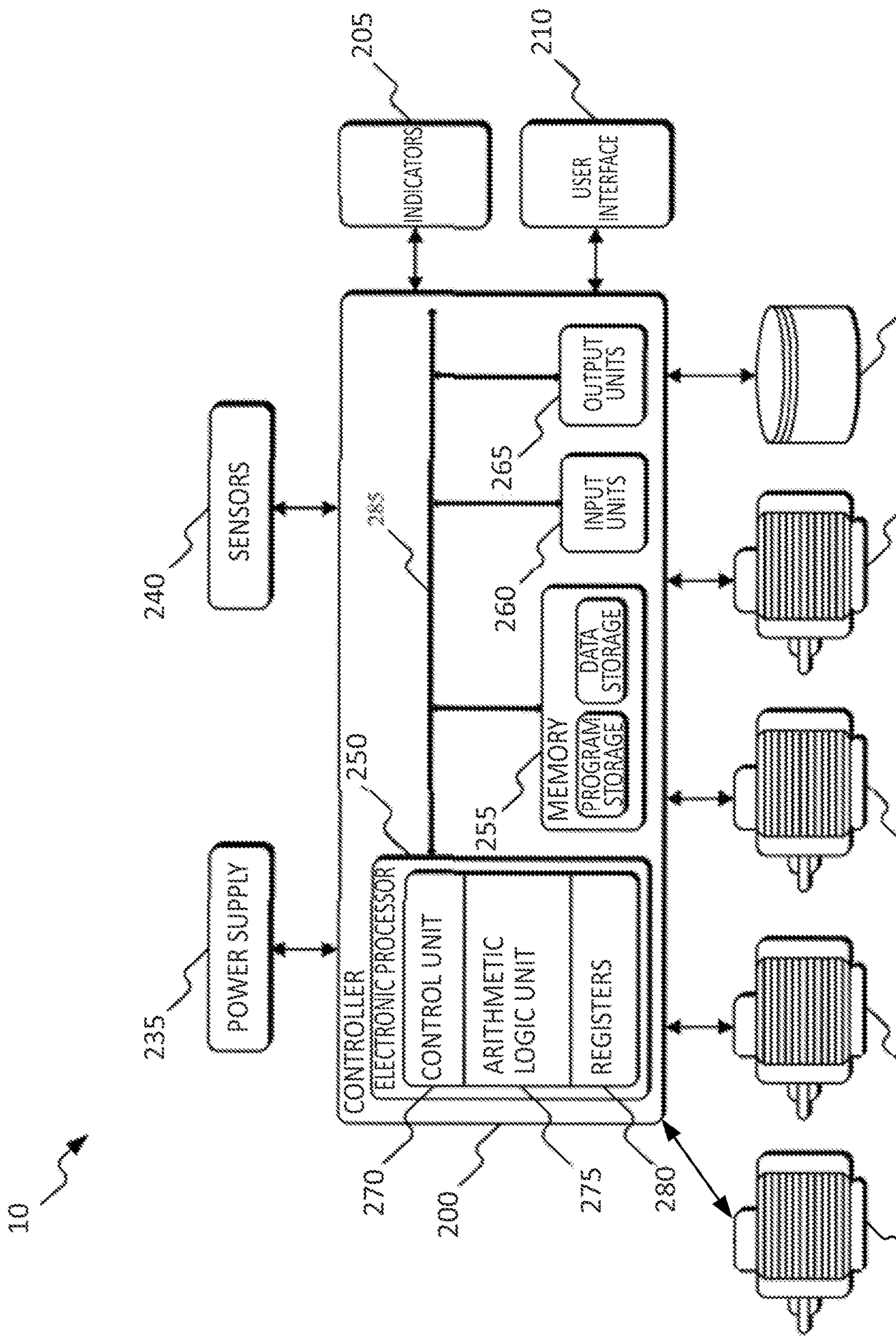

10
235
POWER SUPPLY
240
SENSORS
205
INDICATORS
210
USER INTERFACE
CONTROLLER
ELECTRONIC PROCESSOR
CONTROL UNIT
ARITHMETIC LOGIC UNIT
REGISTERS
250
255
MEMORY
PROGRAM STORAGE
DATA STORAGE
260
INPUT UNITS
265
OUTPUT UNITS
285
270
200
275
280
230
225
220
215
227

FIG. 3A

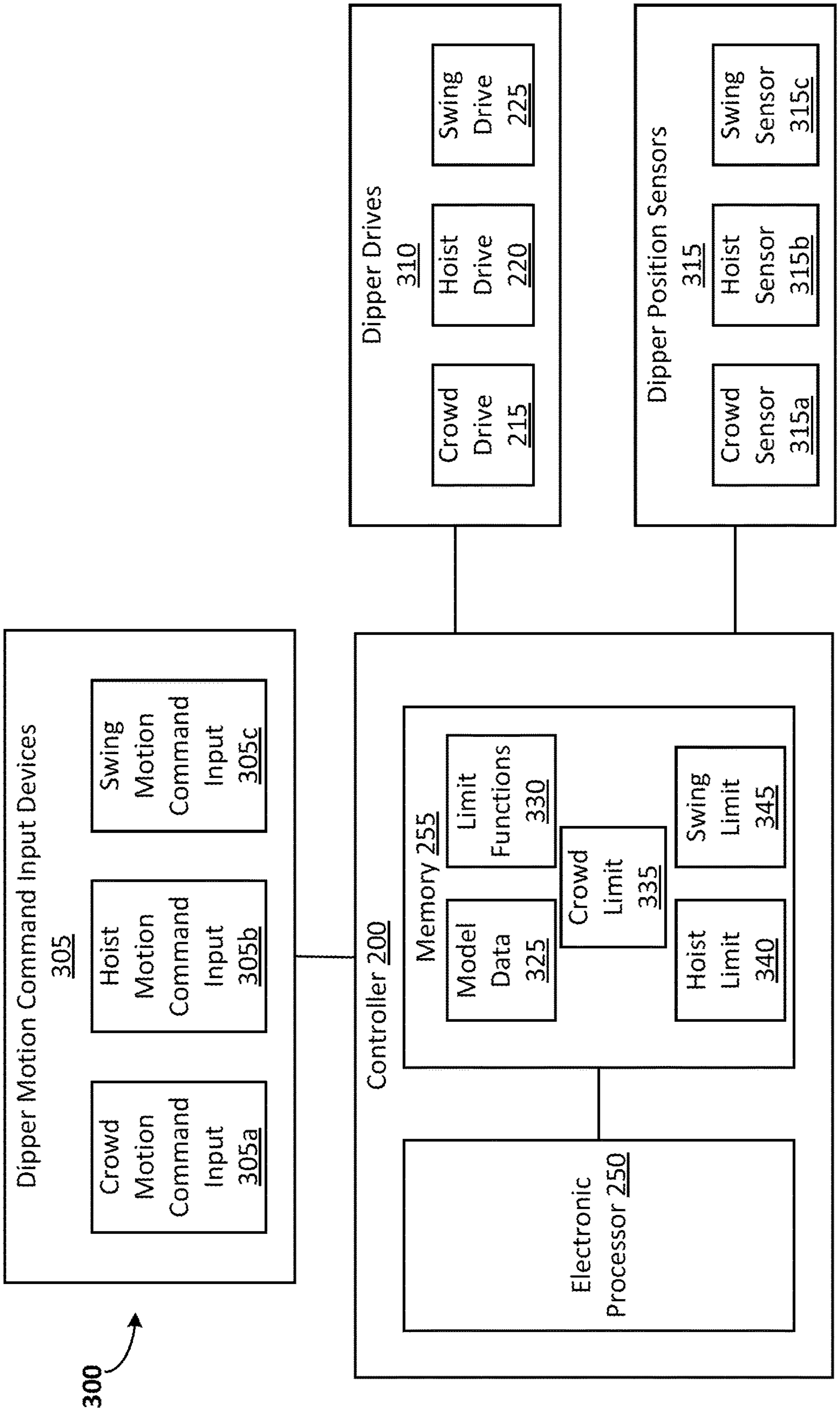

300
Dipper Motion Command Input Devices 305
Crowd Motion Command Input 305a
Hoist Motion Command Input 305b
Swing Motion Command Input 305c
Controller 200
Memory 255
Model Data 325
Limit Functions 330
Crowd Limit 335
Hoist Limit 340
Swing Limit 345
Electronic Processor 250
Dipper Drives 310
Crowd Drive 215
Hoist Drive 220
Swing Drive 225
Dipper Position Sensors 315
Crowd Sensor 315a
Hoist Sensor 315b
Swing Sensor 315c

FIG. 3B

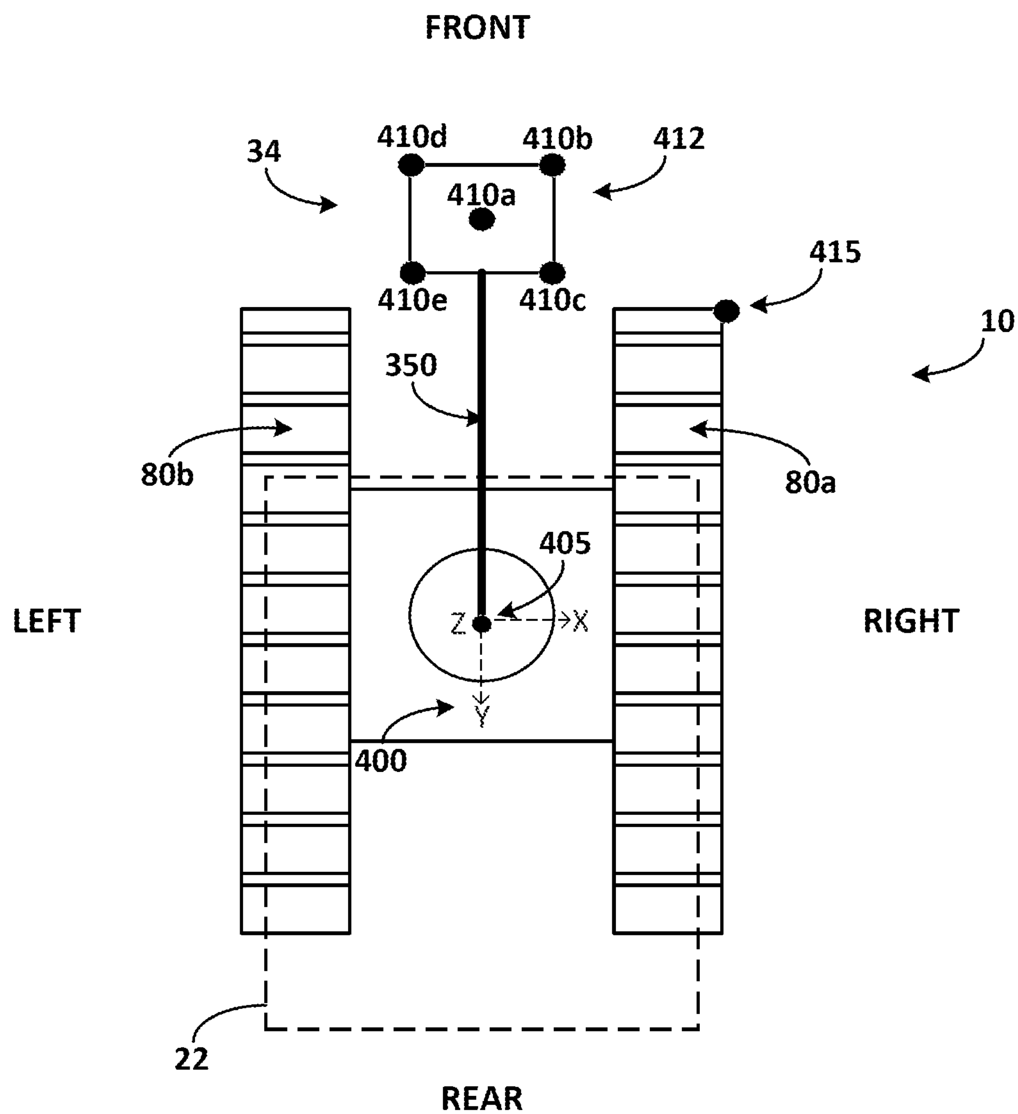

FRONT
34
410d
410b
412
410a
415
410e
410c
10
350
80b
80a
405
LEFT
Z
X
RIGHT
Y
400
22
REAR

FIG. 4

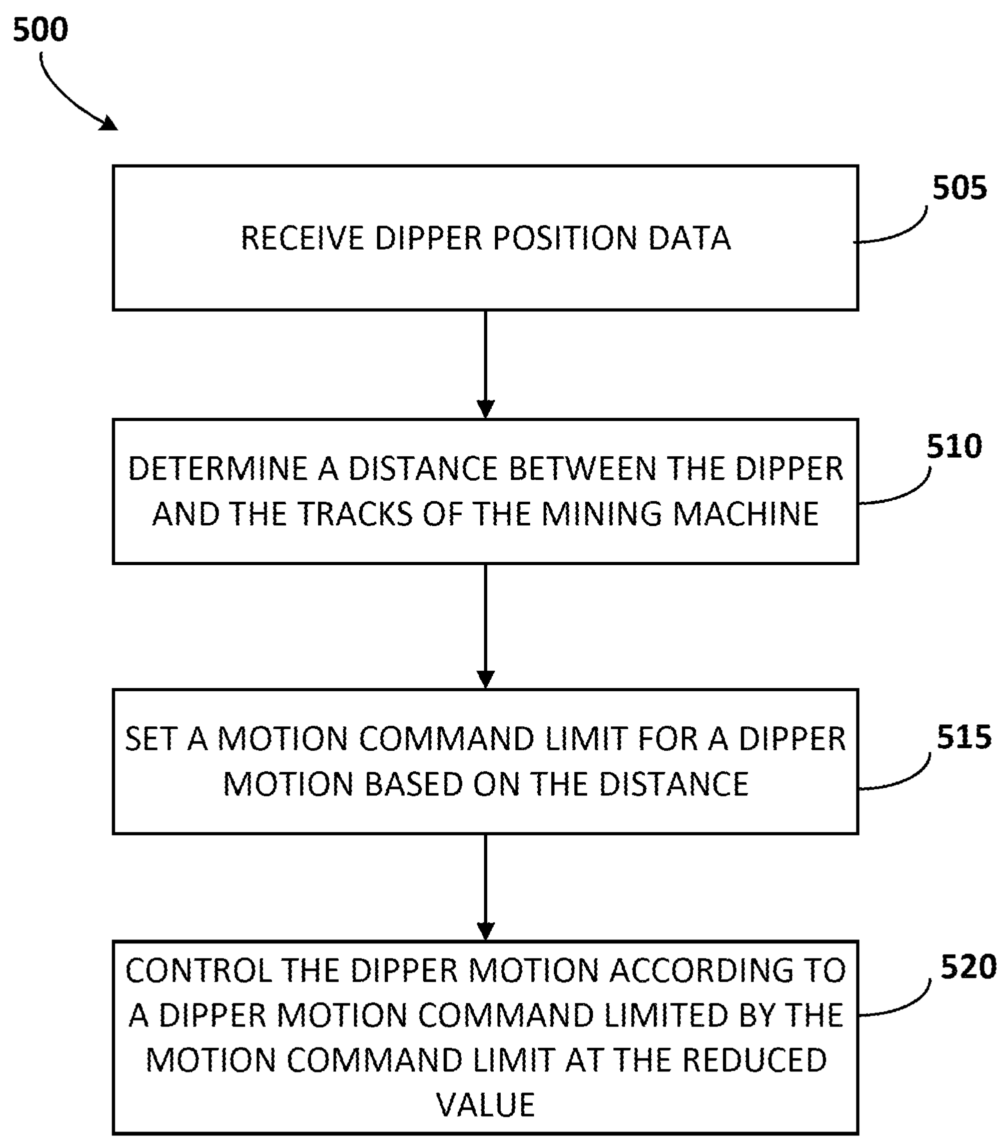

500
RECEIVE DIPPER POSITION DATA
505
DETERMINE A DISTANCE BETWEEN THE DIPPER AND THE TRACKS OF THE MINING MACHINE
510
SET A MOTION COMMAND LIMIT FOR A DIPPER MOTION BASED ON THE DISTANCE
515
CONTROL THE DIPPER MOTION ACCORDING TO A DIPPER MOTION COMMAND LIMITED BY THE MOTION COMMAND LIMIT AT THE REDUCED VALUE
520

FIG. 5

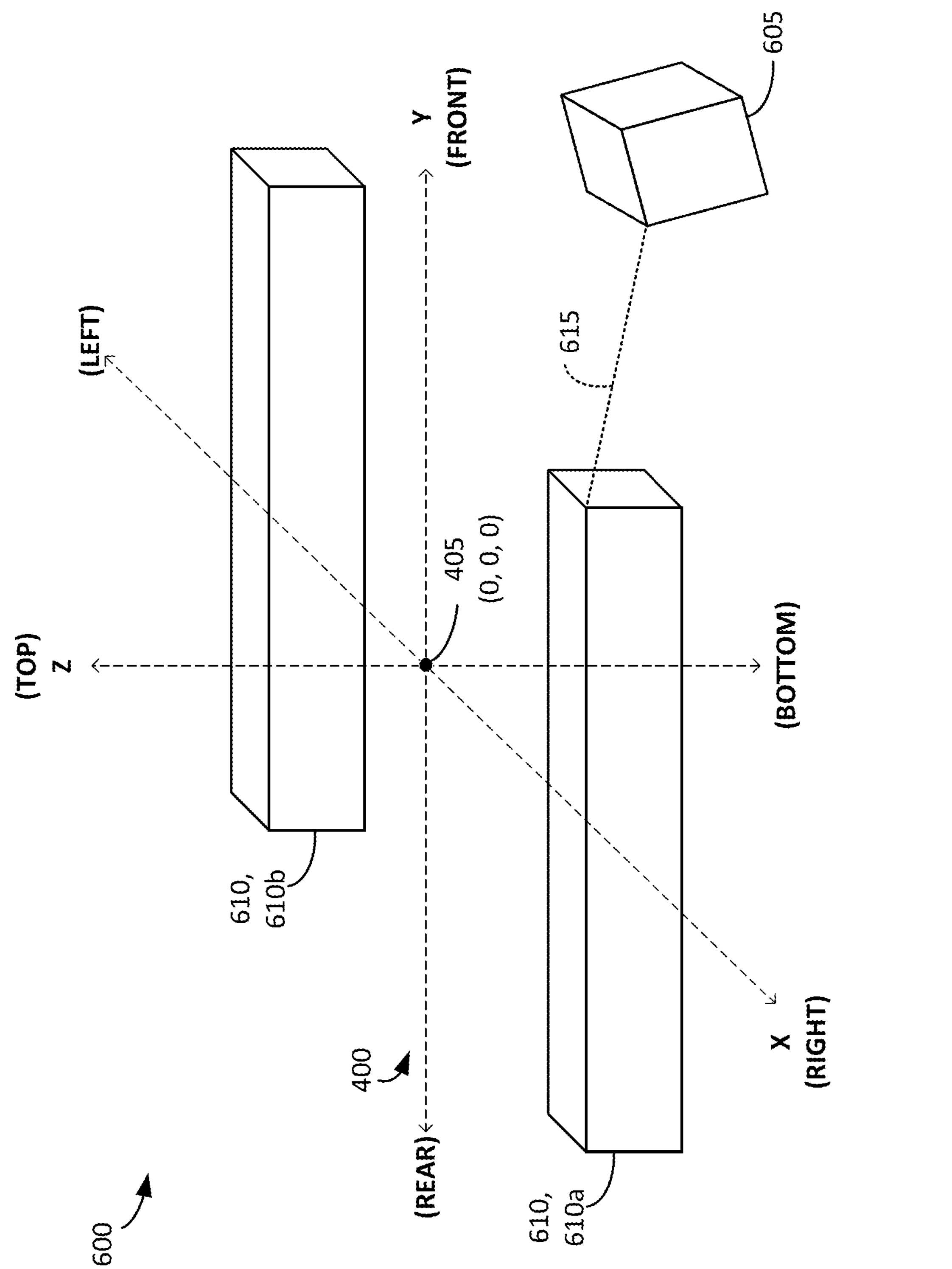

600
400
(TOP)
Z
(BOTTOM)
(LEFT)
X
(RIGHT)
Y
(FRONT)
(REAR)
405
(0, 0, 0)
605
615
610,
610a
610,
610b

FIG. 6

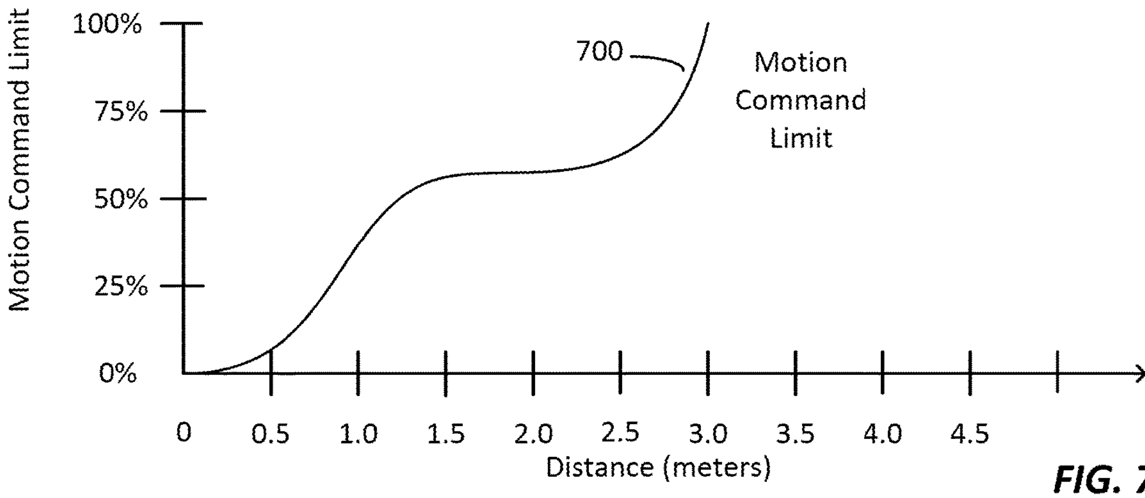


FIG. 7A

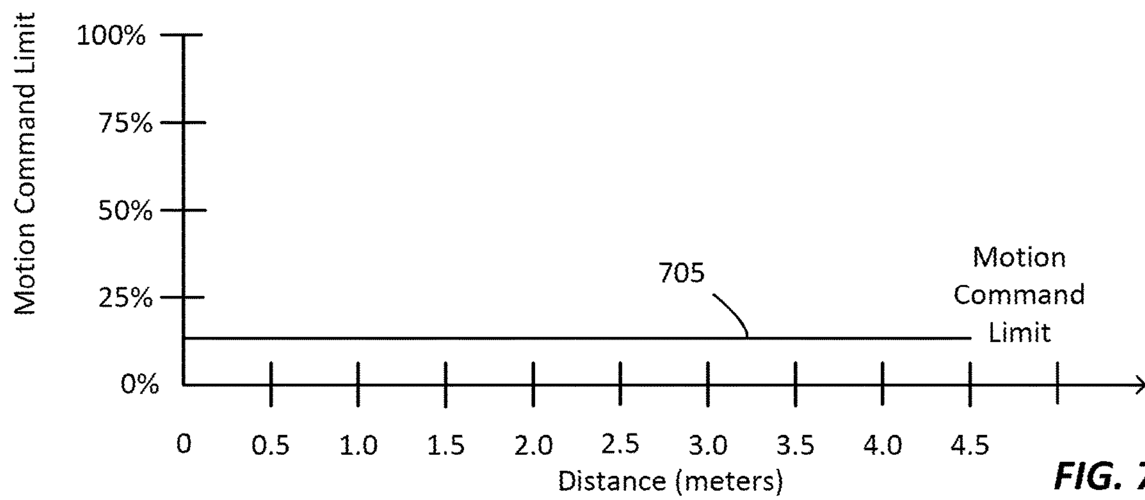


FIG. 7B

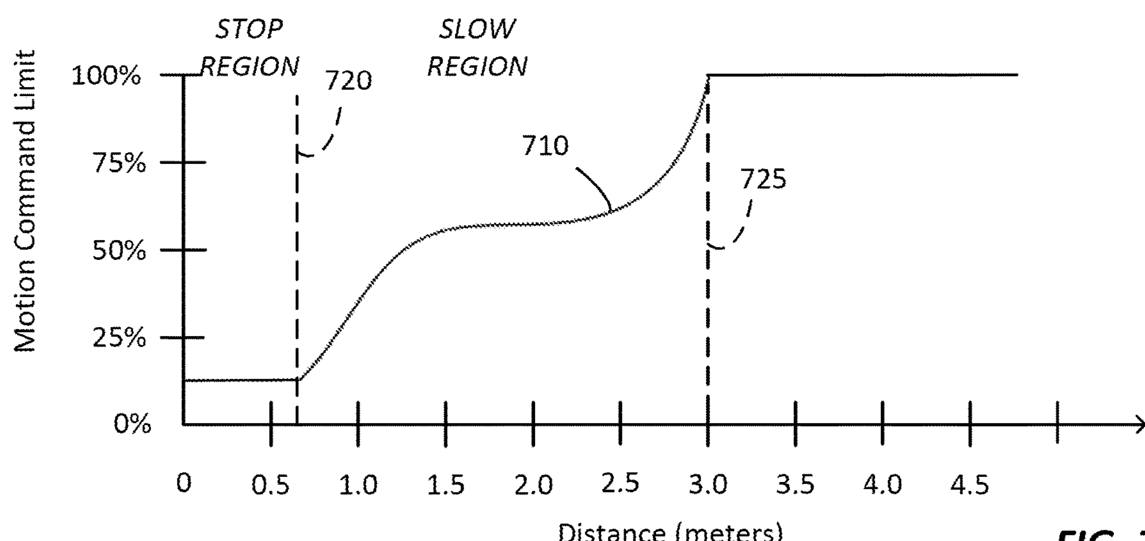


FIG. 7C

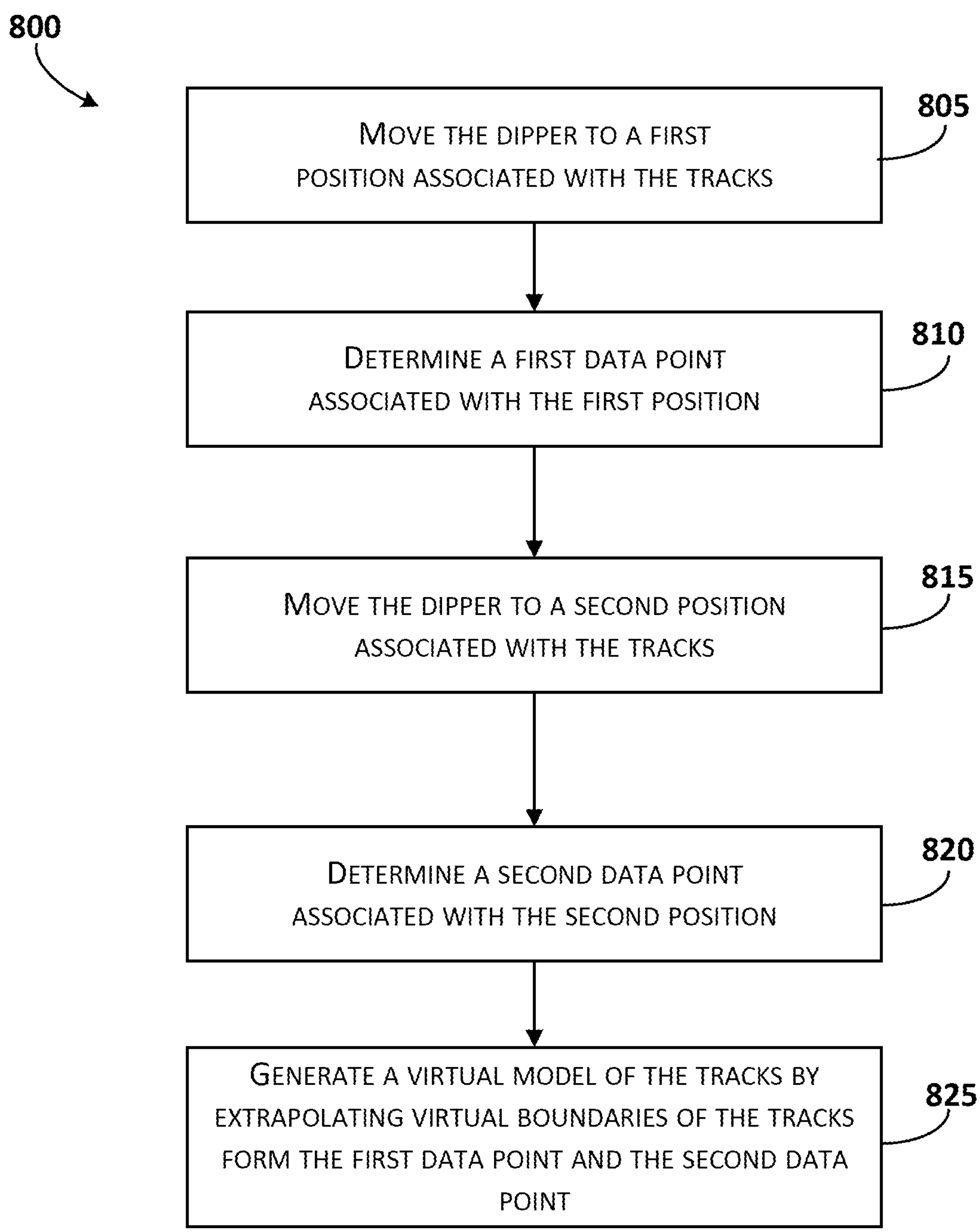

800
Move the dipper to a first position associated with the tracks
805
Determine a first data point associated with the first position
810
Move the dipper to a second position associated with the tracks
815
Determine a second data point associated with the second position
820
Generate a virtual model of the tracks by extrapolating virtual boundaries of the tracks form the first data point and the second data point
825

FIG. 8

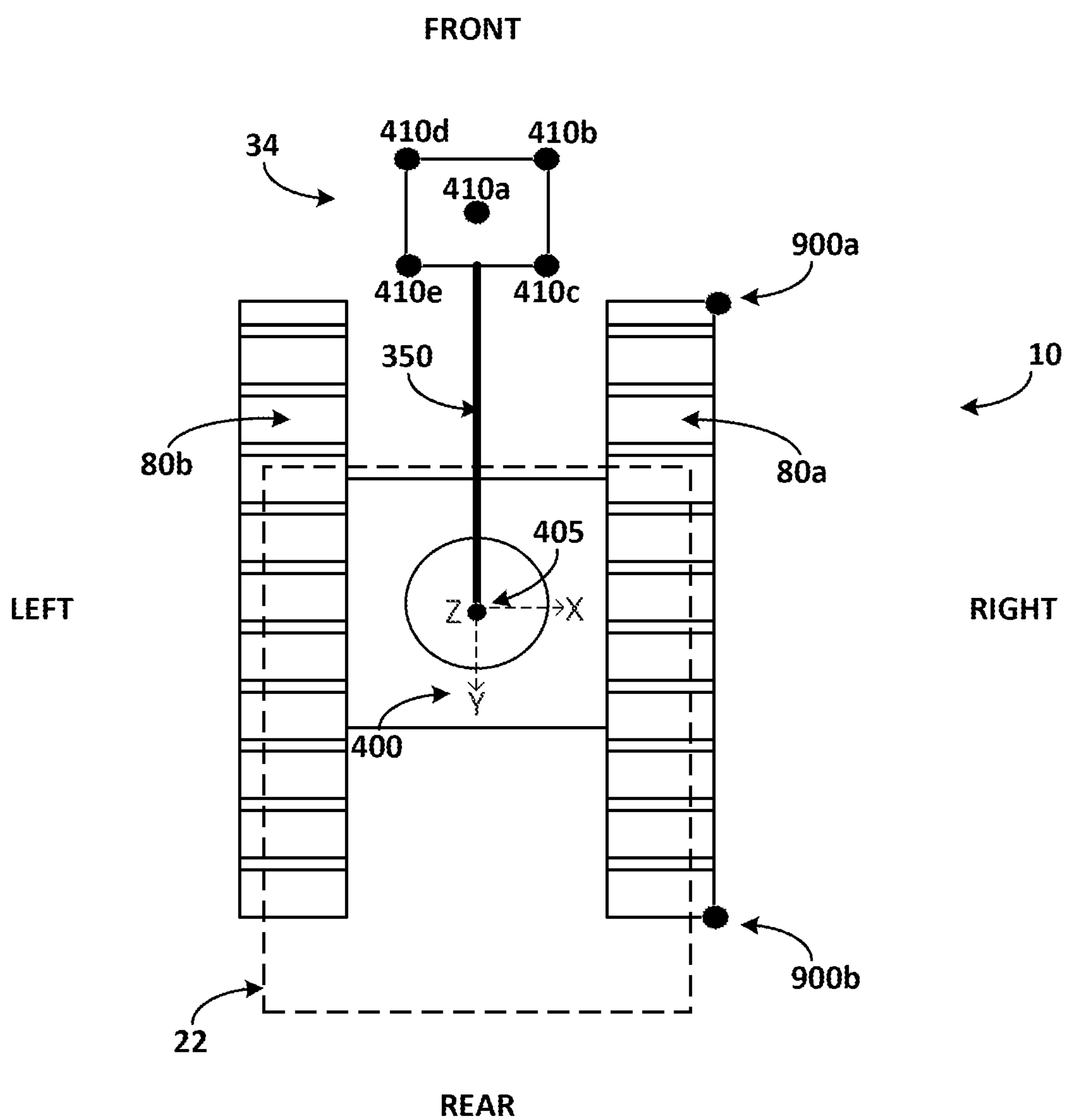

FRONT
34
410d
410b
410a
900a
410e
410c
350
10
80b
80a
405
LEFT
Z
X
RIGHT
Y
400
900b
22
REAR

FIG. 9

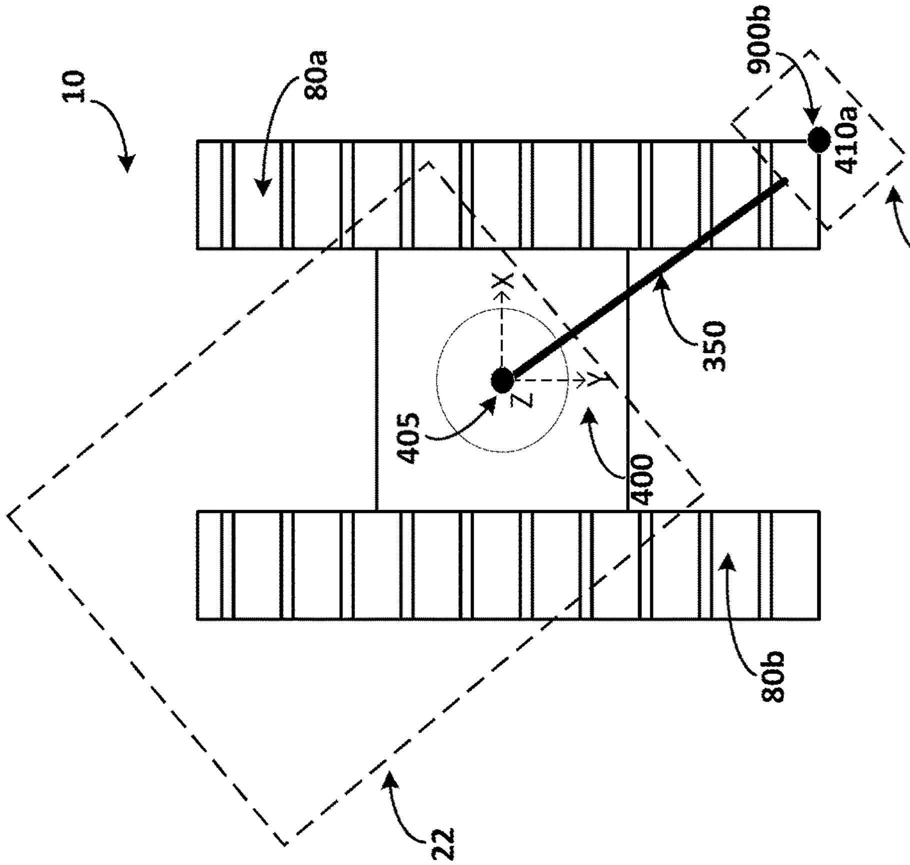


FIG. 10B

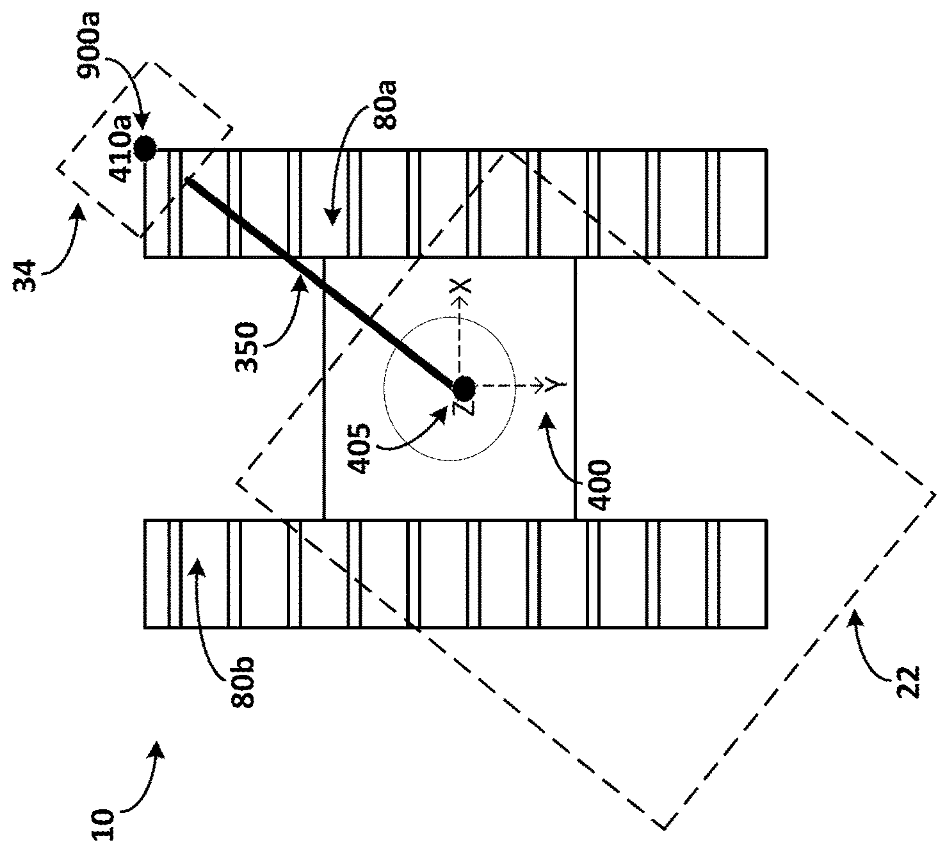


FIG. 10A

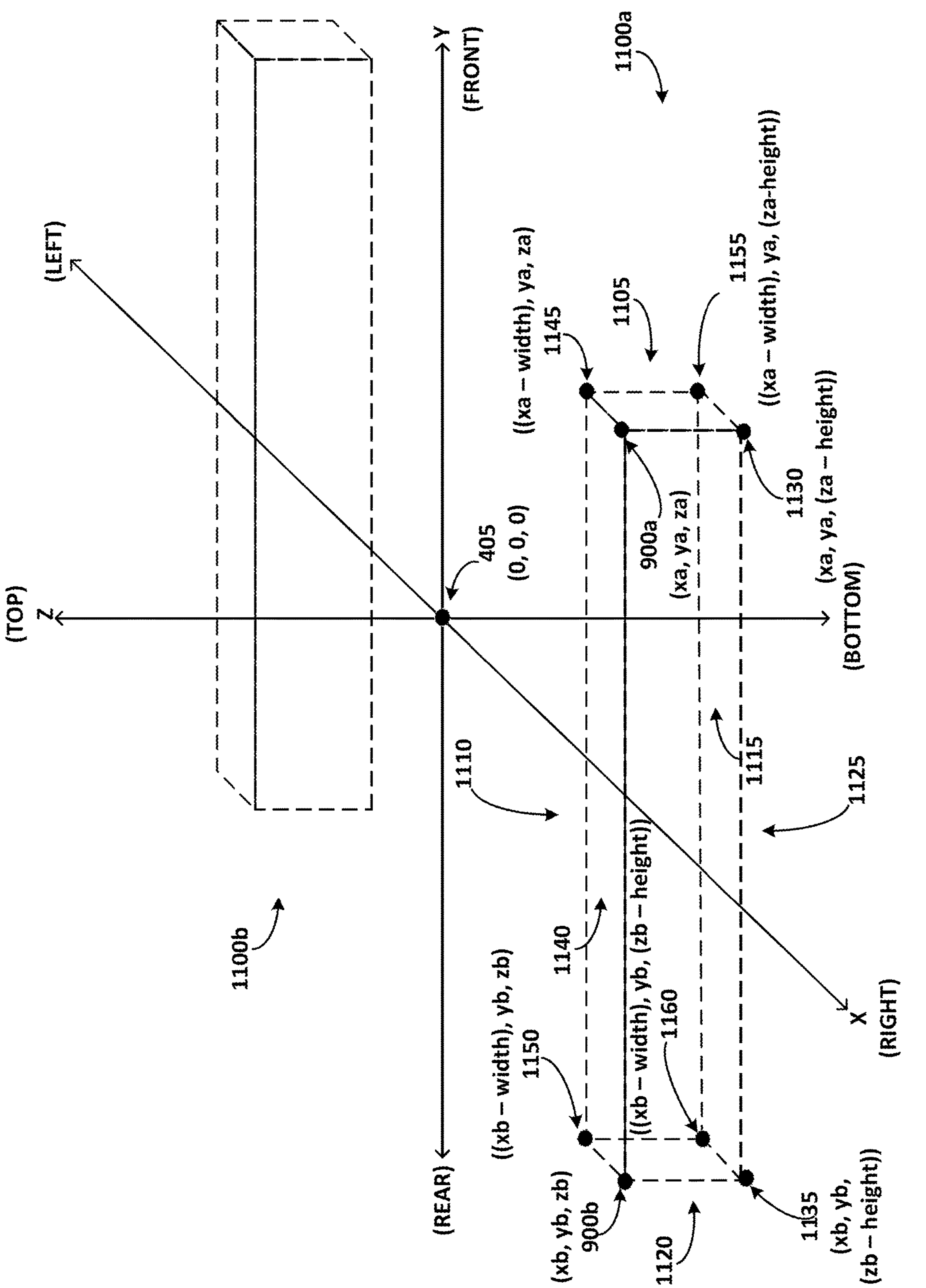

1100a
Y
(FRONT)
(LEFT)
(TOP)
Z
405
(0, 0, 0)
(BOTTOM)
X
(RIGHT)
(REAR)
1105
1145
((xa – width), ya, za)
1155
((xa – width), ya, (za-height))
900a
(xa, ya, za)
1130
(xa, ya, (za – height))
1110
1115
1125
1100b
1140
((xb – width), yb, (zb – height))
1160
1150
((xb – width), yb, zb)
(xb, yb, zb)
900b
1120
1135
(xb, yb,
(zb – height))

FIG. 11

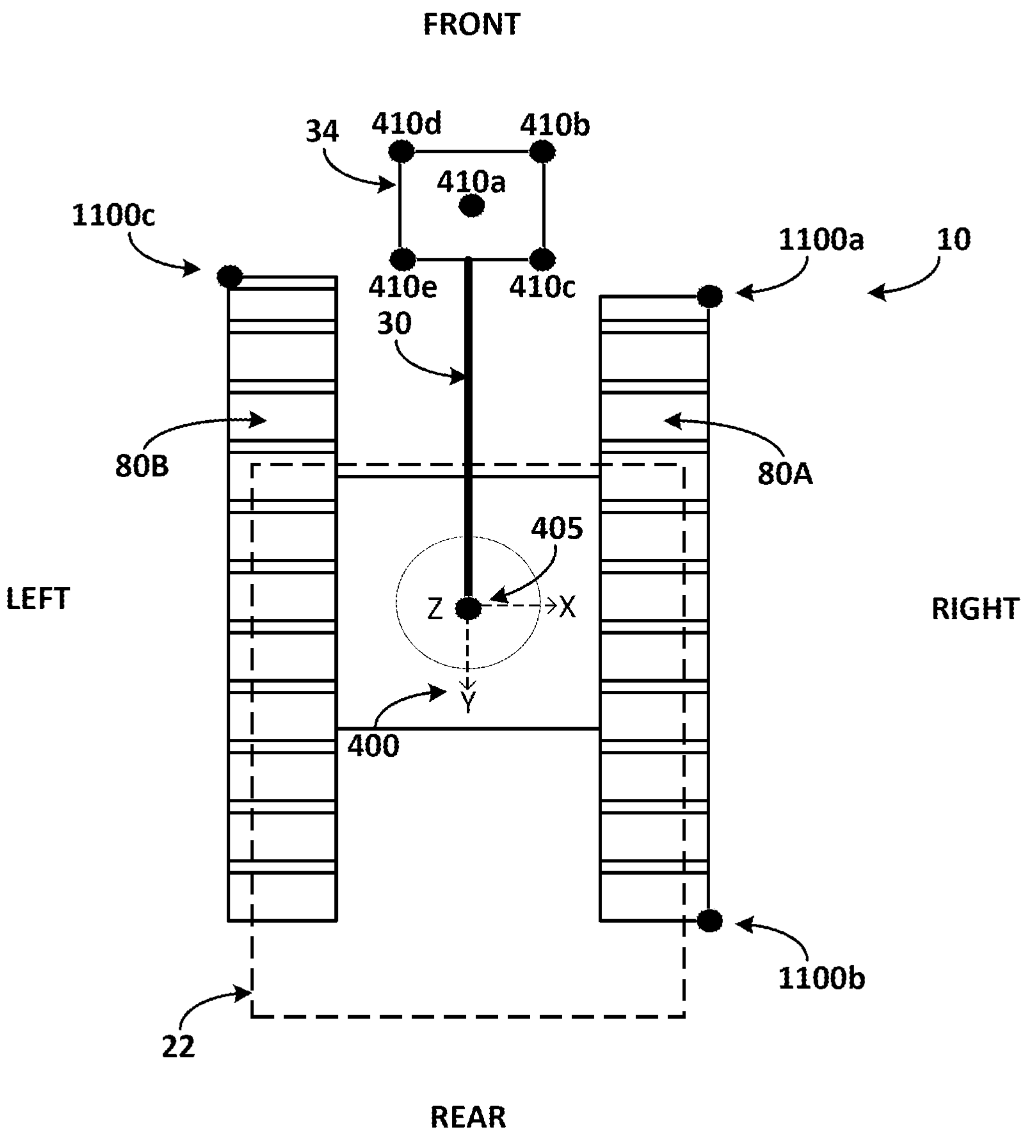

FRONT
34
410d
410b
410a
1100c
1100a
10
410e
410c
30
80B
80A
405
LEFT
Z
X
RIGHT
Y
400
1100b
22
REAR

FIG. 12

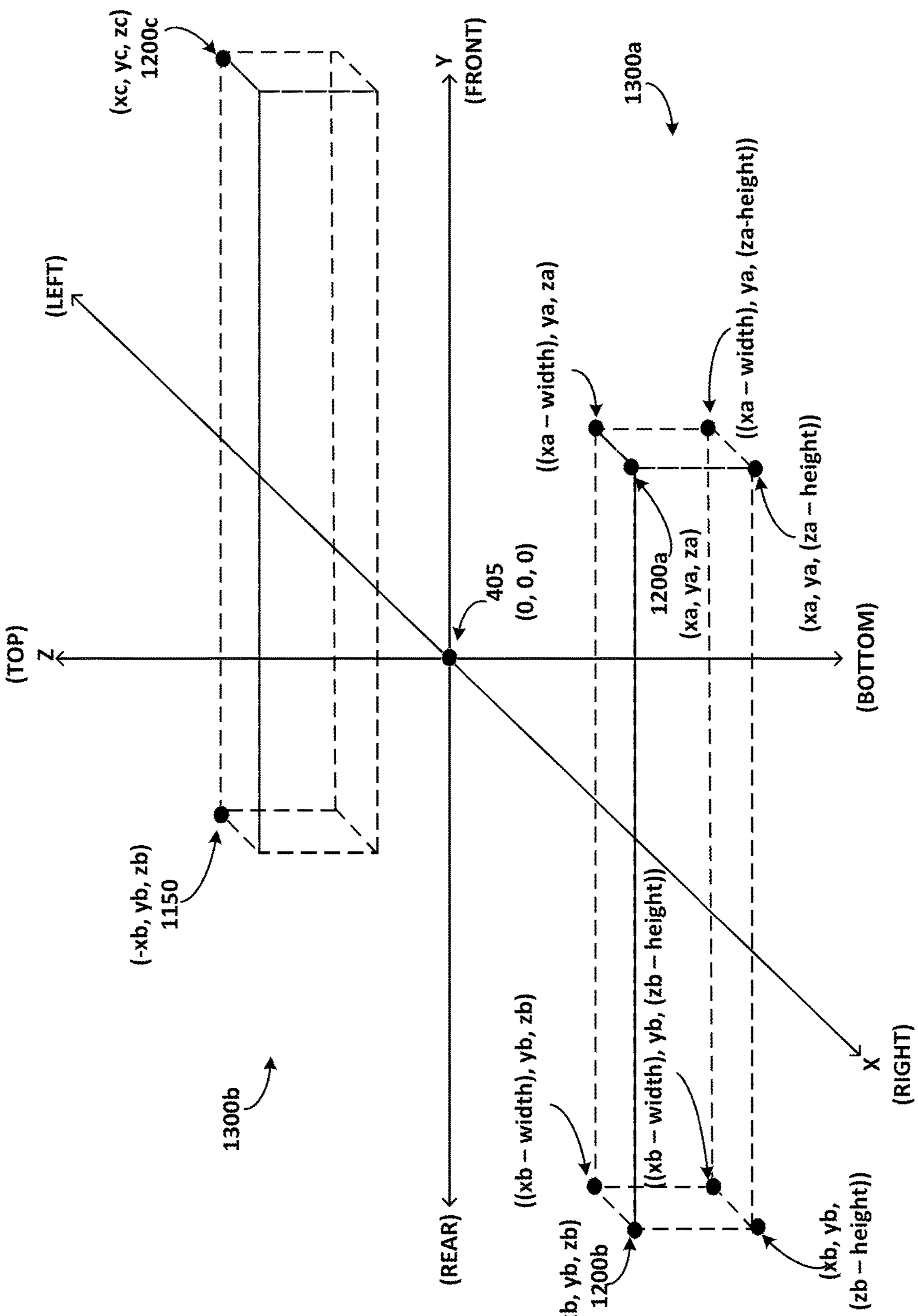

(xc, yc, zc)
1200c
Y
(FRONT)
1300a
((xa – width), ya, (za-height))
(LEFT)
((xa – width), ya, za)
405
(0, 0, 0)
1200a
(xa, ya, za)
(xa, ya, (za – height))
(TOP)
Z
(BOTTOM)
(-xb, yb, zb)
1150
1300b
((xb – width), yb, zb)
((xb – width), yb, (zb – height))
X
(RIGHT)
(REAR)
(xb, yb, zb)
1200b
(xb, yb,
(zb – height))

FIG. 13

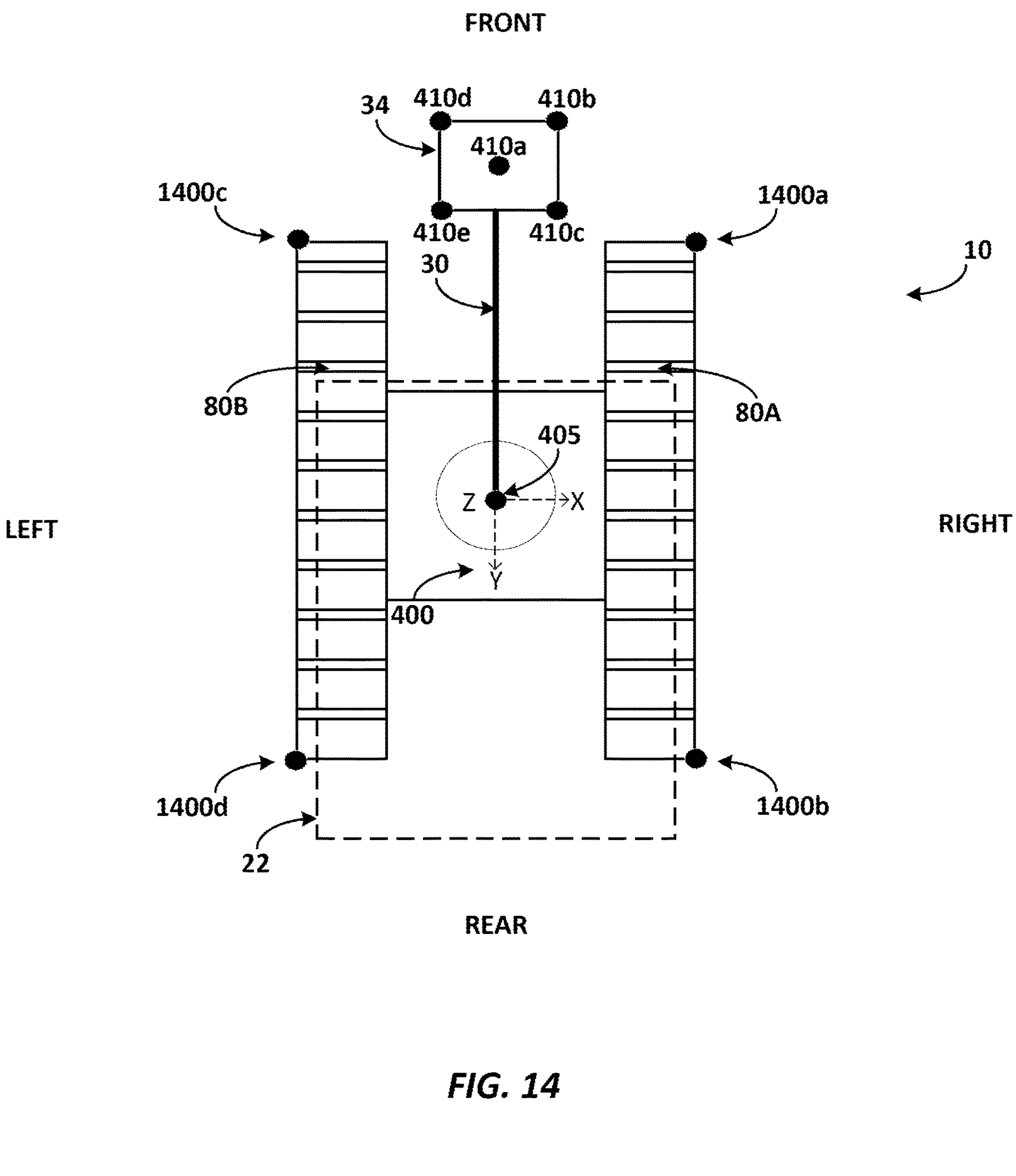

FRONT
34
410d
410b
410a
1400c
1400a
410e
410c
30
10
80B
80A
405
Z
X
LEFT
RIGHT
Y
400
1400d
1400b
22
REAR

FIG. 14

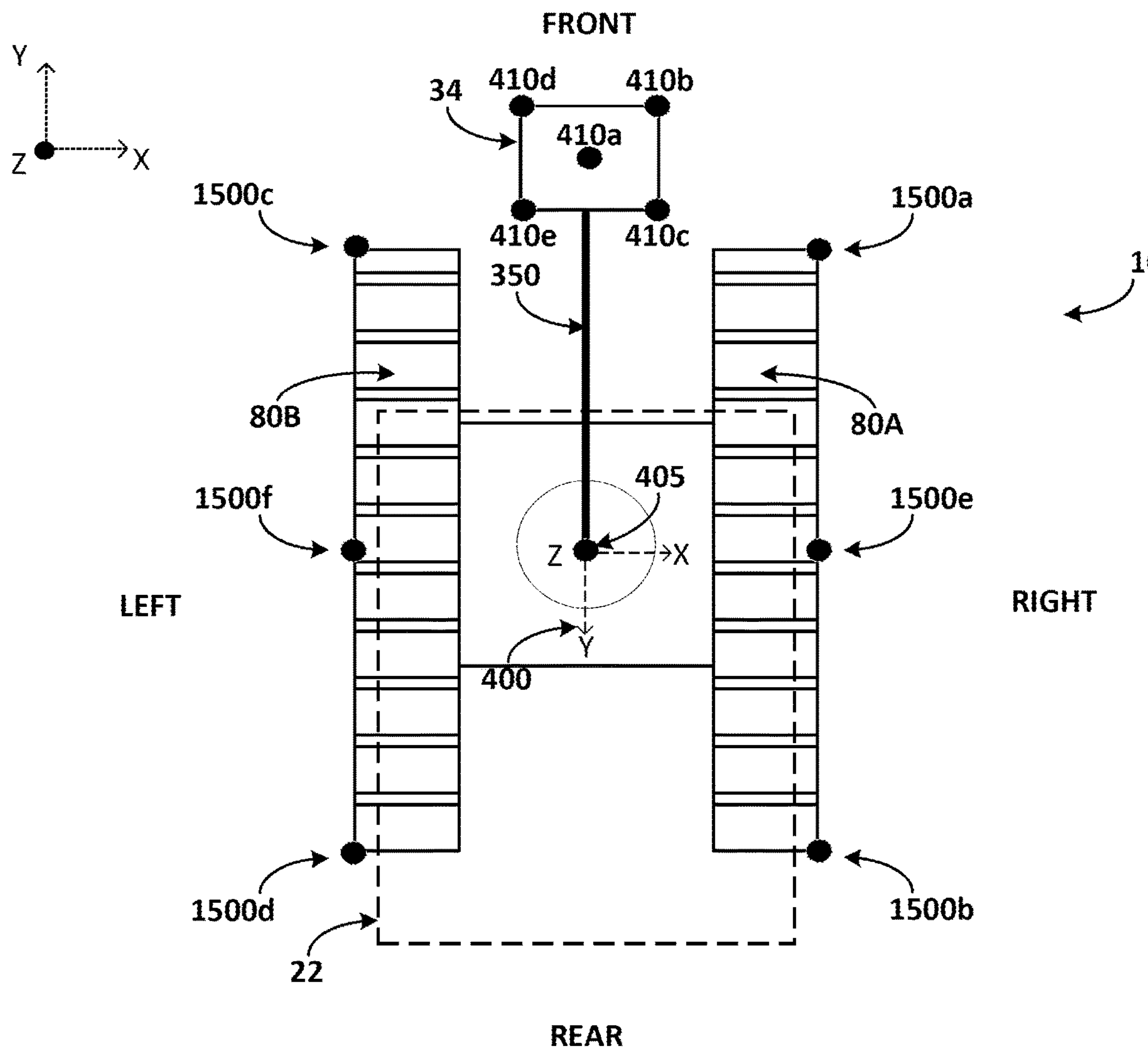

FRONT
Y
Z
X
34
410d
410b
410a
410e
410c
1500c
1500a
350
10
80B
80A
405
1500f
1500e
Z
X
LEFT
RIGHT
Y
400
1500d
1500b
22
REAR

FIG. 15

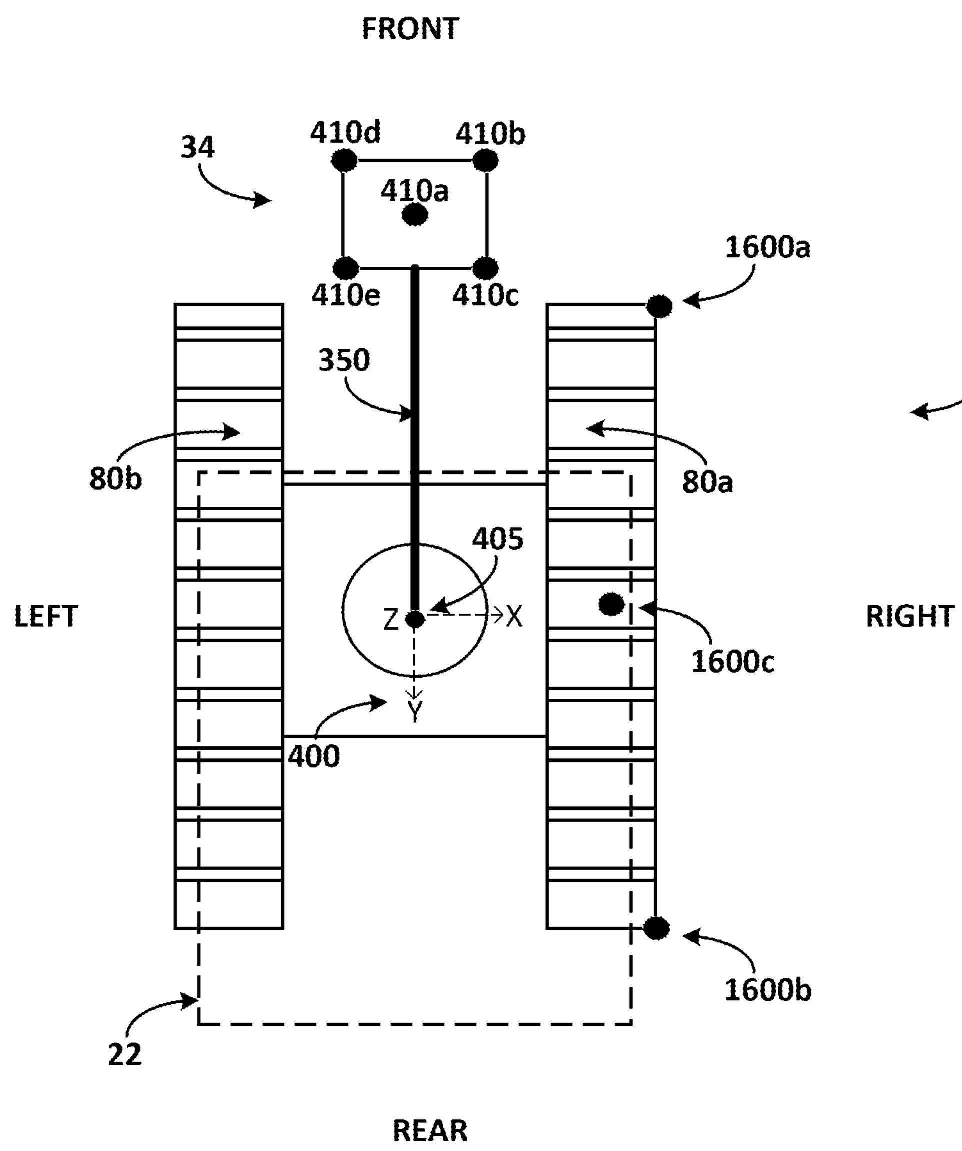

FRONT
34
410d
410b
410a
410e
410c
1600a
350
10
80b
80a
405
LEFT
Z
X
RIGHT
1600c
Y
400
1600b
22
REAR

FIG. 16

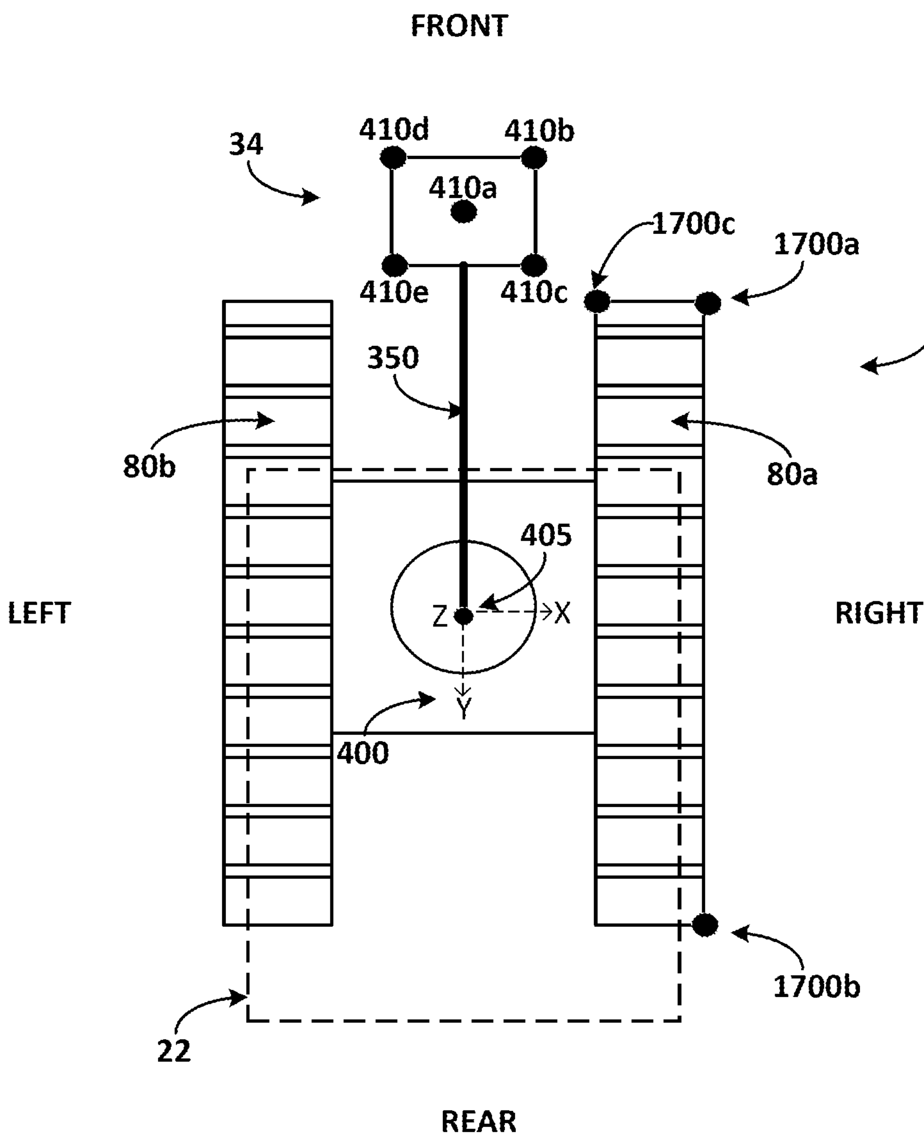

FRONT
34
410d
410b
410a
1700c
1700a
410e
410c
10
350
80b
80a
405
LEFT
Z
X
RIGHT
Y
400
1700b
22
REAR

FIG. 17

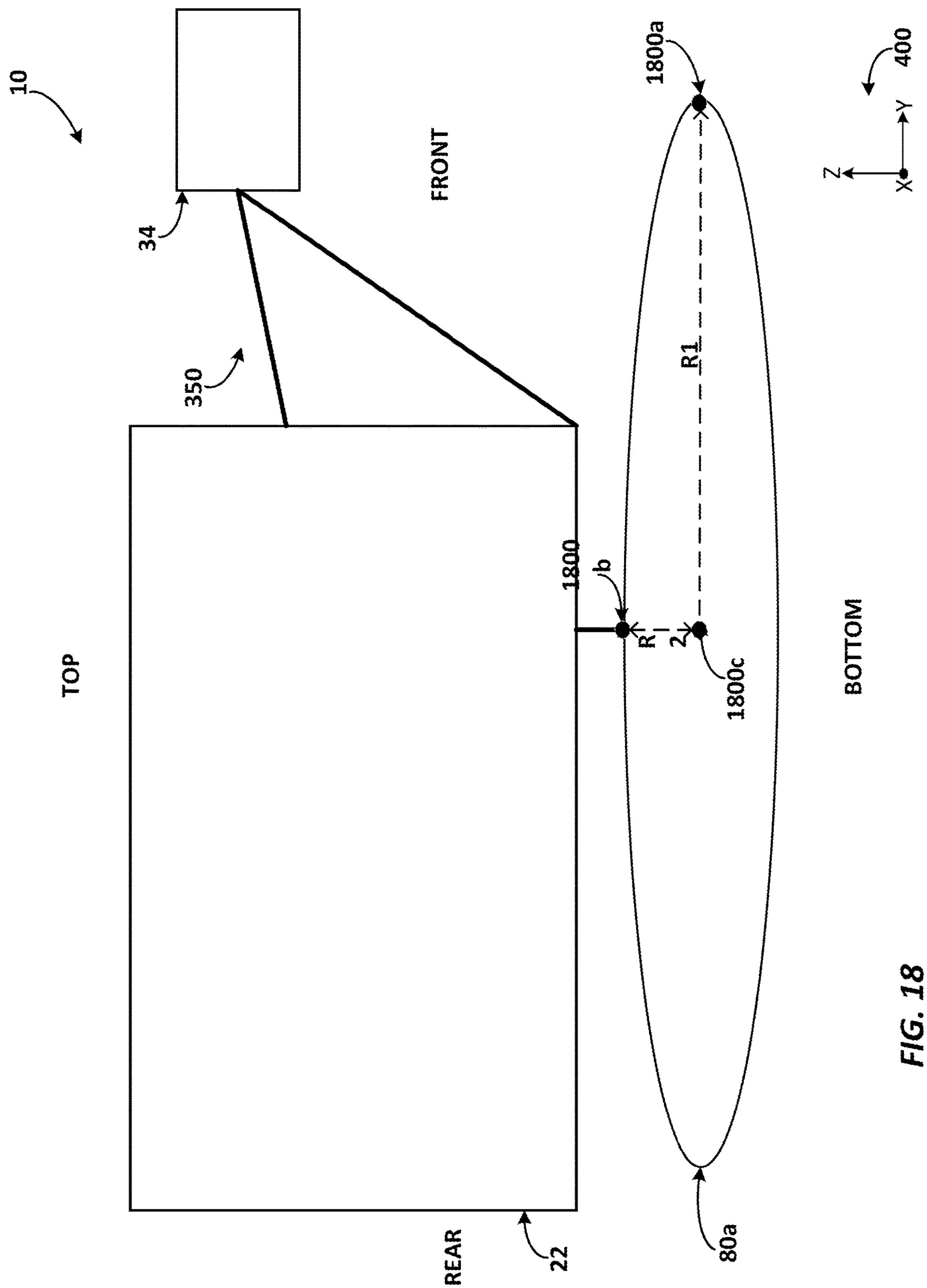

10
34
FRONT
350
TOP
1800b
R2
1800a
R1
1800c
BOTTOM
400
Z
Y
X
REAR
22
80a

FIG. 18

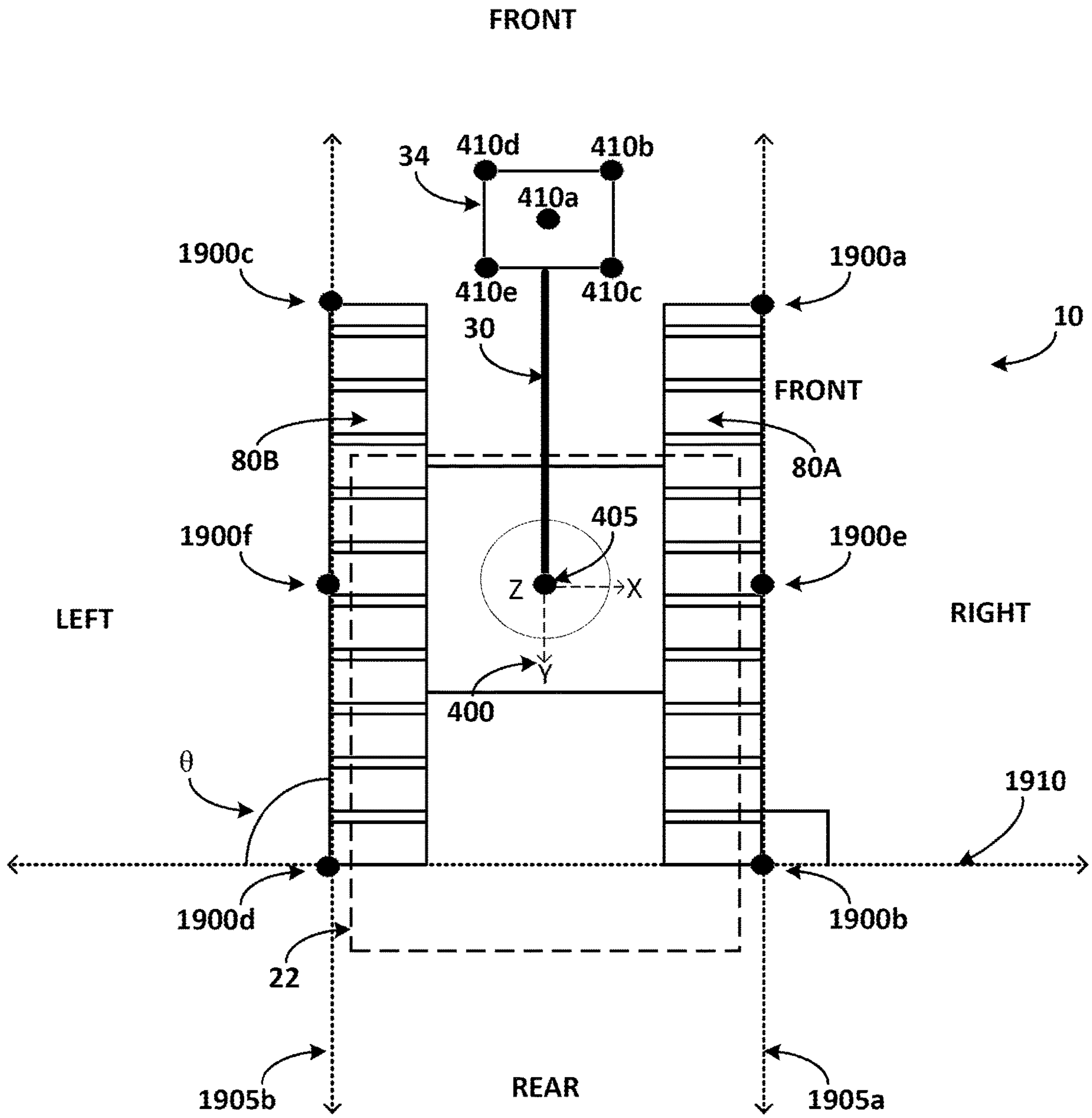

FRONT
34
410d
410b
410a
410e
410c
1900c
1900a
30
10
FRONT
80B
80A
405
1900f
1900e
Z
X
Y
LEFT
RIGHT
400
θ
1910
1900d
1900b
22
1905b
REAR
1905a

FIG. 19

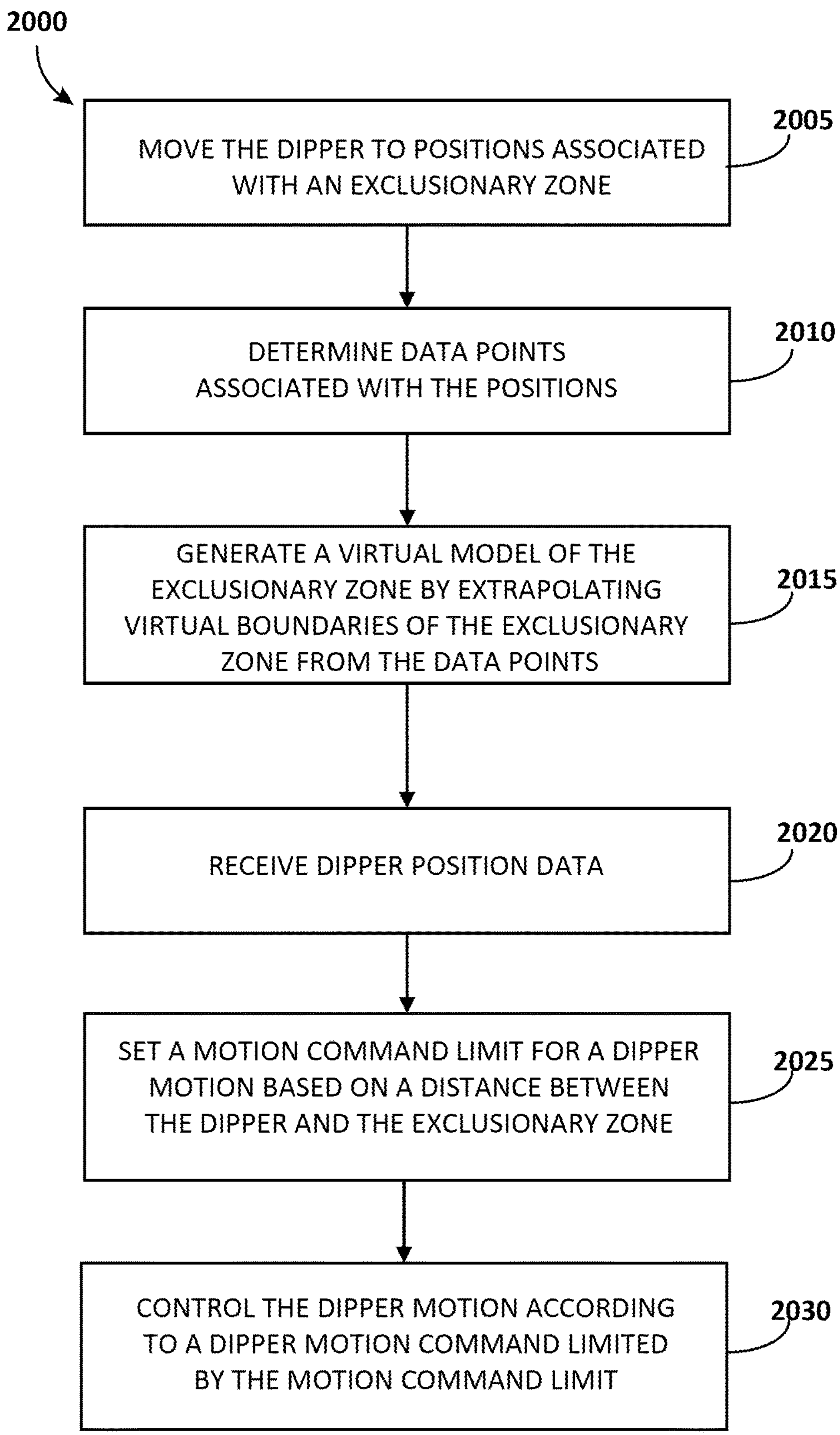

2000
MOVE THE DIPPER TO POSITIONS ASSOCIATED WITH AN EXCLUSIONARY ZONE
2005
DETERMINE DATA POINTS ASSOCIATED WITH THE POSITIONS
2010
GENERATE A VIRTUAL MODEL OF THE EXCLUSIONARY ZONE BY EXTRAPOLATING VIRTUAL BOUNDARIES OF THE EXCLUSIONARY ZONE FROM THE DATA POINTS
2015
RECEIVE DIPPER POSITION DATA
2020
SET A MOTION COMMAND LIMIT FOR A DIPPER MOTION BASED ON A DISTANCE BETWEEN THE DIPPER AND THE EXCLUSIONARY ZONE
2025
CONTROL THE DIPPER MOTION ACCORDING TO A DIPPER MOTION COMMAND LIMITED BY THE MOTION COMMAND LIMIT
2030

FIG. 20

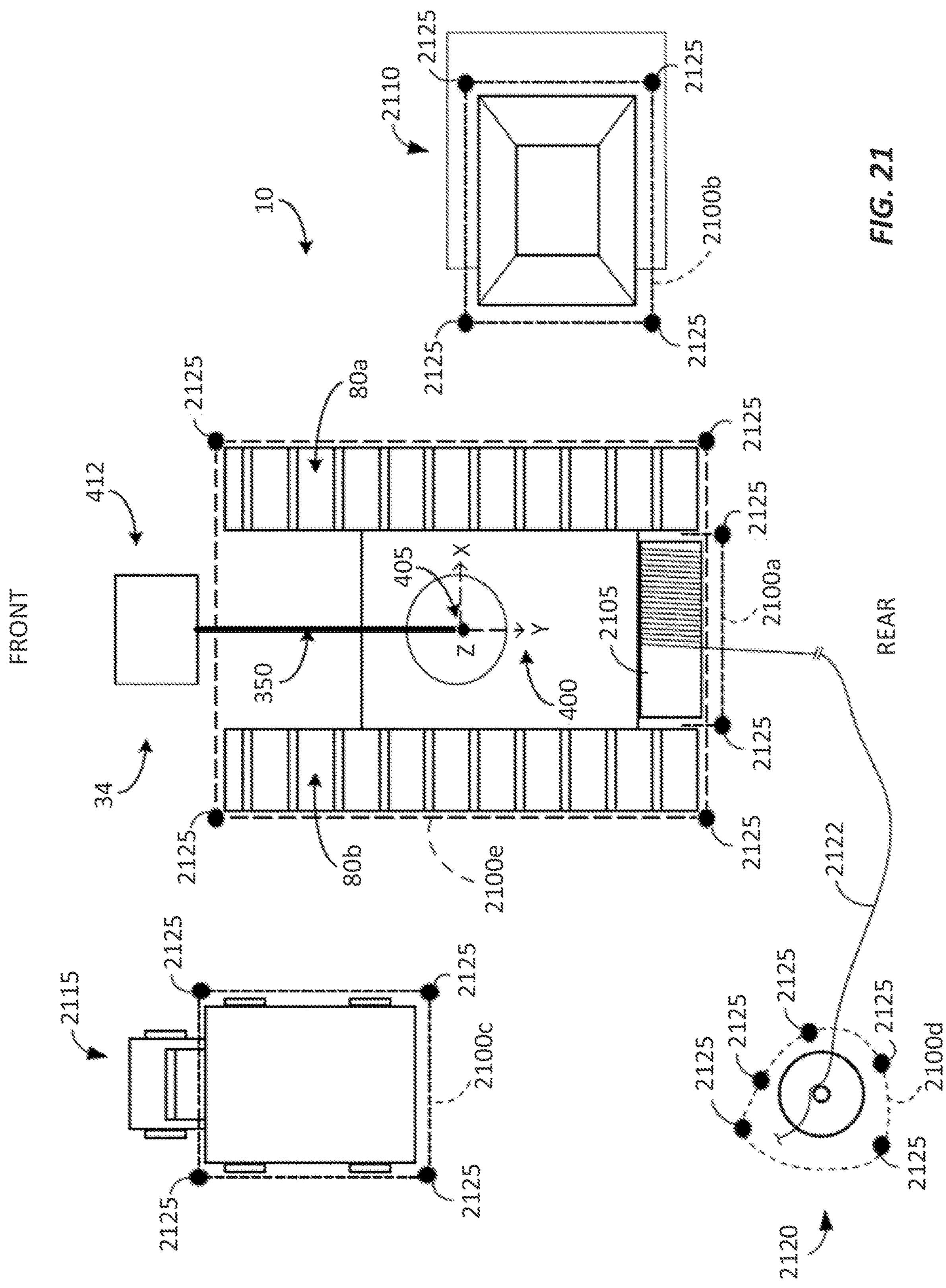

FRONT
REAR
10
412
34
350
400
405
X
Y
Z
80a
80b
2105
2100a
2100b
2100c
2100d
2100e
2110
2115
2120
2122
2125

FIG. 21

SYSTEMS AND METHODS FOR MITIGATING COLLISIONS BETWEEN A MINING MACHINE AND AN EXCLUSIONARY ZONE

FIELD

[0001] Embodiments described herein relate to systems and methods for preventing or mitigating collisions between a dipper and an exclusionary zone associated a mining machine

SUMMARY

[0002] Rope shovels include a dipper that typically can be controlled by an operator to move along at least three motions: hoist (up/down), crowd (in/out), and swing (left/right). During the course of mining operations, an operator may inadvertently control the dipper in such a way that results in a collision with an exclusionary zone located on or near the rope shovel. Such collisions can damage the lower machinery, the dipper, or both.

[0003] Embodiments described herein provide systems and methods that mitigate or avoid such collisions by limiting dipper movement in terms of the swing motion, crowd motion, and/or hoist motion, depending on the current proximity of the dipper to the exclusionary zone. At least some of the embodiments provide collision prevention and mitigation by defining virtual three-dimensional fields around the dipper for each of the swing, crowd, and hoist dipper motions. When one or more of these virtual fields of the dipper overlaps a virtual exclusionary zone model for the rope shovel, the one or more dipper motions associated with the one or more overlapping virtual fields is limited. These dipper motions are increasingly limited the closer that the dipper is to the exclusionary zone, which may be perceived by the operator like the increasing repelling forces of the ends of two magnets having the same pole as they come closer together. By limiting one or more dipper motions, the systems and methods described herein result in mitigated collisions (e.g., collisions with reduced severity than would otherwise occur) and, in some instances, prevented collisions (i.e., collisions that are avoided that would otherwise occur).

[0004] In one embodiment, a method is provided for preventing and mitigating collisions between a dipper and an exclusionary zone that is taught to a mining machine. The method includes moving, by an electronic processor, the dipper to a plurality of positions associated with the exclusionary zone and determining, by the electronic processor, data points for the exclusionary zone, each data point associated with a position of the plurality of positions. The method further includes generating, by the electronic processor, a virtual model of the exclusionary zone by extrapolating virtual boundaries of the exclusionary zone from the data points and receiving, by the electronic processor, dipper position data indicative of a position of the dipper. The method further includes setting, by the electronic processor, a motion command limit for a dipper motion based on a distance between the dipper and the exclusionary zone of the mining machine inferred from the dipper position data, the dipper motion being selected from a group of a swing motion, a crowd motion, and a hoist motion and controlling, by the electronic processor, the dipper motion according to a dipper motion command limited by the motion command limit.

[0005] In another embodiment, a mining machine with a collision prevention and mitigation system is provided. The mining machine includes a frame, a dipper supported by the frame, a dipper drive coupled to the dipper and configured to move the dipper in a dipper motion selected from a group of a swing motion, a crowd motion, and a hoist motion, and a dipper position sensor configured to determine a position of the dipper. The mining machine further includes an electronic controller, which includes an electronic processor and a memory, that is coupled to the dipper drive and the dipper position sensor. The electronic controller is configured to move the dipper to a plurality of positions associated with an exclusionary zone, determine data points for the exclusionary zone, each data point associated with a position of the plurality of positions, and generate a virtual model of the exclusionary zone by extrapolating virtual boundaries of the exclusionary zone from the data points. The electronic controller is further configured to receive dipper position data indicative of a position of the dipper, set a motion command limit for a dipper motion based on a distance between the dipper and the exclusionary zone of the mining machine inferred from the dipper position data, the dipper motion being selected from a group of a swing motion, a crowd motion, and a hoist motion, and control the dipper motion according to a dipper motion command limited by the motion command limit.

[0006] In another embodiment, a collision prevention and mitigation control system is provided for a mining machine having a frame, a dipper supported by the frame, a dipper drive coupled to the dipper and configured to move the dipper in a dipper motion selected from a group of a swing motion, a crowd motion, and a hoist motion, and a dipper position sensor configured to determine a position of the dipper. The control system includes an electronic controller, which includes an electronic processor and a memory, that is coupled to the dipper drive and dipper position sensor. The electronic controller is configured move the dipper to a plurality of positions associated with an exclusionary zone, determine data points for the exclusionary zone, each data point associated with a position of the plurality of positions, and generate a virtual model of the exclusionary zone by extrapolating virtual boundaries of the exclusionary zone from the data points. The electronic controller is further configured to receive dipper position data indicative of a position of the dipper, set a motion command limit for a dipper motion based on a distance between the dipper and the exclusionary zone of the mining machine inferred from the dipper position data, the dipper motion being selected from a group of a swing motion, a crowd motion, and a hoist motion, and control the dipper motion according to a dipper motion command limited by the motion command limit.

[0007] Additional embodiments described herein provide systems and methods that mitigate or avoid such collisions between the dipper and tracks of the rope shovel by limiting dipper movement in terms of the swing motion, crowd motion, and/or hoist motion, depending on the current proximity of the dipper to the tracks. At least some of the embodiments provide collision prevention and mitigation by defining virtual three-dimensional fields around the dipper for each of the swing, crowd, and hoist dipper motions. When one or more of these virtual fields of the dipper

overlaps a virtual tracks model for the rope shovel, the one or more dipper motions associated with the one or more overlapping virtual fields is limited. These dipper motions are increasingly limited the closer that the dipper is to the tracks, which may be perceived by the operator like the increasing repelling forces of the ends of two magnets having the same pole as they come closer together. By limiting one or more dipper motions, the systems and methods described herein result in mitigated collisions (e.g., collisions with reduced severity than would otherwise occur) and, in some instances, prevented collisions (i.e., collisions that are avoided that would otherwise occur).

[0008] Other embodiments described herein provide systems and methods for generating a three-dimensional virtual track model. This track model may be used, for example, in collision prevention and mitigation systems and methods, such as those described herein, and in other collision prevention and mitigation systems and other mining systems using virtual track models. In some embodiments, the systems and methods described herein provide a simplified modeling process that enables quick, accurate modeling of tracks of a mining machine that can account for custom tracks that vary in size depending on the particular mining machine. Other aspects of the embodiments will become apparent by consideration of the detailed description and accompanying drawings.

BRIEF DESCRIPTION OF THE DRAWINGS

[0009] FIG. **1** is a perspective view of a mining machine, according to some embodiments.

[0010] FIG. **2** is a profile view of the mining machine of FIG. **1**.

[0011] FIGS. **3**A-**3**B are block diagrams for the mining machine of FIG. **1**, according to some embodiments.

[0012] FIG. **4** is a top-down schematic view for the mining machine of FIG. **1**.

[0013] FIG. **5** illustrates a flow chart for preventing or mitigating collisions between a dipper and tracks of a mining machine, according to some embodiments.

[0014] FIG. **6** illustrates a virtual model for the mining machine of FIG. **1**, according to some embodiments.

[0015] FIGS. **7**A-**7**C illustrate example limit functions for a dipper motion, according to some embodiments.

[0016] FIG. **8** illustrates a flow chart for modeling tracks of a mining machine, according to some embodiments.

[0017] FIG. **9** illustrates a first position and a second position of tracks in a top-down schematic view for the mining machine of FIG. **1**, according to some embodiments.

[0018] FIGS. **10**A-**10**B illustrate, respectively, the first position and the second position of tracks in a top-down schematic view for the mining machine of FIG. **1**, according to some embodiments.

[0019] FIG. **11** illustrates a perspective view of a virtual model of the tracks for the mining machine of FIG. **1**, according to some embodiments.

[0020] FIG. **12** illustrates an embodiment of the mining machine of FIG. **1** in which the front end of left track extends further than the right track.

[0021] FIG. **13** illustrates a perspective view of a virtual model of the tracks for the mining machine of FIG. **12**, according to some embodiments.

[0022] FIG. **14** illustrates four track positions in a top-down schematic view for the mining machine of FIG. **1**, according to some embodiments.

[0023] FIG. **15** illustrates six track positions in a top-down schematic view for the mining machine of FIG. **1**, according to some embodiments.

[0024] FIGS. **16** and **17** illustrate track positions for generating a track model of tracks with an unknown height and unknown width, respectively, in a top-down schematic view for the mining machine of FIG. **1**, according to some embodiments.

[0025] FIG. **18** illustrates a schematic profile view of the mining machine of FIG. **1**, according to some embodiments.

[0026] FIG. **19** illustrates a top-down schematic view of the mining machine of FIG. **1** for swing sensor calibration, according to some embodiments.

[0027] FIG. **20** illustrates a flow chart for preventing or mitigating collisions between a dipper and an exclusionary zone, according to some embodiments.

[0028] FIG. **21** illustrates a top-down schematic view of the mining machine of FIG. **1** with exclusionary zones, according to some embodiments.

DETAILED DESCRIPTION

[0029] Before any embodiments are explained in detail, it is to be understood that the embodiments are not limited in its application to the details of the configuration and arrangement of components set forth in the following description or illustrated in the accompanying drawings. The embodiments are capable of being practiced or of being carried out in various ways. Also, it is to be understood that the phraseology and terminology used herein are for the purpose of description and should not be regarded as limiting. The use of “including,” “comprising,” or “having” and variations thereof are meant to encompass the items listed thereafter and equivalents thereof as well as additional items. Unless specified or limited otherwise, the terms “mounted,” “connected,” “supported,” and “coupled” and variations thereof are used broadly and encompass both direct and indirect mountings, connections, supports, and couplings.

[0030] In addition, it should be understood that embodiments may include hardware, software, and electronic components or modules that, for purposes of discussion, may be illustrated and described as if the majority of the components were implemented solely in hardware. However, one of ordinary skill in the art, and based on a reading of this detailed description, would recognize that, in at least one embodiment, the electronic-based aspects may be implemented in software (e.g., stored on non-transitory computer-readable medium) executable by one or more electronic processors, such as a microprocessor and/or application specific integrated circuits (“ASICs”). As such, it should be noted that a plurality of hardware and software based devices, as well as a plurality of different structural components, may be utilized to implement the embodiments. For example, “servers,” “computing devices,” “controllers,” “processors,” etc., described in the specification can include one or more electronic processors, one or more computer-readable medium modules, one or more input/output interfaces, and various connections (e.g., a system bus) connecting the components.

[0031] Relative terminology, such as, for example, “about,” “approximately,” “substantially,” etc., used in connection with a quantity or condition would be understood by those of ordinary skill to be inclusive of the stated value and has the meaning dictated by the context (e.g., the term includes at least the degree of error associated with the measurement accuracy, tolerances [e.g., manufacturing, assembly, use, etc.] associated with the particular value, etc.). Such terminology should also be considered as disclosing the range defined by the absolute values of the two endpoints. For example, the expression "from about 2 to about 4" also discloses the range "from 2 to 4." The relative terminology may refer to plus or minus a percentage (e.g., 1%, 5%, 10%, or more) of an indicated value.

[0032] Functionality described herein as being performed by one component may be performed by multiple components in a distributed manner. Likewise, functionality performed by multiple components may be consolidated and performed by a single component. Similarly, a component described as performing particular functionality may also perform additional functionality not described herein. For example, a device or structure that is "configured" in a certain way is configured in at least that way but may also be configured in ways that are not explicitly listed.

[0033] As shown in FIGS. **1** and **2**, a rope shovel **10** rests on a support surface, or floor, and includes a base or frame **22**, a boom **26**, a first member or handle **30**, a dipper or bucket **34**, and a pivot actuator **36**. The base **22** includes a hoist drum **40** (FIG. **1**) for reeling in and paying out a cable, or hoist rope **42**. The boom **26** includes a first end **46** coupled to the base **22**, a second end **50** opposite the first end **46**, a boom sheave **54**, a saddle block **58**, and a shipper shaft **62** (FIG. **1**). The boom sheave **54** is coupled to the second end **50** of the boom **26** and guides the rope **42** over the second end **50**. The rope **42** is coupled to the dipper **34** by a bail **66**. The dipper **34** is raised or lowered as the rope **42** is reeled in or paid out, respectively, by the hoist drum **40**. The motion up and down by the dipper **34** due to the rotation of the hoist drum **40** is referred to as hoist motion, which may include hoisting up and hoisting down.

[0034] The saddle block **58** is rotatably coupled to the boom **26** by the shipper shaft **62**, which is positioned between the first end **46** and the second end **50** of the boom **26** and extends through the boom **26**. The handle **30** is moveably coupled to the boom **26** by the saddle block **58**. The shipper shaft **62** includes a spline pinion for engaging a rack **90** of the handle **30**. The first end **82** of the handle **30** is moveably received in the saddle block **58**, and the handle **30** passes through the saddle block **58** such that the handle **30** is configured for rotational and translational movement relative to the boom **26** (FIG. **1**). Stated another way, the handle **30** is linearly extendable and retractable relative to the saddle block **58** and is rotatable about the shipper shaft **62**. The motion of the dipper **34** in and out due to extension and retraction of the handle **30** is referred to as crowd motion, which may include crowding in and crowding out.

[0035] The dipper **34** is pivotably coupled to the handle **30** at a wrist joint **70**. The bail **66** is coupled to the rope **42** passing over the boom sheave **54** and is pivotably coupled to the dipper **34**. The pivot actuator **36** controls the pitch of the dipper **34** by rotating the dipper **34** about the wrist joint **70**. In the illustrated embodiment, the pivot actuator **36** includes a pair of hydraulic cylinders directly coupled between a lower portion of the handle **30** and a lower portion of the dipper **34**. In other embodiments, a different type of actuator may be used.

[0036] In the illustrated embodiment, the dipper **34** is a clamshell-type dipper including a main body **72** and a rear wall **74**. The main body **72** is pivotably coupled to the rear wall **74** about a dipper joint and can be controlled by a hydraulic cylinder to open apart to discharge contents within the dipper **34**. In other embodiments, instead of a clamshell-type dipper, the dipper **34** is a bucket-type dipper with a pivoting dump door that latches and that is selectively opened to dump contents of the dipper **34**.

[0037] The shovel **10** further includes tracks **80** configured to be driven to move the shovel **10** forward, in reverse, or to turn over a ground surface. The tracks **80** may include a first, or right, track **80***a* and a second, or left, track **80***b*. The term tracks **80** may be used herein to reference one of the tracks **80***a* or **80***b* generically, or both of the tracks **80***a* and **80***b* collectively. The base **22** is further operable to rotate relative to the tracks **80** about a swing axis **84**.

[0038] The shovel **10** of FIGS. **1** and **2** is an example of a rope shovel that may implement one or more embodiments described herein. However, in some embodiments, rope shovels of a different construction are used. For example, some constructions of the shovel **10** do not include the operator cab **120** or one or more other components as described above. Other constructions of the shovel **10** may include additional components not shown in FIGS. **1** and **2**.

[0039] FIG. **3**A illustrates a block diagram of the shovel **10**. The shovel **10** includes a controller **200**, which is an electronic controller that is electrically and/or communicatively connected to a variety of modules or components of the shovel **10**. For example, the illustrated controller **200** is connected to one or more indicators **205**, a user interface **210**, a crowd drive **215**, a hoist drive **220**, a swing drive **225**, a tracks drive **227**, a database **230**, a power supply **235**, and one or more sensors **240**.

[0040] The controller **200** includes combinations of hardware and software that are configured, operable, and/or programmed to, among other things, control the operation of the shovel **10**, generate sets of control signals to activate the one or more indicators **205** (e.g., a liquid crystal display ["LCD"], one or more light sources [e.g., LEDs], etc.), monitor the operation of the shovel **10**, and the like. The one or more sensors **240** include, among other things, a loadpin, a strain gauge, one or more inclinometers, gantry pins, one or more motor field modules (e.g., measuring motor parameters such as current, voltage, power, etc.), one or more rope tension sensors, one or more resolvers, RADAR, LIDAR, one or more cameras, one or more infrared sensors, and the like.

[0041] The controller **200** includes a plurality of electrical and electronic components that provide power, operational control, and protection to the components and modules within the controller **200** and/or shovel **10**. For example, the controller **200** includes, among other things, an electronic processor **250** (e.g., a microprocessor, a microcontroller, or another suitable programmable device), a memory **255**, input units **260**, and output units **265**. The electronic processor **250** includes, among other things, a control unit **270**, an arithmetic logic unit ("ALU") **275**, and a plurality of registers **280** (shown as a group of registers in FIG. **3**A), and is implemented using a known computer architecture (e.g., a modified Harvard architecture, a von Neumann architecture, etc.). The electronic processor **250**, the memory **255**, the input units **260**, and the output units **265**, as well as the various modules connected to the controller **200** are connected by one or more control and/or data buses (e.g., common bus **285**). The control and/or data buses are shown generally in FIG. **3**A for illustrative purposes. The use of one or more control and/or data buses for the interconnection between and communication among the various modules and components would be known to a person skilled in the art in view of the embodiments described herein.

[0042] The memory **255** is a non-transitory computer readable medium that includes, for example, a program storage area and a data storage area. The program storage area and the data storage area can include combinations of different types of memory, such as read-only memory ("ROM"), random access memory ("RAM") (e.g., dynamic RAM ["DRAM"], synchronous DRAM ["SDRAM"], etc.), electrically erasable programmable read-only memory ("EEPROM"), flash memory, a hard disk, an SD card, or other suitable magnetic, optical, physical, or electronic memory devices. The electronic processor **250** is connected to the memory **255** and executes software instructions that are stored in a RAM of the memory **255** (e.g., during execution), a ROM of the memory **255** (e.g., on a generally permanent basis), or another non-transitory computer readable medium such as another memory or a disc. Software included in the implementation of the shovel **10** can be stored in the memory **255** of the controller **200**. The software includes, for example, firmware, one or more applications, program data, filters, rules, one or more program modules, and other executable instructions. The controller **200** and, in particular, the electronic processor **250**, is configured to retrieve from memory and execute, among other things, instructions for implementing or otherwise related to the control processes and methods described herein. In other constructions, the controller **200** includes additional, fewer, or different components.

[0043] The power supply **235** supplies a nominal AC or DC voltage to the controller **200** and other components or modules of the shovel **10**. The power supply **235** receives power from, for example, an engine-generator, and conditions that power (e.g., steps down, steps up, filters the power) and provides the conditioned power to the components of the shovel **10** and controller **200**. For example, the power supply **235** may include a plurality of power supplies providing different power levels to different components of the shovel **10**. For example, a first power supply of the power supply **235** may provide lower voltages to operate circuits and components within the controller **200** or shovel **10** and a second power supply to provide power to the drives **215**, **220**, **225**, **227**. In other constructions, the controller **200** or other components and modules within the shovel **10** are powered by line voltage provided by a power cable coupled to a power station off-board the shovel **10**, one or more batteries or battery packs, or another grid-independent power source (e.g., a solar panel, etc.).

[0044] The user interface **210** is used to control or monitor the shovel **10**. The user interface **210** includes a combination of digital and analog input or output devices used to achieve a desired level of control and monitoring for the shovel **10**. For example, the user interface **210** includes a display (e.g., a primary display, a secondary display, etc.) and input devices such as touch-screen displays, a plurality of knobs, dials, switches, buttons, etc. The display is, for example, a liquid crystal display ("LCD"), a light-emitting diode ("LED") display, an organic LED ("OLED") display, an electroluminescent display ("ELD"), a surface-conduction electron-emitter display ("SED"), a field emission display ("FED"), a thin-film transistor ("TFT") LCD, or the like. The user interface **210** can also be configured to display conditions or data associated with the shovel **10** in real-time or substantially real-time. For example, the user interface **210** is configured to display measured electrical characteristics of the shovel **10**, the status of the shovel **10**, etc. In some implementations, the user interface **210** is controlled in conjunction with the one or more indicators **205** (e.g., LEDs, speakers, etc.) to provide visual or auditory indications (e.g., from a horn of the shovel **10**) of the status or conditions of the shovel **10**. In some implementations, at least a portion of the user interface **210** is off-board of the shovel **10** and includes control inputs enabling remote control of the shovel **10** by an operator not present in the operator cab.

[0045] The crowd drive **215**, the hoist drive **220**, the swing drive **225**, and the tracks drive **227** may each include a respective motor and a drive controller configured to drive the motor based on commands from the controller **200**. The commands may be generated in response to inputs received from an operator of the shovel **10** via the user interface **210**.

[0046] FIG. **3**B provides a block diagram **300** for the shovel **10** illustrating portions of the shovel **10** in further detail. For example, FIG. **3**A illustrates dipper motion command input devices **305**, dipper drives **310**, and dipper position sensors **315** coupled to the controller **200**. The dipper motion command input devices **305** form a portion of the user interface **210** and include a crowd motion command input **305***a*, a hoist motion command input **305***b*, and a swing motion command input **305***c*. Each of the crowd motion command input **305***a*, hoist motion command input **305***b*, and swing motion command input **305***c* may be referred to generically as a dipper motion command input device **305** or collectively as the dipper motion command input devices **305**. Each of the dipper motion command input devices **305** is a human-machine interface (HMI) device that allows an operator to input a motion command to ultimately maneuver a position of the dipper **34**. For example, each of the dipper motion command input devices **305** may include a human-manipulatable control element, such as a joystick or lever, that generates an output signal provided to the controller **200** indicative of the requested movement of the control element. The electronic processor **250** of the controller **200** receives the output signals from the dipper motion command input devices **305** and translates the signals to corresponding motion commands for the dipper drives **310**. The corresponding motion commands may be in the form of a speed command, torque command, or another form.

[0047] The dipper drives **310** include the crowd drive **215**, the hoist drive **220**, and the swing drive **225** that are also illustrated in FIG. **3**A. Each of the crowd drive **215**, the hoist drive **220**, and the swing drive **225** may be referred to generically as a dipper drive **310** or collectively as the dipper drives **310**. Each of the dipper drives **310** may include a drive controller and motor or other actuator to control a respective motion of the dipper. More specifically, and with reference to FIG. **2**, the crowd drive **215** controls the dipper **34** to crowd in and out by extending and retracting the handle **30**, the hoist drive **220** controls the dipper **34** to hoist up and down by winding the hoist rope **42** up and down, and the swing drive **225** controls the dipper to swing left and right by rotating the base **22** relative to the tracks **80** about the axis **84**. As noted, the motion commands from the controller **200** may be in the form of a speed command or torque command. As an example, in response to a speed command to the crowd drive **215**, which may include both a magnitude and direction component, the crowd drive **215** controls the dipper **34** to crowd at the requested speed in the requested direction by: (1) increasing the torque to a motor of the crowd drive **215** until the requested speed is reached, (2) decreasing the speed until the requested speed is reached by reducing the torque to the motor, controlling the motor to regeneratively brake, or driving the motor in reverse, and (3) maintaining the current torque to the motor when the speed is at the requested speed. As another example, in response to a torque command to the swing drive **225**, which may include both a magnitude and direction component, the swing drive **225** controls a motor of the swing drive **225** with torque at the requested magnitude and direction. In some embodiments, the crowd drive **215** and hoist drive **220** receive speed commands from the controller **200**, and the swing drive **225** receives torque commands.

[0048] In some embodiments, the dipper drives **310** implement closed loop feedback to control the respective motions of the dipper **34** according to the motion commands received from the controller **200**. The feedback (e.g., sensed speed or torque) may be provided to the dipper drives **310** from the sensors **240**, directly or via the controller **200**.

[0049] The dipper position sensors **315** include a crowd sensor **315***a*, a hoist sensor **315***b*, and a swing sensor **315***c*. The dipper position sensors **315** form a portion of the sensors **240** (see FIG. 3A) and include a crowd sensor **315***a*, a hoist sensor **315***b*, and a swing sensor **315***c*. Each of the crowd sensor **315***a*, hoist sensor **315***b*, and swing sensor **315***c* may be referred to generically as a dipper position sensor **315** or collectively as the dipper position sensors **315**. Each of the dipper position sensors **315** senses a position of the dipper in terms of a respective dipper motion. More specifically, and with reference to FIG. **2**, the crowd sensor **315***a* senses a crowd position, which is the extent to which the dipper **34** is crowded (e.g., between a minimum and maximum extension amount), the hoist sensor **315***b* senses a hoist position, which is the extent to which the dipper **34** is hoisted (e.g., between a minimum and maximum hoist amount), and the swing sensor **315** senses a swing position, which is the rotational position of the dipper **34** about the axis **84** (e.g., between 0 and 360 degrees). In some embodiments, the dipper position sensors **315** also indicate a speed, acceleration, or both speed and acceleration of the dipper **34** for the respective crowd, hoist, and swing motions in addition to the position data. In some embodiments, each of the dipper position sensors **315** includes a resolver configured to indicate a rotational position of an associated dipper drive **310** (e.g., the crowd sensor **315***a* includes a resolver to indicate the rotational position of a crowd motor of the crowd drive **215**). In some embodiments, the dipper position sensors **315** are non-contact sensors, such as Hall sensors or optical sensors, that sense the rotational position of an associated dipper drive **310**. In some embodiments, the controller **200** is configured to infer speed of each of the dipper drives **310** by calculating an amount of rotation of each of the dipper drives **310** over a period of time, using a timer circuit and the changing position data provided by the dipper position sensors **315**.

[0050] As also illustrated in FIG. 3B, the memory **255** further includes model data **325**, limit functions **330**, a crowd limit **335**, a hoist limit **340**, and a swing limit **345**. As explained in further detail below, the model data **325** may include a virtual model of the dipper **34**, a virtual model of the tracks **80**, a coordinate system for the shovel **10**, and position information for the shovel **10** within the coordinate system. Additionally, the limit functions **330** may define one or more virtual fields for the dipper **34**. As also explained in further detail below, the crowd limit **335**, hoist limit **340**, and swing limit **345** may limit a motion command provided by the controller **200** to the dipper drives **310** (e.g., to a level lower than requested by an operator).

[0051] In addition to virtual models of the dipper **34** and tracks **80**, the model data **325** may also include dimensional data associated with the dipper **34**, tracks **80**, and any other components of the rope shovel **10**. For example, the model data **325** may include dimensional data associated with the base **22**. Likewise the model data **325** may include dimensional data associated with a support structure of the dipper **34**, or dipper support **350** (see FIG. **4**), which is a combination of the rope shovel components that support movement and positioning of the dipper **34** (e.g., the boom **26**, handle **30**, etc.). The dimensional data for the various components of the rope shovel **10** may be, for example, a series of dimensions (e.g., lengths, widths, heights), points, and/or other definitions of the boundaries of the rope shovel components. For example, dimensional data associated with the dipper **34** may include information such as lengths of dipper edges, lengths of dipper cross-sections, distances between respective sides of and the center of dipper **34**, and the like. As another example, dimensional data associated with the dipper support **350** may include information such as a length of the boom **26**, a length of the handle **30**, a length of the rope **42**, size of the boom sheave **54**, and the like. As another example, dimensional data associate with the tracks **80** may include track width, track height, track curvature, and the like.

[0052] The controller **200** may also be referred to as a control system, such as a collision prevention and mitigation control system (e.g., when implementing the method **500**) or a virtual track modeling system (e.g., when implementing the method **800** described below with respect to FIG. **8**). In some embodiments, the above-described controller **200**, which includes, among other things, the electronic processor **250** and memory **255**, is implemented as one or more components of an aftermarket control system. In such embodiments, the aftermarket control system is configured to be installed in an existing mining machine, such as the rope shovel **10**, to provide additional control to the mining machine to which it is installed. When the aftermarket control system is installed in the rope shovel **10**, the controller **200** is coupled to and configured to control operation of the indicators **205**, the user-interface **210**, the tracks drive **227**, the database **230**, the power supply **235**, the one or more sensor(s) **240**, the dipper motion command input devices **305**, dipper drives **310**, and dipper position sensors **315**. That is, when the aftermarket control system is installed in the rope shovel **10**, the controller **200** included in the aftermarket control system is operable to control operation of any of the above-described components of the rope shovel **10**. In some embodiments, one or more of above-described components of the rope shovel **10** are included in the aftermarket control system. For example, the database **230**, the tracks drive **227**, the one or more sensors **240**, and/or the dipper drive **310** may be included as components of the aftermarket control system.

[0053] FIG. **4** illustrates a top-down schematic view of the rope shovel **10**. As shown in FIG. **4**, a local coordinate system **400** for the rope shovel **10** may be defined with respect to a point on or near the rope shovel **10**. That is, a point on or near the rope shovel **10** may be used as a reference point, or origin, of the rope shovel's local coordinate system **400**. In the illustrated embodiment, an origin **405** of the rope shovel's local coordinate system **400** is defined as a center point of the of the rope shovel tracks **80**, hereinafter referred to as "track center **405**." In other embodiments, other points on or near the rope shovel **10** may be defined as the origin of the local coordinate system **400**. In addition, the local coordinate system **400** of the rope shovel **10** is illustrated and described herein as a cartesian coordinate system including an x-axis, a y-axis, and a z-axis. Therefore, a position, or point, within the local coordinate system **400** includes an x-component, a y-component, and a z-component. With respect to FIG. **4**, the x-component of a point in the local coordinate system **400** indicates how far "right" or "left" the point is relative to the track center **405**. Similarly, the y-component of a point represents how far "frontward" or "rearward" the point is relative to the track center **405**. Likewise, the z-component of a point represents how far "above (out of page)" or "below (into page)" the point is relative to the track center **405**. Although illustrated and described as a cartesian coordinate system, the local coordinate system **400** may additionally or alternatively be defined as a cylindrical coordinate system, spherical coordinate system, or any other coordinate system that is desired.

[0054] The electronic processor **250** may be configured to determine the position, or (x, y, z) coordinates, of a point on the rope shovel **10** relative to the track center **405**, based on a combination of one or more sensor readings and/or the dimensional data stored in memory **255**. The sensor readings used to determine the coordinates of a point on the rope shovel **10** may include, but are not limited to, readings generated by the dipper position sensors **315**. The dimensional data used to determine the coordinates of a point on the rope shovel **10** may include, but is not limited to, dimensional data associated with the base **22**, dipper **34**, tracks **80**, and dipper support **350**.

[0055] As an example, positions of one or more of the reference points associated with the dipper **34**, or dipper reference points **410**, shown in FIG. **4** may be determined relative to the track center **405**. The dipper reference points **410** include, but are not limited to, a dipper center **410***a*, a front right dipper vertex **410***b*, a rear right dipper vertex **410***c*, a front left dipper vertex **410***d*, and a rear left dipper vertex **410***e*. Although FIG. **4** is a two-dimensional schematic drawing, it can be assumed that the dipper reference points **410***a*-**410***e* are located on a bottom surface of the dipper **34**. That is, the dipper center **410***a* is the center of a bottom surface of the dipper. Similarly, the dipper vertices **410***b*-**410***e* are vertices that join the bottom surface of the dipper to the side surfaces of the dipper **34**. The dipper reference points **410***a*-**410***e* collectively form a virtual dipper model **412**, which is a virtual model of the dipper **34** (stored as part of the model data **325** of FIG. 3B). Although the virtual dipper model **412** is two-dimensional in the illustration of FIG. **4**, in some embodiments, the virtual dipper model **412** is three-dimensional and defined by additional reference points. For example, in some embodiments, the virtual dipper model **412** is defined in a computer aided design (CAD) program with sufficient resolution to appear, when plotted, as the dipper **34** in FIG. **1**. In some embodiments, a lower resolution model is used as the virtual dipper model **412**.

[0056] The electronic processor **250** may be configured to determine respective sets of (x, y, z) coordinates for each dipper reference point making up the virtual dipper model **412** (e.g., the reference points **410***a*-**410***e*) based on a combination of the dimensional data stored in memory **255** and swing, crowd, and hoist measurements taken by the dipper position sensors **315**. When the dipper **34** is moved to a new position, the electronic processor **250** is operable to determine a new respective set of (x, y, z) coordinates for each one of the dipper reference points **410***a*-**410***e* based on a combination of the dimensional data and updated values of the swing, crowd, and hoist measurements taken by the dipper position sensors **315**. Therefore, the electronic processor **250** may be configured to determine the position of a dipper reference point **410** relative to the track center **405** regardless of the extent to which the dipper **34** is hoisted, crowded, or rotated.

[0057] Although described with respect to the dipper reference points **410***a*-**410***e*, the electronic processor **250** may also be configured to determine a set of (x, y, z) coordinates, or a position relative to the track center **405**, for any point on or near a component of the rope shovel **10**. For example, the electronic processor **250** may be configured to determine the (x, y, z) coordinates of a point on a surface of the boom **26** or a point on the surface of the handle **30**. In addition, as will be described in more detail below, the electronic processor **250** may be configured to derive, or determine, (x, y, z) coordinates of a point on a surface of the tracks **80** based on the (x, y, z) coordinates of a dipper reference point **410**. With respect to FIG. **4**, (x, y, z) coordinates of a point **415** located on the top surface of the front right vertex of track **80***a* may be determined by moving the dipper **34** such that a dipper reference point **410** is aligned with and/or contacts the point **415** on track **80***a*. For example, if it is assumed that the dipper center **410***a* is aligned with and/or contacting the point **415**, the electronic processor **250** may be configured to determine the (x, y, z) coordinates of the point **415** are equivalent to the (x, y, z) coordinates of the dipper center **410***a* while the dipper center **410***a* is aligned with and/or contacts the point **415**.

[0058] In some embodiments, the data defining the coordinate system **400** and position information for the shovel **10** on that coordinate system **400**, including the current positions for the various reference points making of the virtual model of the dipper **34** and the virtual model of the tracks **80**, including the swing position, crowd position, and hoist position of the dipper **34**, and including the position information for the dipper support **350**, may be stored as part of the model data **325**.

[0059] Preventing and Mitigating Collisions Between a Dipper and Tracks of a Mining Machine

[0060] FIG. **5** illustrates a method **500** for preventing and mitigating collisions between a dipper and tracks of a mining machine includes blocks **505**, **515**, and **520**. The method **500** is described with respect to the rope shovel **10**, dipper **34**, tracks **80**, and the electronic processor **250**; however, in some embodiments, the method **500** is implemented with respect to other rope shovels or mining machines having tracks and dippers with crowd, hoist, and swing motions. Additionally, although actions within the method **500** are described as being carried out by the electronic processor **250**, the actions may also be described, for example, as being carried out by the electronic controller **200** having the electronic processor **250**. Furthermore, in some embodiments, the controller **200** and electronic processor **250** implementing the method **500** are included in the rope shovel **10** as original equipment (e.g., installed at the time of manufacture of the rope shovel **10**) and, in some embodiments, one or more of the controller **200**, the electronic processor **250**, and the software included thereon are included in an aftermarket control system installed in the rope shovel **10** to implement the method **500**.

[0061] In block **505**, the electronic processor **250** receives dipper position data indicative of a position of the dipper **34**. The dipper position data is provided to the electronic processor **250** by one or more of the dipper position sensors **315**. For example, the dipper position data may include an output from one or more of the crowd sensor **315***a*, the hoist sensor **315***b*, and the swing sensor **315***c*. The output of the crowd sensor **315***a* indicates the crowd position of the dipper **34**, the hoist sensor **315***b* indicates the hoist position of the dipper **34**, and the swing sensor **315** indicates the swing position of the dipper **34**.

[0062] Returning to FIG. **5**, in block **515**, the electronic processor **250** sets a motion command limit for a dipper motion based on a distance between the dipper **34** and the tracks **80** of the mining machine **10** inferred from the dipper position data, where the dipper motion is selected from a group of a swing motion, a crowd motion, and a hoist motion. In some embodiments, to set the motion command limit based on the distance inferred from the dipper position data, the electronic processor **250** may determine a limit value using one or more of the limit functions **330** stored in the memory **255** (see FIG. 3B). For example, in some embodiments, the limit functions **330** include distance-based functions that define the motion command limit based on the distance between the dipper **34** and the tracks **80** such that they use the distance between the dipper **34** and the tracks **80** as an input and provide a limit value as an output. As another example, in some embodiments, the limit functions **330** include position-based functions that define the motion command limit based on the dipper position data, where such a position-based function is defined based on relationships between (i) potential dipper positions and (ii) associated distances between the potential dipper positions and the tracks **80** of the mining machine **10**. In other words, the distance between each potential position of the dipper **34** and the tracks **80** may be determined in advance (e.g., in a setup stage); then, at a later stage during operation, when the dipper **34** is determined to be at a particular position, the distance between the dipper **34** and the tracks **80** is presumed based on the prior determined relationship. The position-based function may be generated based on these underlying relationships between the position of the dipper **34** and the associated distance between the dipper **34** and the tracks **80** that results. Accordingly, the position-based functions use the current position of the dipper **34** indicated by the dipper position data as an input (and as a proxy for the distance between the dipper **34** and the tracks **80**) and provide a limit value as an output. Then, with continued reference to FIG. 3B, after determining the limit value, the electronic processor **250** may store the limit value in the memory **255** as the motion command limit (e.g., as one or more of the crowd limit **335**, hoist limit **340**, and swing limit **345**).

[0063] As noted, the distance between the dipper **34** and the tracks **80** may be used directly as an input into the limit function(s) or may be used indirectly in advance to generate the limit function(s) such that the current position of the dipper **34** may be used as an input into the limit function(s). In some embodiments, the electronic processor **250** determines a distance between the dipper **34** and the tracks **80** of the mining machine based on the dipper position data. In some embodiments, the distance may be a shortest distance between the dipper **34** and the tracks **80** (e.g., the distance between the two nearest points of the dipper **34** and the tracks **80**). The distance may be a length measurement across three dimensions of space (e.g., x, y, and z dimensions) and, accordingly, may be referred to as a three-dimensional distance.

[0064] FIG. **6** depicts a virtual model **600** of the rope shovel **10**, on the same local coordinate system **400** illustrated in FIG. **4**, to illustrate an example technique for determining the distance between the dipper **34** and the tracks **80**. In this example, to determine the distance, the electronic processor **250** determines a position of the dipper **34**, determines a position of the tracks **80**, and then determines a shortest distance between the dipper **34** and the tracks **80** based on the determined positions of each. In some embodiments, to determine the position of the dipper **34**, the electronic processor **250** determines a position of a three-dimensional virtual dipper model (a virtual model of the dipper **34**) in a three-dimensional coordinate system for the rope shovel **10** based on the dipper position data. More particularly, the electronic processor **250** may translate the dipper position data (received in the preceding block **505**) to calculate the position of the dipper **34** on the local coordinate system **400** for the rope shovel **10**. For example, the dipper position data may indicate the extent that the dipper **34** is hoisted, crowded, and rotated about the swing axis **84**, and the electronic processor **250** may extrapolate the position of the dipper **34** in the local coordinate system **400** using this information in combination with model data **325** (e.g., dimensional data associated with the dipper support **350**). Thus, as shown in FIG. **6**, the electronic processor **250** is configured to map, onto the local coordinate system **400**, a virtual model **605** of the dipper **34** at the extrapolated dipper position.

[0065] Like the virtual dipper model **412** of FIG. **4**, the virtual model **605** of the dipper **34** may be, for example, a series of dimensions, points, or other definition of the outer boundaries of the dipper **34**. The virtual model **605** of the dipper **34** may be obtained from a computer-aided drawing (CAD) file for the dipper **34**. In some embodiments, the model data **325**, including the virtual model **605** of the dipper **34** and dimensional data of the dipper support **350**, may be received and stored in the memory **255** in a setup stage. Although separately labeled in FIGS. **4** and **6**, respectively, the virtual dipper model **412** and the virtual model **605** may be the same virtual model.

[0066] Additionally, in some embodiments, to determine the position of the tracks **80**, the electronic processor **250** determines a position of a three-dimensional virtual tracks model (a virtual model of the tracks **80**) in the three-dimensional coordinate system (e.g., the local coordinate system **400**). As shown in FIG. **6**, the electronic processor **250** is configured to map, onto the local coordinate system **400**, a virtual model of the tracks **80** including a virtual tracks model **610***a* for tracks **80***a* and virtual tracks model **610***b* for track **80***b*. The virtual tracks models **610***a* and **610***b* may be collectively referred to as the virtual tracks model **610**, although the virtual tracks model **610** may also generically refer to just one of the virtual tracks models **610***a* or

610*b*. The virtual tracks model **610** and its position on the local coordinate system **400** may be received and stored in the memory **255** as part of the model data **325** in a setup stage. In some embodiments, the virtual tracks model **610** is, for example, a series of dimensions, points, or other definition of the outer boundaries of the tracks **80** (e.g., of one or both of the tracks **80***a* and **80***b*), defined with respect to an origin point of the three-dimensional coordinate system (e.g., origin **405** of the local coordinate system **400**). The virtual model of the tracks **80** (e.g., virtual tracks model **61**), and the position of the tracks **80** in the three-dimensional coordinate system, may be obtained from a computer-aided drawing (CAD) file for the tracks **80** or during a calibration process, such as described in further detail below (see, e.g., FIG. **8**). Accordingly, to determine the position of a three-dimensional virtual tracks model (e.g., the virtual tracks model **610**) in the three-dimensional coordinate system (e.g., the local coordinate system **400**), the electronic processor **250** may access such information in the model data **325** of the memory **255**.

[0067] With the positions of the dipper **34** and tracks **80** determined, the electronic processor **250** may then determine the distance between the dipper **34** and the tracks **80**. For example, in some embodiments, the electronic processor **250** may determine a shortest distance **615** between the virtual dipper model **605** and the virtual tracks model **610** on the three-dimensional coordinate system **400**, where the shortest distance represents the distance between the dipper **34** and the tracks **80** used in the method **500**. For example, as described above, the electronic processor **250** is configured to determine the position of three-dimensional models **605** and **610** of the dipper **34** and the tracks **80**, respectively, on the coordinate system **400**. The electronic processor **250** may then execute a nearest neighbor algorithm, or similar known algorithm, to determine the shortest distance **615** between the three-dimensional models **605** and **610** in the coordinate system **400**. As the distance is determined for two, three-dimensional models **605** and **610** in a three-dimensional coordinate system **400**, the distance is a length measurement across three dimensions (e.g., x, y, and z dimensions). This distance measurement across three dimensions (also referred to as a three-dimensional distance) contrasts with, for example, a length measurement in a two-dimensional coordinate system (e.g., that considers just crowd and hoist motions) or between two points in a one-dimensional coordinate system (e.g., that considers just crowd motion or just hoist motion).

[0068] In some embodiments, other techniques are implemented by the electronic processor **250** to determine the distance between the dipper **34** and the tracks **80**.

[0069] In some embodiments, the limit functions **330** include a slow region function and a stop region function for each of the crowd, hoist, and swing motions. In such embodiments, the electronic processor **250** may select the stop region function for a dipper motion in response to determining that the distance **615** is below a stop region threshold for that dipper motion, and may select the slow region function for a dipper function in response to determining that the distance **615** is above the stop region threshold, but below the slow region threshold for that dipper motion. In response to determining that the distance **615** is above the slow region threshold, the electronic processor **250** may return the default limit value for the motion command limit. In some embodiments, the slow region thresholds, stop region thresholds, and default limit values for each of the hoist, crowd, and swing motions are stored in the memory **255** (e.g., as part of the limit function **330**).

[0070] FIGS. **7**A-C illustrate an example of limit functions **330** for a dipper motion. More particularly, FIG. **7**A illustrates a slow region plot **700** of an example of a slow region function for the dipper motion, FIG. **7**B illustrates a stop region plot **705** of an example of a stop region function for the dipper motion, and FIG. **7**C illustrates a motion limit plot of a motion limit function resulting from a combination of the slow and stop region functions. The particular motion limit functions, thresholds, motion command limits, and distance values are merely examples. In other embodiments, one or more different functions, thresholds, limits, and values are employed in the method **500**.

[0071] In some embodiments, the slow region function (see plot **700** in FIG. **7**A) includes a function that receives a distance value as input and outputs a motion command limit, where the function defines an s-shaped curve. For example, in some embodiments, the slow region function includes an inverse tangent function, offset by a positive integer to align the bottom portion of the s-shaped curve with motion command limit of zero. In some embodiments of the slow region function (not shown in FIG. **7**A), the slow region is further divided into an s-shaped curve portion for lower values of the distance **615** and a linear portion for larger values of the distance **615**. In some embodiments, rather than an s-shaped curve, the slow region function is linear or is a curve of another shape (e.g., a parabolic function).

[0072] In the illustrated embodiment of FIG. **7**B, the stop region function (see plot **705**) provides a set value of about 10% regardless of the distance **615**. In some embodiments, the particular set value is a different value than illustrated, such as 0%, 2%, 5%, or 15%. In some embodiments, the stop region function of FIG. **7**B provides a set value that is negative (e.g., −5% or −10%) to provide reverse torque to the dipper **34** (i.e., in a direction that pushes the dipper **34** away from the tracks **80**).

[0073] FIG. **7**C illustrates the motion limit function (see plot **710**) resulting from a combination of the slow region function and the stop region function. As illustrated, the stop region function applies for "x" values (values of the distance **615**) that are less than a stop region threshold **720** and the slow region function applies for "x" values (values of the distance **615**) that are between the stop region threshold **720** and a slow region threshold **725**. When the distance value **615** is greater than the slow region threshold **725**, the motion command limit is a default value, such as 100%. As will become more apparent below, when at 100%, the motion command limit does not limit the dipper motion associated with the motion command limit.

[0074] In some embodiments, the limit functions of FIGS. **7**A-C are applicable for one or more of the hoist motion, the crowd motion, and the swing motion. In some embodiments, the particular thresholds, slopes of the limit curve in the slow region, and limit in the stop region may vary depending on the particular motion. For example, in some embodiments, the limit value for the stop region for the hoist motion, crowd motion, or both hoist and crowd motion is a non-zero value (e.g., 10%), whereas the limit value in the stop region for the swing motion may be set to zero (i.e., 0%). In some embodiments, the curve of the limit value for the slow region for one or more of the dipper motions has a different shape or is linear. In some embodiments, the swing motion has a stop region function, but does not have a slow region function. The swing motion may use a different limit function because, in some embodiments, the swing motor is not powerful enough in most cases to stop momentum of the dipper **34** swinging towards the tracks **80**. However, when the operator of the rope shovel **10** is maneuvering the dipper **34** near the tracks **80** (e.g., to clear a boulder near the tracks), the limit value (e.g., of zero) for the swing motion in the stop region will block a swing motion requested by the operator that may otherwise cause the dipper **34** to collide with the tracks **80**. Additionally, when an operator inadvertently is swinging the dipper **34** at an increased speed when the dipper enters the stop region, the limit value for the swing motion in the stop region (e.g., zero), may remove the torque from the swing motion so as to stop the swing torque moments before impact and avoid driving the swing motion even after the collision of the dipper **34** with the tracks **80**. Thus, although the collision may not be avoided, the resulting damage may be mitigated by blocking further swing torque when in the stop region.

[0075] In some embodiments, the limit functions **330** include one or more equations (e.g., defining the function illustrated in FIG. **7**C) that are computed during operation by the electronic processor **250** to generate a limit value as an output. In some embodiments, the limit functions **330** include one or more lookup tables that map potential inputs (e.g., shown on the x-axis of the function in FIG. **7**C) to pre-calculated outputs (e.g., shown on the y-axis of the function in FIG. **7**C). In some embodiments, the limit functions **330** include a combination of one or more equations and one or more lookup tables.

[0076] In block **520**, the electronic processor **250** controls the dipper motion according to a dipper motion command limited by the motion command limit. For example, in response to operator operation of one of the motion command input devices **305** (see FIG. **3**B), the electronic processor **250** receives a dipper motion command input (e.g., a hoist, crowd, or swing command input). The electronic processor **250** then determines the lower of (a) the motion command limit and (b) the dipper motion command input. The electronic processor **250** then provides a dipper motion command to the dipper drives **310** associated with the motion command limit (e.g., a hoist drive **220**), where the dipper motion command is the lower of (a) the motion command limit and (b) the dipper motion command input. The dipper drive **310** that receives the motion command then controls the dipper motion of the dipper **34** according to the command. For example, when the electronic processor **250** provides a crowd motion command to the crowd drive **215** to crowd in at 20% speed, the crowd drive **215** controls the dipper **34** to crowd in at 20% speed.

[0077] In some embodiments of the method **500**, in block **515**, rather than setting a motion command limit for one dipper motion, the electronic processor **250** sets a motion command limit for two or three dipper motions based on the distance between the dipper **34** and the tracks **80**, where the dipper motions are selected from the group of the swing motion, the crowd motion, and the hoist motion. In these embodiments, a similar process used to set the motion command limit for one dipper motion is used to set the dipper motion for the other dipper motions. For example, to set the motion command limits for the dipper motions, the electronic processor **250** may determine a limit value for each dipper motion using the distance between the dipper **34** and the tracks **80** (directly or indirectly) with one or more of the limit functions **330** stored in the memory **255** (see FIG. **3**B). The limit functions **330** may include a custom function (or functions) for each motion (e.g., a crowd limit function for the crowd motion, a hoist limit function for the hoist motion, and a swing limit function for the swing motion). Then, with continued reference to FIG. **3**B, the electronic processor **250** may store the respective limit values in the memory **255** as the crowd limit **335**, hoist limit **340**, and swing limit **345**. Accordingly, in these embodiments, in block **520**, the electronic processor **250** is configured to control the dipper motion of the dipper **34** according to dipper motion commands (e.g., crowd, hoist, and swing commands) limited by each of the crowd limit, hoist limit, and swing limit.

[0078] Stated another way, in some embodiments of the method **500**, the dipper motion is the crowd motion and motion command limit is a crowd motion command limit, and, in block **515**, the electronic processor **250** further sets one or both of: (a) a hoist motion command limit for the hoist motion based on the distance and (b) a swing motion command limit for the swing motion based on the distance. Then, in block **520**, the electronic processor **250** is configured to control the dipper motion of the dipper **34** according to dipper motion commands (e.g., crowd, hoist, and swing commands) limited by each of the crowd motion command limit, hoist motion command limit, and swing motion command limit.

[0079] In some embodiments, after block **520**, the electronic processor **250** loops back to block **505** such that the electronic processor **250** repeatedly executes the method **500**. By repeatedly executing the method **500**, the electronic processor **250** may account for changes over time in the position of the dipper **34** and in the dipper motion command received via the dipper motion command input device **305**. Thus, in some embodiments, the electronic processor **250** repeatedly determines the distance between the dipper **34** and the tracks **80** over time as the dipper **34** moves and updates the motion command limit based on the distance **615** as the distance **615** is repeatedly determined.

[0080] Accordingly, in some embodiments, in a first pass through method **500**, to set the motion command limit for the dipper motion based on the distance (in block **515**), the electronic processor **250** reduces the motion command limit from an initial value to a reduced value according to a function that defines the motion command limit to be lower as the distance **615** is reduced (e.g., according to the function for plot **710** in FIG. **7**C). Further, in a second pass through method **500** after the dipper **34** has moved further from the tracks **80**, the electronic processor **250** receives updated dipper position data indicative of an updated position of the dipper (block **505**); sets the motion command limit to an updated value based on an updated distance between the dipper **34** and the tracks **80** based on the updated dipper position data, where the updated distance is greater than the distance (from the first pass) and where the updated value is greater than the reduced value (block **515**); and controls the dipper motion according to a further dipper motion command limited by the updated motion command limit (block **520**).

[0081] To assist in illustrating the method **500**, several example scenarios in accordance with the plot **710** of FIG.

7C are provided in Table I, below. Table I is described with respect to a dipper motion generally, but applies to one or more of the hoist motion, crowd motion, and swing motion of a mining machine, such as the rope shovel **10**.

TABLE I

Scenario	Distance	Motion Command Limit	Dipper Motion Command Input	Dipper Motion Command
(1)	0.5 (m)	10%	75%	10%
(2)	0.5 (m)	10%	5%	5%
(3)	1.5 (m)	60%	75%	60%
(4)	1.5 (m)	60%	40%	40%
(5)	4.0 (m)	100%	75%	75%

[0082] In scenario 1, the distance **615** between the tracks **80** and the dipper **34** is 0.5 meters (m), and a dipper motion command input of 75% is received by the electronic processor **250**. Accordingly, with reference to FIG. **7**C, the dipper **34** is determined to be in the stop region, and the motion command limit is set to 10% (e.g., in block **515**). The electronic processor **250** then determines that the motion command limit (10%) is less than the dipper motion command input (75%), and, accordingly, sets the dipper motion command to the motion command limit 10%. The electronic processor **250** then provides the dipper motion command of 10% to the dipper drive **305** associated with the dipper motion command. As explained with reference to FIG. **3**B above, the dipper motion command may be a speed command (e.g., for the crowd or hoist motion) or a torque command (e.g., for the swing motion).

[0083] In scenario 2, the distance **615** between the tracks **80** and the dipper **34** is 0.5 meters (m), and a dipper motion command input of 5% is received by the electronic processor **250**. Accordingly, with reference to FIG. **7**C, the dipper **34** is determined to be in the stop region, and the motion command limit is set to 10% (e.g., in block **515**). The electronic processor **250** then determines that the dipper motion command input (5%) is less than the motion command limit of 10%, and, accordingly, sets the dipper motion command to the dipper motion command input. The electronic processor **250** then provides the dipper motion command of 5% to the dipper drive **305** associated with the dipper motion command.

[0084] In scenarios 3, 4, and 5 of Table I, the dipper motion command limit and dipper motion command are generated following a similar technique as explained with respect to scenarios 1 and 2 and, accordingly, are not explained in further detail.

[0085] As previously noted with respect to FIG. **3**B, in some embodiments, the crowd drive **215** and hoist drive **220** receive speed commands from the electronic processor **250**, whereas the swing drive **225** receives a torque command from the electronic processor **250**. Accordingly, considering scenario 1 for the crowd drive **215** as an example, when the electronic processor **250** provides the dipper motion command of 10% to the crowd drive **215**, the crowd drive **215** uses a closed loop feedback speed control to control the speed of the crowd drive **215** to be at 10%. Now, considering scenario 1 for the swing drive **225** as an example, when the electronic processor **250** provides the dipper motion command of 10% to the swing drive **225**, the swing drive **225** uses a closed loop feedback torque control to control the torque being applied to the swing drive **225** to be at 10%. In some embodiments, to control the speed or torque of a drive, a controller of the dipper drive **310** may adjust a duty cycle of a pulse width modulated (PWM) signal used to control switching elements of the dipper drive **310** that provide power to a rotor or stator of a motor of the dipper drive **310**. For example, to increase torque or speed, the duty cycle, which may be a value between 0 and 100%, is increased, whereas to decrease the torque or speed, the duty cycle may be reduced. Additionally, as previously noted, to reduce the speed of a dipper drive **310**, the controller of the dipper drive **310** may implement regenerative braking (e.g., by selectively controlling switching elements of the dipper drive **310** to generated regenerative current) or may drive the dipper drive **310** in reverse (e.g., by selectively controlling switching elements of the dipper drive **310** to provide reverse torque).

[0086] In light of the above discussion, it should be apparent that, as the dipper **34** is controlled to be closer to the tracks **80**, as a general rule, the motion commands are further limited. As a result, in some embodiments, when the dipper **34** is very close to the tracks **80**, one or more of the dipper motions are restricted such that the dipper **34** moves slowly or not at all in response to motion command inputs from an operator. Additionally, in some embodiments, when the dipper **34** is controlled to crowd in (or hoist down) quickly by the operator towards the tracks **80**, the electronic processor **250** will limit the crowd (or hoist) motion command more and more such that the dipper **34** is gradually slowed to prevent a collision with the tracks **80** or at least mitigate the impact of a collision with the tracks **80**.

[0087] In some embodiments, the motion limits described with respect to the method **500** of FIG. **5** apply regardless of the direction of the particular dipper motion. For example, when the electronic processor **250** determines that the command motion limit for the crowd drive **215** is 10%, that 10% limit on the crowd motion is applied regardless of whether the dipper **34** is being commanded to crowd in or to crowd out. In some embodiments, particularly for the hoist and crowd motions, the motion limits apply in only one direction. For example, when the electronic processor **250** determines that the command motion limit for the crowd drive **215** is 10%, that 10% limit on the crowd motion is applied when the dipper **34** is being commanded to crowd in (towards the tracks **80**), but the limit is not applied when the dipper **34** is being commanded to crowd out.

[0088] In effect, at least in some embodiments, the limit functions **330** of the rope shovel **10** define virtual three-dimensional fields around the dipper **34** for each of the swing, crowd, and hoist dipper motions. When one or more of these virtual fields of the dipper **34**, which may be mapped onto the coordinate system **400** around the virtual dipper **605**, overlaps the virtual tracks model **610**, the one or more dipper motions associated with the one or more overlapping virtual fields is limited. These dipper motions are increasingly limited the closer that the dipper **34** is to the tracks **80**. Accordingly, the increasing limitations imposed by the electronic processor **250** as the overlapping virtual fields of the dipper **34** get closer to the tracks **80** are perceived like the repelling forces of the ends of two magnets having the same pole. That is, as the same pole of two magnets approach one another, the repelling force of the magnetic fields increases. From the perspective of an operator of the shovel **10**, the limit functions are smoothly applied in a natural and intuitive manner that does not inhibit productivity. Further, because, at least in some embodiments, the limit functions are applied independently to each of the dipper motions (hoist, crowd, and swing), limits are not placed on dipper motions unnecessarily. For example, if the dipper **34** is close enough to the tracks such that the virtual field for the crowd and hoist motions overlap the tracks **80**, but the virtual field for the swing motion does not overlap the tracks **80**, the operator is able to continue to control the dipper **34** to swing without limitation.

[0089] Modeling Tracks of a Mining Machine

[0090] As described above with respect to method **500**, a virtual model of the tracks **80** used in the collision prevention and mitigation system may be obtained during a calibration process for modeling tracks of a mining machine. FIG. **8** illustrates a method **800** for modeling tracks of a mining machine and includes blocks **805**, **810**, **815**, **820**, and **825**. The method **800** is described with respect to the rope shovel **10**, dipper **34**, tracks **80**, and electronic processor **250**; however, in some embodiments, the method **800** is implemented with respect to other rope shovels or other mining machines having tracks. Additionally, although actions within the method **800** are described as being carried out by the electronic processor **250**, the actions may also be described, for example, as being carried out by the electronic controller **200** having the electronic processor **250**. Furthermore, in some embodiments, the controller **200** and electronic processor **250** implementing the method **800** are included in the rope shovel **10** as original equipment (e.g., installed at the time of manufacture of the rope shovel **10**) and, in some embodiments, one or more of the controller **200**, the electronic processor **250**, and the software included thereon are included in an aftermarket control system installed in the rope shovel **10** to implement the method **800**.

[0091] In block **805**, the electronic processor **250** moves the dipper **34** to a first position associated with the tracks **80** of the rope shovel **10**. For example, using the dipper motion command input devices **305**, a rope shovel operator may input a command for moving the dipper **34** to the first position associated with the tracks **80**. The electronic processor **250** receives the operator input signals from the dipper motion command input devices **305** and translates the signals to corresponding motion commands for the dipper drives **310**. In response to receiving the motion commands from the electronic processor **250**, the dipper drives **310** control movement of the dipper **34** to the first position associated with the tracks **80**.

[0092] In some embodiments, the first position associated with the tracks **80**, or first track position, is located near a front end of the tracks **80**. For example, as shown in FIGS. **9** and **10**A, the first track position may be a first track position **900***a* located at the vertex that joins the front, top, and right (outer) surfaces of the right track **80***a*, hereinafter referred to as "front-top-right vertex of right track **80***a*." It should be understood that the first track position **900***a* is provided as an exemplary first track position, and the first track position may be located at any other point on or near the right track **80***a*. For example, the first track position may be located at a middle portion or rear end of the right track **80***a*. Furthermore, the first track position need not necessarily be located at a point on or near the right track **80***a*. For example, the first track position may be located a point on or near the left track **80***b*. In some embodiments, the first track position may be located in between, in front of, behind, or outside of the tracks **80**.

[0093] Moving the dipper **34** to the first track position **900***a* may include aligning and/or contacting the first track position **900***a* with a specific point on the surface of the dipper **34**. For example, the electronic processor **250** may be configured to move the dipper **34** such that one of the dipper reference points **410** is aligned with and/or contacting the first track position. As shown in FIG. **10**A, the dipper **34** is moved to the first track position **900***a* such that the dipper center **410***a* is aligned with and contacting the front-top-right vertex of right track **80***a* while the dipper **34** is located at the first track position **900***a*. Although illustrated and described with respect to the dipper center **410***a*, it should be understood that any of the dipper reference points **410** may be used to align and/or contact the first track position **900***a* with the dipper **34**. For example, the electronic processor **250** may alternatively be configured to align and/or contact front-top-right vertex of right track **80***a* with the front right dipper vertex **410***b*, the rear right dipper vertex **410***c*, the front left dipper vertex **410***d*, the rear left dipper vertex **410***e*, or any other reference point defined on a surface of the dipper **34**.

[0094] In block **810**, the electronic processor **250** determines a first data point associated with, or indicative of, the first track position **900***a*. The first data point may include, but is not limited to, one or more measurements taken by the dipper position sensors **315** while the dipper **34** is located at the first track position **900***a*. For example, the electronic processor **250** may determine, based on measurements taken by the dipper position sensors **315**, the extent to which the dipper **34** is crowded, the extent to which the dipper **34** is hoisted, and/or the rotational position of the dipper **34** while the dipper **34** is located at the first track position **900***a*. The crowd, hoist, and rotation measurements taken by the dipper position sensors **315** may be included in and/or stored in association with the first data point.

[0095] In addition, the electronic processor **250** may be configured to determine a set of (x, y, z) coordinates representing the first track position **900***a*, which may be included and/or stored in association with the first data point. As described above with respect to the rope shovel's local coordinate system **400**, the electronic processor **250** may be configured to determine, or derive, the (x, y, z) coordinates of a point on or near the tracks **80** based on the (x, y, z) coordinates of a particular dipper reference point **410**. Therefore, the (x, y, z) coordinates of the first track position **900***a* may be derived from the (x, y, z) coordinates of a particular dipper reference point **410** while the dipper **34** is located at the first track position **900***a*.

[0096] With respect to the FIGS. **9** and **10**A, the electronic processor **250** may be configured to determine the (x, y, z) coordinates of the first track position **900***a*, which is the point located on top of the front-top-right vertex of right track **80***a*, by determining the (x, y, z) coordinates of a dipper reference point **410** that is aligned with and/or contacting the front-top-right vertex of right track **80***a*. For example, as shown in FIG. **10**A, the dipper center **410***a* is aligned with and contacting the front-top-right vertex of right track **80***a* while the dipper **34** is located at the first track position **900***a*. Therefore, the electronic processor **250** may be configured to determine that the (x, y, z) coordinates of the first track position **900***a* are equal to the (x, y, z) coordinates of the dipper center **410**_a_ while the dipper center **410**_a_ contacts the front-top-right vertex of right track **80**_a_. Accordingly, after the electronic processor **250** determines the (x, y, z) coordinates of the first track position **900**_a_, the (x, y, z) coordinates of the first track position **900**_a_ may be included in and/or stored in association with the first data point.

[0097] Although the (x, y, z) coordinates of the first track position **900**_a_ are illustrated and described as being equivalent to the (x, y, z) coordinates of the dipper center **410**_a_, it should be understood that (x, y, z) coordinates of the first track position **900**_a_ may be derived from any of the respective (x, y, z) coordinates of the dipper reference points **410**. For example, if the front right vertex **410**_b_ of the dipper is aligned with and/or contracting the front-top-right of right track **80**_a_, the electronic processor may be configured to determine that the (x, y, z) coordinates of the first track position **900**_a_ are equivalent to the (x, y, z) coordinates of the front right dipper vertex **410**_b_. In other instances, the electronic processor **250** may derive the (x, y, z) coordinates of the first track position **900**_a_ from the respective (x, y, z) coordinates of the rear right dipper vertex **410**_c_, the front left dipper vertex **410**_d_, the rear left dipper vertex **410**_e_, or any other reference point defined on a surface of the dipper **34**.

[0098] In block **815**, the electronic processor **250** moves the dipper **34** to a second position associated with the tracks **80** of the rope shovel **10**. For example, using the dipper motion command input devices **305**, a rope shovel operator may input a command for moving the dipper **34** to the second position associated with the tracks **80**. The electronic processor **250** receives the operator input signal the dipper motion command input devices **305** and translates the signals to corresponding motion commands for the dipper drives **310**. In response to receiving the motion commands from the electronic processor **250**, the dipper drives **310** control movement of the dipper **34** to the second position associated with the tracks **80**.

[0099] In some embodiments, the second position associated with the tracks **80**, or second track position, is located near a rear end of the tracks **80**. For example, as shown in FIGS. **9** and **10**B, the second track position may be a second track position **900**_b_ located at the vertex that joins the rear, top, and right (outer) surfaces of the right track **80**_a_, hereinafter referred to as "rear-top-right vertex of right track **80**_a_." It should be understood that the second track position **900**_b_ is provided as an exemplary second track position, and the second track position may be located at any other point on or near the right track **80**_a_. For example, in some instances, the second track position may be located at a middle portion or front end of the right track **80**_a_. Furthermore, the second track position need not necessarily be located at point on or near the right track **80**_a_. For example, the second track position may be located at a point on or near the left track **80**_b_. In some embodiments, the second track position is chosen based on the location of the first track position. For example, if the first track position is located at or near a front end of the tracks **80**, the second track position may be chosen to be located at or near a middle portion or rear end of the tracks **80**. In some embodiments, the second track position may be located in between, in front of, behind, or outside of the tracks **80**.

[0100] Moving the dipper **34** to the second track position **900**_b_ may include aligning and/or contacting the second track position **900**_b_ with a specific point on the surface of the dipper **34**. For example, the electronic processor **250** may be configured to move the dipper **34** such that one of the dipper reference points **410** is aligned with and/or contacting the second track position **900**_b_. As shown in FIG. **10**B, the dipper **34** is moved to the second track position **900**_b_ such that the dipper center **410**_a_ is aligned with and contacting the rear-top-right vertex of right track **80**_a_ while the dipper **34** is located at the second track position **900**_b_. Although illustrated and described with respect to the dipper center **410**_a_, it should be understood that any of the dipper reference points **410** may be used to align and/or contact the second track position **900**_b_ with the dipper **34**. For example, the electronic processor **250** may alternatively be configured to align and/or contact the rear-top-right vertex of right track **80**_a_ with the front right dipper vertex **410**_b_, the rear right dipper vertex **410**_c_, the front left dipper vertex **410**_d_, the rear left dipper vertex **410**_e_, or any other reference point defined on a surface of the dipper **34**.

[0101] In block **820**, the electronic processor **250** determines a second data point associated with, or indicative of, the second track position **900**_b_. The second data point may include, but is not limited to, one or more measurements taken by the dipper position sensors **315** while the dipper **34** is located at the second track position **900**_b_. For example, the electronic processor **250** may determine, based on measurements taken by the dipper position sensors **315**, the extent to which the dipper **34** is crowded, the extent to which the dipper **34** is hoisted, and/or the rotational position of the dipper **34** while the dipper **34** is located at the second track position **900**_b_. The crowd, hoist, and rotation measurements taken by the dipper position sensors **315** may be included in and/or stored in association with the second data point.

[0102] In addition, the electronic processor **250** may be configured to determine a set of (x, y, z) coordinates representing the second track position **900**_b_, which may be included and/or stored in association with the second data point. As described above with respect to the rope shovel's local coordinate system **400**, the electronic processor **250** may be configured to determine, or derive, the (x, y, z) coordinates of point on or near the tracks **80** based on the (x, y, z) coordinates of a particular dipper reference point **410**. Therefore, the (x, y, z) coordinates of the second track position **900**_b_ may be derived from the (x, y, z) coordinates of a particular dipper reference point **410** while the dipper **34** is located at the second track position **900**_b_.

[0103] With respect to FIGS. **9** and **10**B, the electronic processor **250** may be configured to determine the (x, y, z) coordinates of the second track position **900**_b_ by determining the (x, y, z) coordinates of a dipper reference point **410** that is aligned with and/or contacting the rear-top-right vertex of right track **80**_a_. For example, as shown in FIG. **10**B, the dipper center **410**_a_ is aligned with and contacting the top of the rear-top-right vertex of right track **80**_a_ while the dipper **34** is located at the second track position **900**_b_. Therefore, the electronic processor **250** may be configured to determine that the (x, y, z) coordinates of the second track position **900**_b_ are equal to the (x, y, z) coordinates of the dipper center **410**_a_ while the dipper center **410**_a_ contacts the rear-top-right vertex of right track **80**_a_. Accordingly, after the electronic processor **250** determines the (x, y, z) coordinates of the second track position **900**_b_, the (x, y, z) coordinates of the second track position **900**_b_ may be included in and/or stored in association with the second data point.

[0104] Although the (x, y, z) coordinates representing the second track position **900***b* are illustrated and described as being equivalent to the (x, y, z) coordinates of the dipper center **410***a*, it should be understood that (x, y, z) coordinates of the second track position **900***b* may be derived from any of respective set of (x, y, z) coordinates representing the dipper reference points **410**. For example, if the front right vertex **410***b* of the dipper is aligned with and/or contracting the rear-top-right vertex of right track **80***a*, the electronic processor **250** may be configured to determine that the (x, y, z) coordinates of the second track position **900***b* are equivalent to the (x, y, z) coordinates of the front right dipper vertex **410***b*. In other instances, the electronic processor **250** may derive the (x, y, z) coordinates of the second track position **900***b* from the respective (x, y, z) coordinates of the rear right dipper vertex **410***c*, the front left dipper vertex **410***d*, the rear left dipper vertex **410***e*, or any other reference point defined on a surface of the dipper **34**.

[0105] In block **825**, the electronic processor **250** generates a virtual model of the tracks **80** based on the first and second data points. For example, the electronic processor **250** may be configured to extrapolate virtual boundaries of the tracks **80** from the data included in the first and second data points. The virtual boundaries of the tracks **80** collectively form the virtual model of the tracks **80** and define a three-dimensional volume representing the tracks **80** in the rope shovel's local coordinate system **400**. In some embodiments, the electronic processor **250** may be further configured to combine the first and second data points with dimensional data stored in memory **255** when extrapolating virtual boundaries of the tracks **80**.

[0106] In some embodiments, the electronic processor **250** may be configured to define a virtual track boundary as one or more points within the local coordinate system **400** that represent and/or are otherwise extrapolated from the coordinates representing the first and second track positions. In such embodiments, the electronic processor **250** may be configured to generate a virtual model of the tracks **80** that is defined by the one or more boundary points extrapolated from the coordinates representing the first and second track positions. In some embodiments, the electronic processor **250** may be configured to define a virtual track boundary as a one or more line segments within the local coordinate system **400** that intersect, or are otherwise extrapolated from, the coordinates of the first and/or second track positions. In such embodiments, the electronic processor **250** may be configured to generate a virtual model of the tracks **80** that is defined by the intersection or joining of the line segments representing virtual track boundaries. In some embodiments, the electronic processor **250** may be configured to define a virtual track boundary as one or more arcs within the local coordinate system **400** that intersect, or are otherwise extrapolated from, the coordinates representing the first and/or second track positions. In such embodiments, the electronic processor **250** may be configured to generate a virtual model of the tracks **80** that is defined by the intersection or joining of the arcs representing virtual track boundaries. In some embodiments, the electronic processor **250** is configured to define a virtual track boundary as one or more curves (e.g., a line, a parabola, an ellipse, a circle, etc.) within the local coordinate system **400** that intersect, or are otherwise extrapolated from, the coordinates representing the first and/or second track positions. In such embodiments, the electronic processor **250** may be configured to generate a virtual model of the tracks **80** that is defined by the intersection of curves representing virtual track boundaries. In some embodiments, the electronic processor **250** may be configured to define a virtual track boundary as being a plane within local coordinates system **400** that intersects, or is otherwise extrapolated from, the coordinates representing the first and/or second track positions within the local coordinate system **400**. In such embodiments, the electronic processor **250** may be configured to generate a virtual model of the tracks **80** that is defined by the intersection of planes representing virtual track boundaries. In some embodiments, the electronic processor **250** may be configured to define a virtual track boundary as a combination of one or more points, line segments, arcs, curves, and/or planes within the local coordinate system **400** that intersect, or are otherwise extrapolated from, the coordinates representing the first and/or second track positions within the local coordinate system **400**. In such embodiments, the electronic processor **250** may be configured to generate a virtual model of the tracks **80** that is defined by the intersection of points, line segments, arcs, curves, and/or planes representing virtual track boundaries. It should be understood that the above described examples of defining track boundaries are not limiting, as the electronic processor **250** may be configured to define virtual track boundaries using alternative means. Furthermore, it should be understood that the electronic processor **250** may be further configured to use the dimensional data stored in memory **255** in combination with the first and second data points when generating the virtual track boundaries.

[0107] FIG. **11** illustrates a perspective view of a virtual model of the tracks **80**, or track model **1100**, generated by electronic processor **250** according to some embodiments. In particular, FIG. **11** illustrates a virtual model of the right track **80***a*, or right track model **1100***a*, and a virtual model of the left track **80***b*, or left track model **1100***b*. As will be described in more detail below, the electronic processor **250** may be configured to extrapolate virtual boundaries from the data points associated with the first and second track positions **900***a*, **900***b* when generating the track model **1100**. It should be understood that the track model **1100** illustrated in FIG. **11** and described herein is just one example of a virtual model of the tracks **80** that may be generated by electronic processor **250**, and various other embodiments of virtual track models may be generated by the electronic processor **250**. Furthermore, it should be understood that the below described process for extrapolating virtual boundaries from the first and second data points is just one example as to how the electronic processor **250** may be configured to extrapolate virtual boundaries from the data points associated with the first and second track positions **900***a*, **900***b*. Accordingly, in other embodiments, the electronic processor **250** may be configured to employ additional or alternative processes for extrapolating virtual track boundaries when generating a virtual model of the tracks **80**.

[0108] With reference to FIG. **11**, the first track position **900***a* and the second track position **900***b* are represented as points in the rope shovel's local coordinate system **400**. In particular, the first track position **900***a* is represented as a point having a first set of cartesian coordinates, (x_a, y_a, z_a), which were determined by the electronic processor **250** at step **810** of the track modeling method **800**. Similarly, the second track position **900***b* is represented as a point having a second set of cartesian coordinates, (x_b, y_b, z_b), which were determined by the electronic processor **250** at step **820** of the track modeling method **800**.

[0109] As shown in FIG. **11**, the electronic processor **250** may be configured to generate right and left track models **1100***a*, **1100***b* that are generally box-shaped. In particular, the electronic processor **250** may be configured to generate a box-shaped right track model **1100***a* that is defined by eight boundary vertices. As described above with respect to steps **805** and **810**, the first track position **900***a* is located at a vertex that joins the front, top, and right (outer) surfaces of the right track **80***a*. Thus, when generating the virtual track model, the electronic processor **250** may be configured to define the first track position **900***a* as the boundary vertex that joins the front, top, and right surface of the right track model **1100***a*. As shown in FIG. **11**, the first track position **900***a* is the vertex that joins the front surface **1105**, the top surface **1110**, and the right surface **1115** of the right track model **1100***a*. Similarly, as described above with respect to steps **815** and **820**, the second track position **900***b* is located at a vertex that joins the rear, top, and right (outer) surfaces of the right track **80***a*. Thus, as shown in FIG. **11**, the electronic processor **250** may be configured to define the second track position **900***b* as the boundary vertex that joins the rear surface **1120**, top surface **1110**, and right surface **1115** of the right track model **1100***a*.

[0110] The electronic processor **250** may be further configured to extrapolate the six remaining boundary vertices of the box-shaped right track model **1100***a* from the first set of cartesian coordinates representative of the first track position **900***a*, the second set of cartesian coordinates from the second track position **900***b*, and dimensional data associated with the tracks **80** that is stored in memory **255**.

[0111] For example, the electronic processor **250** may be configured to determine the cartesian coordinates of the boundary vertex that joins the front surface **1105**, bottom surface **1125**, and right surface **1115** of the right track model **1100***a* (hereinafter referred to as "front-bottom-right vertex **1130**") based on the first set of cartesian coordinates and a known height of the right track **80***a* that is stored in memory **255**. In particular, the electronic processor **250** may determine that the front-bottom-right vertex **1130** has the following set of cartesian coordinates: $(x_a, y_a, (z_a\text{–height}))$, where the z-component of the front-bottom-right vertex **1130** equals the difference between the z-component of the first track position **900***a* and the known height of right track **80***a*. Similarly, the electronic processor **250** may be configured to extrapolate the cartesian coordinates of the boundary vertex that joins the rear surface **1120**, bottom surface **1125**, and right surface **1115** of the right track model **1100***a* (hereinafter referred to as "rear-bottom-right vertex **1135**") based on the second set of cartesian coordinates and the known height of the right track **80***a*. In particular, the electronic processor **250** may determine that the rear-bottom-right vertex **1135** has the following set of cartesian coordinates: $(x_b, y_b, (z_b\text{–height}))$, where the z-component of the rear-bottom-right vertex **1135** equals the difference between the z-component of the second track position **900***b* and the known height of right track **80***a*.

[0112] The electronic processor **250** may be further configured to determine the cartesian coordinates of the boundary vertex that joins the front surface **1105**, top surface **1125**, and left surface **1140** of the right track model **1100***a* (hereinafter referred to as "front-top-left vertex **1145**") based on the first set of cartesian coordinates and a known width of the right track **80***a* that is stored in memory **255**. In particular, the electronic processor **250** may determine that the front-top-left vertex **1145** has the following set of cartesian coordinates: $((x_a\text{–width}), y_a, z_a)$, where the x-component of the front-top-left vertex **1145** equals the difference between the x-component of the first track position **900***a* and the known width of right track **80***a*. Similarly, the electronic processor **250** may be further configured to determine the cartesian coordinates of the boundary vertex that joins the rear surface **1120**, top surface **1125**, and left surface **1140** of the right track model **1100***a* (hereinafter referred to as "rear-top-left vertex **1150**") based on the second set of cartesian coordinates and the known width of the right track **80***a*. In particular, the electronic processor **250** may determine that the rear-top-left vertex **1150** has the following set of cartesian coordinates: $((x_b\text{–width}), y_b, z_b)$, where the x-component of the rear-top-left vertex **1150** equals the difference between the x-component of the first track position **900***a* and the known width of right track **80***a*.

[0113] In addition, the electronic processor **250** may be configured to determine the cartesian coordinates of the boundary vertex that joins the front surface **1105**, bottom surface **1125**, and left surface **1140** of the right track model **1100***a* (hereinafter referred to as "front-bottom-left vertex **1155**") based on the first set of cartesian coordinates, the known height of the right track **80***a*, and the known width of the right track **80***a*. In particular, the electronic processor **250** may determine that the front-bottom-left vertex **1155** has the following set of cartesian coordinates: $((x_a\text{–width}), y_a, (z_a\text{–height}))$. The x-component of the front-bottom-left vertex **1155** equals the difference between the x-component of the first track position **900***a* and the known width of right track **80***a*, and the z-component of the front-bottom-left vertex **1155** equals the difference between the z-component of the first track position **900***a* and the known height of right track **80***a*. Similarly, the electronic processor **250** may be further configured to determine the cartesian coordinates of the boundary vertex that joins the rear surface **1120**, bottom surface **1125**, and left surface **1140** of the right track model **1100***a* (hereinafter referred to as "rear-bottom-left vertex **1160**") based on the second set of cartesian coordinates, the known height of the right track **80***a*, and the known width of the right track **80***a*. In particular, the electronic processor **250** may determine that the rear-bottom-left vertex **1160** has the following set of cartesian coordinates: $((x_b\text{–width}), y_b, (z_b\text{–height}))$. The x-component of the rear-bottom-left vertex **1160** equals the difference between the x-component of the second track position **900***b* and the known width of right track **80***a* and the z-component of the rear-bottom-left vertex **1160** equals the difference between the z-component of the second track position **900***b* and the known height of right track **80***a*.

[0114] In view of the above, the right track model **1100***a* generated by the electronic processor **250** includes six boundary surfaces and eight boundary vertices, wherein each boundary surface is defined by a respective set, or group, of four boundary vertices. The front surface **1105** of the right track model **1100***a* is bound by the first track position **900***a*, the front-bottom-right vertex **1130**, the front-top-left vertex **1145**, and the front-bottom-left vertex **1155**. The top surface **1110** of the right track model **1100***a* is bound by the first track position **900***a*, the second track position **900***b*, the front-top-left vertex **1145**, and the rear-top-left vertex **1150**. The right surface **1120** of the right track model **1100***a* is bound by the first track position **900***a*, the second track position **900***b*, the front-bottom-right vertex **1130**, and the rear-bottom-right vertex **1135**. The rear surface **1120** of the right track model **1100***a* is bound by the second track position **900***b*, the rear-bottom-right vertex **1135**, the rear-top-left vertex **1150**, and the rear-bottom-left vertex **1160**. The bottom surface **1125** of the right track model **1125** is bound by the front-bottom-right vertex **1130**, the rear-bottom-right vertex **1135**, the front-bottom-left vertex **1155**, and the rear-bottom-left vertex **1160**. The left surface **1140** of the right rack model **1100***a* is bound by the front-top-left vertex **1145**, the rear-top-left vertex **1150**, the front-bottom-left vertex **1155**, and the rear-bottom-left vertex **1160**.

[0115] In some instances, the tracks **80** may have a curved shape (e.g., see side view of FIG. **2** and FIG. **18**). If a track **80** has a curved shape, the height of the front and/or rear ends of the track **80** may be less than the height of the middle portion of the track **80**. With respect to the example provided above, if the right track **80***a* is curved, the height of the front end of right track **80***a* may be less than the height at the middle portion of the right track **80***a*. Therefore, the electronic processor **250** may be configured to modify the right track model **1100***a* to accommodate for the differences in height between the middle and ends of right track **80***a*. For example, rather than the track model **1100***a* being defined by boundaries that are straight lines, one or more of the boundaries may have defined as a curved line. For example, the vertex connecting the first track position **900***a* and the second track position **900***b* may be a curved line having end points at positions **900***a* and **900***b*, and a midpoint with a height that is higher than the z coordinate of the position **900***a* or **900***b* by the known difference in height between the middle portion and end portions of the right track **80***a*. A similar curved line may serve as a vertex joining the points **1145** and **1150**. Alternatively, the electronic processor **250** may maintain the generally cuboid shape of the track model **1100***a* shown in FIG. **11**, but shift the boundary vertices of the right track model **1100***a* along the z-axis as a function of the difference in heights between the middle and ends of right track **80***a*. For example, if it is known that the height of the first track position **900***a* is half of the height of the middle portion of the track **80***a*, the electronic processor **250** may shift the right track model **1100***a* up the z-axis by a value equal to half of the height of the middle portion of right track **80***a*. Accordingly, the electronic processor **250** is operable to modify the virtual track model **1100** to accurately represent the right and left tracks **80***a*, **80***b*, even if the tracks **80** are curved.

[0116] If it can be assumed that the right track **80***a* is approximately equal in size to the left track **80***b*, the electronic processor **250** may be configured to generate the left track model **1100***b* by mirroring, or reflecting, the boundary vertices included in the right track model **1100***a* across the y-z plane of the local coordinate system **400**. In other words, if the right and left tracks **80***a*, **80***b* are approximately equal in size, the electronic processor **250** may be configured to define a set of boundary vertices for the left track model **1100***b* by flipping the signs of (e.g., changing from positive to negative) the x-components of the boundary vertices included in the right track model **1100***a*. For example, the cartesian coordinates of the front-top-left vertex of the left track model **1100***b*, $(-x_a, y_a, z_a)$, are determined by flipping the sign of the x-component included in the cartesian coordinates representing the first track position **900***a*.

[0117] Although the virtual track model **1100** is described in several embodiments herein as being generally box-shaped, in some embodiments, the virtual track model may be generated as a variety of different shapes. For example, as described above, the electronic processor **250** may be configured to generate a virtual track model that is any combination of one or more boundary points, line segments, arcs, curves, and/or planes that define a three dimensional volume representing the tracks **80**.

[0118] The virtual track model **1100** generated by electronic processor **250** may be used in the collision prevention and mitigation system described above with respect to method **500**. For example, the virtual track model **1100** may be generated and stored in the memory **255** as part of the model data **325**. Accordingly, the distance between the dipper **34** and the tracks **80** determined and used as part of the step **515** may include receiving the virtual track model **1100** from the memory **255**. In some embodiments, step **515** of the method **500** includes generating and using, by the electronic processor **250**, the virtual track model **1100** without storing the virtual track model **1100** in the memory **255**.

[0119] Referring back to generation of a virtual track model, in some instances, the right track **80***a* is not assumed to be approximately equal in size to the left track **80***b*. For example, the respective front ends of the right and left tracks **80***a*, **80***b* may be configured to be individually extended and/or retracted. Thus, at times, the right track **80***a* may be shorter than, the same length as, or longer than the left track **80***b*. Therefore, while performing the track modeling method **800**, the electronic processor **250** may be further configured to move the dipper **34** to a third track position and to determine a third data point associated with the third track position to accommodate for differences in track length.

[0120] FIG. **12** illustrates an embodiment of the rope shovel **10** in which the front end of left track **80***b* has been extended, making left track **80***b* longer than the right track **80***a*. Since the right and left tracks **80***a*, **80***b* have different lengths, the electronic processor **250** a virtual model of the left track **80***b* generated by mirroring a virtual model of the right track **80***a* across the y-z plane would be inaccurate. Thus, in some embodiments of the track modeling method **800**, the electronic processor **250** may be configured to move the dipper **34** to and determine respective data points indicative of three positions, **1200***a*, **1200***b*, and **1200***c*, associated with the tracks **80**. The first and second track positions **1200***a*, **1200***b* shown in FIG. **12** are similar to the first and second track positions **900***a*, **900***b* described herein. That is, the first track position **1200***a* is located at the front-top-right vertex of right track **80***a*, and the second track position **1200***b* is located at the rear-top-right vertex of right track **80***a*. As described above, the electronic processor **250** may determine a first data point that includes measurements taken by the dipper position sensors **315** while the dipper **34** is located at the first track position **1200***a* and a set of cartesian coordinates representing the first track position **1200***a*. Similarly, the electronic processor **250** may determine a second data point that includes measurements taken by the dipper position sensors **315** while the dipper **34** is located at the second track position **1200***b* and a set of cartesian coordinates representing the second track position **1200***b*.

[0121] Furthermore, the electronic processor **250** may be configured to move the dipper **34** to the third track position **1200***c* (e.g., after block **820** in the method **800** of FIG. **8**). As shown in FIG. **12**, the third track position **1200***c* is located at the front-top-left vertex of the left track **80***b*. While the dipper **34** is located at the third track position **1200***c*, the electronic processor **250** determines a third data point that includes measurements taken by the dipper position sensors **315** and a set of cartesian coordinates representing the third track position **1200***c*.

[0122] In these embodiments of the method **800**, in block **825**, the electronic processor **250** is operable to generate a virtual model of the tracks **80** using the first, second, and third data points associated with track positions **1200***a*-**1200***c*. In particular, by using the first data point associated with the first track position **1200***a* and the second data point associated with the second track position **1200***b*, the electronic processor **250** is operable to generate a right track model **1300***a* (FIG. **13**) in a manner that is similar to the above-described process used for generating the right track model **1100***a*. However, rather than mirroring the right track model **1300***a* across the y-z plane to generate a left track model, the electronic processor **250** is configured to generate the left track model **1300***b* based on the second data point associated with the second track position **1200***b* and the third data point associated with the third track position **1200***c*.

[0123] As shown in FIG. **13**, the third track position **1200***c* is represented as a coordinate point in the rope shovel's local coordinate system **400**. In particular, the third track position **1200***c* is represented as a point having the third set of coordinates, (x_c, y_c, z_c), which are included in the third data point determined by the electronic processor **250**. The third track position **1200***c* is located at the vertex joining the front, top, and left surfaces of the left track model **1300***b*, or the front-top-left boundary vertex of left track model **1300***b*. In a manner that is similar to the above-described process used for generating the virtual track model **1100**, the electronic processor **250** may be configured to extrapolate coordinates of the three remaining front boundary vertices (e.g., the front-top-right vertex, the front-bottom-left vertex, and the front-bottom-right vertex) of the left track model **1300***b* from the coordinates representing the third track position **1200***c*, (x_c, y_c, z_c).

[0124] In addition, in some embodiments (e.g., where the rear end of the tracks **80** cannot be individually extended or retracted), it may be assumed that the distance from the track center **405** to the rear-top-right vertex of right track **80***a* (e.g., the second track position **1200***b*) is equal to the distance from the track center **405** to the rear-top-left vertex of left track **80***b*. Accordingly, the electronic processor **250** may be configured to extrapolate the coordinates of the rear-top-left boundary vertex **1305** from the coordinates representing the second track position **1200***b*. In particular, the electronic processor **250** may derive the coordinates of the rear-top-left boundary vertex **1305**, $(-x_b, y_b, z_b)$, by flipping the sign of the x-component included in the second set of coordinates (x_b, y_b, z_b). In a manner that is similar to the process described above, the electronic processor **250** may be configured to extrapolate coordinates of the three remaining rear boundary vertices (e.g., the rear-top-right vertex, the rear-bottom-left vertex, and the rear-bottom-right vertex) of the left track model **1300***b* from the coordinates of the rear-top-left boundary vertex **1305**, $(-x_b, y_b, z_b)$. Therefore, the track modelling method **800** may be modified to generate a virtual model of tracks **80** that have varying lengths. Although described with respect to rope shovel tracks **80** having front ends that can be individually extended or retracted, it should be understood that the above described track modelling method may also be useful for generating tracks having rear ends that can be individually extended or retracted. Furthermore, it should be understood that the above described track modelling method may be used to generate a virtual model of tracks that cannot be individually extended or retracted. In such embodiments, the third data point associated with the third track position is redundant and provides for additional accuracy when generating the virtual track model.

[0125] In some embodiments, both the front end and the rear end of an individual track **80** may be configured to extend and retract. In such embodiments, the electronic processor **250** may not assume that the distance from the track center **405** to a point located on the rear surface of right track **80***a* is equal to the distance from the track center **405** to a corresponding point located on the rear surface of left track **80***b*. Rather, while performing the track modeling method **800**, the electronic processor **250** may be configured to generate a virtual track model based on four track positions to accommodate for differences in track length.

[0126] For example, four track positions **1400***a*-**1400***d* that may be used by the electronic processor **250** when generating a virtual track model are illustrated in FIG. **14**. As shown, the first track position **1400***a* is located at a front-top-right vertex of the right track **80***a* and the second track position **1400***b* is located at a rear-top-right vertex of the right track **80***a*. Similarly, the third track position **1400***c* is located at a front-top-left vertex of the left track **80***b* and the fourth track position **1400***d* is located at a rear-top-left vertex of the left track **80***b*. In a manner that is similar to the processes described above with respect to FIGS. **9**-**13**, the electronic processor **250** may be configured to determine respective data points indicative of each of the four track positions **1400***a*-**1400***d*. Furthermore, the electronic processor **250** may be configured to extrapolate virtual boundaries from the data points indicative of the track positions and **1400***a*-**1400***d* when generating a virtual model of the tracks **80** in a manner similar to the processes described above with respect to FIGS. **9**-**14**. Accordingly, the track modelling method **800** may be modified to generate a virtual model of rope shovel tracks **80** having front and rear ends that can be individually extended or retracted.

[0127] In some embodiments, the electronic processor **250** may be configured to generate a virtual track model based on data points associated with more than four track positions. In such embodiments, extrapolating virtual track boundaries from more than four track positions may provide for a more accurate track model than when compared to virtual track boundaries that are extrapolated from four or fewer track positions. For example, the track modeling method **800** may be modified such that the electronic processor **250** is configured to extrapolate virtual track boundaries from as many as five, six, eight, ten, twelve, or more track positions when generating a virtual track model. However, in some instances, the method **800** may require an excessive amount of time to complete if virtual track boundaries are extrapolated from too many positions associated with the tracks **80**. That is, moving the dipper **34** to and deriving data points from a large number of track positions before generating the virtual track model may be inefficient and not provide improved accuracy that is worth the additional time. Accordingly, to prevent the track modeling method **800** from requiring too much time to complete, it may be desirable to generate a virtual model of the tracks **80** that is derived from fewer than 12 positions associated with the tracks **80**. In some embodiments, it may be desirable to generate a virtual model of the tracks **80** that is derived from fewer than 10, 8, or 6 positions associated with the tracks **80**, or in a range between 3 to 6, 3 to 8, 3 to 10, 3 to 12, 4 to 6, 4 to 10, or 4 to 12 positions associated with the tracks **80**. These example ranges are inclusive of endpoints such that, for example, a range between 3 to 6 includes 3, 4, 5, and 6. As another example, six track positions **1500***a*-**1500***f* that may be used by the electronic processor **250** when generating a virtual track model are illustrated in FIG. **15**. The first four positions **1500***a*-**1500***d* are similar to the track positions **1400***a*-**1400***d* shown in FIG. **14**. That is, the first track position **1500***a* is located at a front-top-right vertex of the right track **80***a* and the second track position **1500***b* is located at a rear-top-right vertex of the right track **80***a*. Likewise, the third track position **1500***c* is located at a front-top-left vertex of the left track **80***b* and the fourth track position **1500***d* is located at a rear-top-left vertex of the left track **80***b*. However, an additional fifth track position **1500***e* is located at point on the right track **80***a* that is between the first position **1500***a* and the second position **1500***b*. In particular, the fifth track position **1500***e* is located at a midpoint along the right, or outer edge, of the right track **80***a*'s top surface. Similarly, an additional sixth track position **1500***f* is located at a midpoint along the left, or outer edge, of the left track **80***b*'s top surface.

[0128] Similar to the embodiments described above with respect to FIGS. **9-14**, the electronic processor **250** may be configured to determine respective data points associate with of each of the six track positions **1500***a*-**1500***e*. Furthermore, the electronic processor **250** may be configured to extrapolate virtual boundaries from the data points associated with the track positions **1500***a*-**1500***f* when generating a virtual model of the tracks **80**. It should be understood that the respective locations of the six track positions **1500***a*-**1500***f* are not limited to the locations illustrated shown in FIG. **15**. For example, the first four track positions **1500***a*-**1500***d* need not necessarily be located on the outer corners of the tracks **80**. Rather, the track positions **1500***a*-**1500***d* may be moved to any other desired locations associated with the tracks **80**. Similarly, fifth and sixth track positions **1500***e*, **1500***f* are not limited to being located at midpoints along the outer edges of the right and left tracks **80***a*, **80***b*, respectively. Rather, the fifth and sixth track positions **1500***a*-**1500***d* may be move to any other desired locations associated with the tracks **80**.

[0129] In some embodiments, the respective locations of track positions are determined according to which information associated with the tracks **80** is known in advance of the process. For example, in the embodiments described above, virtual track boundaries are derived in part from known dimensional data associated with the tracks **80**, such as track height and/or track width. However, in some embodiments, predetermined values of the track height and/or the track width are not stored in memory **255** in advance. Accordingly, in such embodiments, the respective locations of track positions may be chosen such that the electronic processor **250** is operable to extrapolate track dimensions from data points indicative of the track positions.

[0130] FIG. **16** illustrates an embodiment in which the positions associated with the tracks **80** are chosen for generating a virtual track model when a height of the tracks **80** is unknown. The track modeling method **800** may be modified such that while generating the virtual track model, the electronic processor **250** is configured to move the dipper **34** to and determine respective sets of cartesian coordinates representing the track positions **1600***a*-**1600***c*. As shown, the respective locations of the first and second track positions **1600***a*, **1600***b* are similar to the locations of the first and second track positions **900***a*, **900***b* described above. In particular, the first track position **1600***a* is located at the front-top-right vertex of right track **80***a*, and the second track position **1600***b* is located at the rear-top-right vertex of right track **80***a*.

[0131] The location of the third track position **1600***c* is chosen to be located on a top surface of the right track **80***a*. In particular, the third track position **1600***c* is chosen to be located at a position on the top surface of right track **80***a* that has the tallest height, or largest displacement along the z-axis relative to the track center **405**. For example, when the right track **80***a* is curved, a middle portion of the right track **80***a* is taller than the front and/or rear ends of the right track **80***a*. Thus, the third track position **1600***c* may be located on top of a middle portion of the right track **80***a* to enable the electronic processor to determine a height of the right track **80***a*.

[0132] The electronic processor **250** may be configured to derive the height of right track **80***a* from a relationship between the z-component of the third track position **1600***c* and the z-component of the first track position **1600***a*. In some embodiments, it may be assumed that the height, or z-component, of the first track position **1600***a* is a fraction of the height of the third track position **1600***c*. Accordingly, the electronic processor **250** may be configured to determine that the height of right track **80***a* is equal to a multiple of the difference between the z-component of the third track position **1600***c* and the z-component of the first track position **1600***a*. For example, if it is assumed that the height of the first track position **1600***a* is half the height of the third track position **1600***c*, the height of right track **80***a* is calculated by doubling the difference between the z-components of the first and third track positions **1600***a*, **1600***c*.

[0133] Although deriving track height is described with respect to the illustrated embodiment of FIG. **16**, it should be understood that alternative and/or additional track positions may be used by the electronic processor **250** to determine a height of the tracks **80**. For example, the electronic processor **250** may be configured to move the dipper **34** to a location at which the bottom surface of the dipper **34** is contacting the surface on which the tracks **80** are resting. Accordingly, the electronic processor **250** may determine that the height of the tracks **80** is equal to the difference between the respective z-components of the top surface of the right track **80***a* and the surface on which the tracks **80** are resting. As another example, the electronic processor **250** may be configured to derive the track height from the coordinates of track positions **1500***a*-**1500***f* illustrated in FIG. **15**. As another example, the electronic processor **250** may be configured to determine track height based on corresponding positions associated with the left track **80***b*.

[0134] In some instances, it can be assumed that the height of right track **80***a* is approximately equal to the height of left track **80***b*. Accordingly, in such instances, the electronic processor **250** may be configured to determine that the calculated height of the right track **80***a* is equal to the height of the left track **80***b* when generating a virtual model of the tracks **80**. As a first example, if it can be assumed that the right and left tracks **80***a*, **80***b* are equal in height and other boundary dimensions (e.g., length and width), the electronic processor **250** may be configured to generate a virtual model of the left track **80***b* by mirroring, or reflecting, the virtual model of right track **80***a* across the y-z plane of the local coordinate system **400**. As another example, if it can be assumed the right and left tracks **80***a*, **80***b* are approximately equal in height but not equal in length, the electronic processor **250** may be configured to generate a virtual model of the left track **80***b* using the calculated height of right track **80***a* and the modelling processes described above with respect to FIGS. **12** and **13**. In some instances, it may not be assumed that the right and left tracks **80***a*, **80***b* are approximately equal in height. In such instances, the electronic processor **250** may be further configured to determine a height of the left track **80***b* in a manner that is similar to the process used for determining the height of right track **80***a*. Accordingly, the electronic processor **250** may be configured to move the dipper **34** to and derive data points from additional positions associated with left track **80***b* when generating a virtual model of tracks **80** that are unequal in height.

[0135] FIG. **17** illustrates an embodiment in which the positions associated with the tracks **80** are chosen for generating a virtual track model when a width of the tracks **80** is unknown. The track modeling method **800** may be modified such that while generating the virtual track model, the electronic processor **250** is configured to move the dipper **34** to and determine respective sets of cartesian coordinates representing the track positions **1700***a*-**1700***c* within the local coordinate system **400**. As shown, the respective locations of the first and second track positions **1700***a*, **1700***b* are similar to the locations of the first and second track positions **900***a*, **900***b* described above. In particular, the first track position **1700***a* is located at the front-top-right vertex of right track **80***a*, and the second track position **1700***b* is located at the rear-top-right vertex of right track **80***a*. The location of the third track position **1700***c* is chosen to be located at the front-top-left vertex of right track **80***a*. Therefore, the electronic processor **250** may determine the width of right track **80***a* by calculating the difference between the x-component of the first track position **1700***a* and the x-component of the third track position **1700***c*. In some embodiments, alternative and/or additional track positions are used to determine the width of the tracks **80**. For example, the electronic processor **250** may be configured to determine track width based on positions associated with the left track **80***b*.

[0136] In some instances, it can be assumed that the width of right track **80***a* is approximately equal to the width of left track **80***b*. Accordingly, in such instances, the electronic processor **250** may be configured to determine that the calculated width of the right track **80***a* is equal to the width of the left track **80***b* when generating a virtual model of the tracks **80**. As a first example, if it can be assumed that the right and left tracks **80***a*, **80***b* are equal in width and other boundary dimensions (e.g., length and height), the electronic processor **250** may be configured to generate a virtual model of the left track **80***b* by mirroring, or reflecting, the virtual model of right track **80***a* across the y-z plane of the local coordinate system **400**. As another example, if it can be assumed the right and left tracks **80***a*, **80***b* are approximately equal in width but not equal in length, the electronic processor **250** may be configured to generate a virtual model of the left track **80***b* using the calculated width of right track **80***a* and the modelling processes described above with respect to FIGS. **12** and **13**. In some instances, it may not be assumed that the right and left tracks **80***a*, **80***b* are approximately equal in width. In such instances, the electronic processor **250** may be further configured to determine a width of the left track **80***b* in a manner that is similar to the process used for determining the width of right track **80***a*. Accordingly, the electronic processor **250** may be configured to move the dipper **34** to and derive data points from additional positions associated with left track **80***b* when generating a virtual model of tracks **80** that are unequal in width.

[0137] In some embodiments, the track modeling method **800** may be modified to enable the electronic processor **250** to determine a curvature of the tracks **80**. For example, FIG. **18** illustrates a right-side view of a rope shovel embodiment in which the rope shovel **10** includes curved tracks **80**. As shown, three positions associated with the tracks **80** are chosen such that a curvature of the tracks **80** may be derived from the cartesian coordinates representing track positions **1800***a*-**1800***c*.

[0138] The first track position **1800***a* is located at the front-right vertex of right track **80***a*. The second track position **1800***b* is located at a midpoint of the top surface of right track **80***a*. That is, the second track position **1800***b* is centered between the front and rear track ends on the top surface of right track **80***a*. The third track position **1800***c* is located at the center of the right-surface of the right track **80***a*. That is, the third track position **1800***c* is located at position on the right surface of right track **80***a* that is centered between the top and bottom surface of the right track **80***a*. Furthermore, the third track position **1800***c* is centered between the front and rear ends of the right track **80***a*.

[0139] While determining a curvature of the right track **80***a*, the electronic processor **250** is configured to move the dipper **34** to and determine respective sets of cartesian coordinates representing the track positions **1800***a*-**1800***c*. At least in some embodiments, the shape of the right surface of right track **80***a* can be approximately modeled as an ellipse. Accordingly, the electronic processor **250** may be configured to extrapolate virtual boundaries of the right track **80***a* from the respective coordinates of the track positions **1800***a*-**1800***c* and the equation for an ellipse.

[0140] For example, with respect to Equation 1 below, the electronic processor **250** may be configured to determine that the first radius, R1, of the right track **80***a* is equal to the difference between the respective y-components of the first track position **1800***a* and the third track position **1800***c*. Similarly, the electronic processor **250** may be configured to determine that the second radius, R2, of the right track **80***a* is equal to the difference between the respective z-components of the second track position **1800***b* and the third track position **1800***c*. Accordingly, by using Equation 1, the electronic processor **250** may be configured to extrapolate virtual track boundaries from cartesian coordinates representing points on the surface of a curved track **80**.

$$\left(\frac{y^2}{R1^2}\right)+\left(\frac{z^2}{R2^2}\right)=1 \quad \text{[Equation 1]}$$

[0141] Swing Encoder Calibration

[0142] In some embodiments, the electronic processor **250** may additionally be configured to calibrate the swing sensor **315***c* (e.g., a swing encoder) of the rope shovel **10** based on cartesian coordinates of the positions associated with the tracks **80**. As noted above, the swing sensor **315***c* (see FIG. 3B) is configured to indicate a rotational position of the dipper **34** with respect to the swing axis **84** (see FIG. **2**). For example, with reference to FIG. **19**, where the dipper **34** is centered in front of the rope shovel **10**, the swing sensor **315***c* may be positioned and configured to indicate a rotational position of 0 degrees. In this configuration, as a further example, when the dipper **34** is centered facing in the opposite, rear direction, the swing sensor **315***c* indicates a rotational position of 180 degrees. Due to tolerances of components, wear of components overtime, and other factors, the swing sensor **315***c* may not indicate precisely 0 degrees when the dipper **34** is centered in front of the rope shovel **10**. Rather, the swing sensor **315***c* may output a rotational position that is offset from 0 degrees (e.g., 0.5 degrees, 2 degrees, 5 degrees, 355 degrees, 358 degrees, etc.).

[0143] To ensure that accurate rotational position information is being provided by the swing sensor **315***c*, it may be desirable to calibrate the swing sensor **315***c* during an initial setup stage, periodically after a certain amount of time or use of the rope shovel **10**, or both to account for this offset. For example, the electronic processor **250** may determine the offset angle for the swing sensor **315***c* and may calibrate the swing sensor **315***c* by, for example, by reprogramming the swing sensor **315***c* based on the offset angle such that it provides the expected rotational angle for a given swing position of the dipper **34** (e.g., 0 degrees when the dipper is centered in front of the rope shovel **10**) or storing the offset angle on the controller **200** such that the controller **200** may transform a received rotational position from the swing sensor **315***c* (e.g., swing angle R) with the offset angle (e.g., +2.5 degrees) to calculate an actual rotational position for the dipper **34** (e.g., R+2.5 degrees).

[0144] FIG. **19** illustrates an embodiment in which an offset angle of the swing sensor **315***c* may be derived from the track positions **1900***a*-**1900***f* In a manner that is similar to the processes described above, the electronic processor **250** may be configured to move the dipper **34** to and determine respective sets of cartesian coordinates representing the track positions **1900***a*-**1900***f* within the local coordinate system **400**.

[0145] The electronic processor **250** may be further configured to extrapolate a pair of lines that respectively pass through, or nearly pass through, the track positions **1900***a*-**1900***f*. In particular, as shown in FIG. **19**, the electronic processor **250** may be configured to extrapolate a first line **1905***a* that passes through, or nearly passes through, the positions associated with the outer edge of the right track **80***a* (e.g., the first track position **1900***a*, the second track position **1900***b*, and the fifth track position **1900***e*). Similarly, the electronic processor **250** may be configured to extrapolate a second line **1905***b* that passes through, or nearly passes through, the positions associated with the outer edge of the left track **80***b* (e.g., the third track position **1900***c*, the fourth track position **1900***d*, and the sixth track position **1900***f*).

[0146] The electronic processor **250** then extrapolates a third line **1910** that passes through the second track position **1900***b* and is perpendicular to the first line **1905***a*. The electronic processor **250** then determines an angle (θ) between the third line **1910** and the second line **1905***b*. When the swing sensor **315***c* is properly calibrated, the third line **1910** intersects the second line **1905***b* at a right angle (i.e., the angle (θ)=90 degrees). However, when the third line does not intersect the second line **1905***b* at a right angle, the electronic processor **250** determines the offset angle to be equal to the difference between 90 degrees and the angle, θ, at which the third line **1910** intersects the second line **1905***b*. The electronic processor **250** then calibrates the swing sensor **315***c*, as described above, using the determined offset angle.

[0147] Thereafter, the rotational position for the dipper **34** is determined using the swing sensor **315***c* as calibrated by the offset angle, improving the accuracy of the determined rotational position. Although the swing sensor calibration was described such that, when the dipper **34** is centered in front of the rope shovel **10**, the swing sensor **315***c* indicates a rotational position of 0 degrees, in some embodiments, the reference system for the swing angle is shifted such that 0 degrees indicates another reference point (e.g., where the dipper **34** is centered in the rear direction of the rope shovel **10**).

[0148] With respect to FIG. **19**, the electronic processor **250** may be configured to use alternative methods for deriving an offset angle of the swing sensor **315***c*. For example, in some embodiments, the electronic processor **250** is configured to determine a respective rotational position, or angle of rotation, of the dipper **34** when the dipper **34** is moved to each of the front and rear track positions **1900***a*, **1900***b*, **1900***c*, and **1900***d*. That is, while the dipper **34** is at the track position **1900***a*, the electronic processor **250** determines an amount by which the dipper **34** is rotated (e.g., 30 degrees) relative to the track center **405**. Similarly, the electronic processor **250** determines a respective angle of rotation of the dipper **34** while the dipper **34** is located at each of the track positions **1900***b*, **1900***c*, and **1900***d*.

[0149] After determining a respective rotation angle of the dipper **34** at each of the front and rear track positions **1900***a*, **1900***b*, **1900***c*, and **1900***d*, the electronic processor **250** is configured to sum the four rotation angles and divide the sum of rotation angles by the total number of rotation angles, four. Accordingly, the electronic processor **250** determines that the offset angle of the swing sensor **315***c* is equal to the result of the sum of rotation angles divided by the total number of rotation angles. As an example, if it is determined that the rotation angle of dipper **34** is equal to 30 degrees at track position **1900***a*, 150 degrees at track position **1900***b*, −29.5 degrees at track position **1900***c*, and −149.5 degrees at track position **1900***d*, the electronic processor **250** will determine that the offset angle of swing sensor **315***c* is equal to 0.25 degrees. Although described with respect to four rotational positions of the dipper **34**, it should be understood that the electronic processor **250** may be configured to use more (e.g., six) or less (e.g., two) rotational positions of the dipper **34** when determining an offset angle of the swing sensor **315***c*.

[0150] Preventing and Mitigating Collisions Between a Dipper and Exclusionary Zone

[0151] FIG. **20** illustrates a method **2000** for preventing or mitigating collisions between a dipper and an exclusionary zone, according to some embodiments. Generally, an exclusionary zone is an area or volume that defines the position of an object with which the dipper **34** should avoid colliding. In the method **2000**, the exclusionary zone is taught to the electronic processor **250** by movements of the dipper **34**.

[0152] FIG. **21** illustrates a top-down schematic view of the mining machine of FIG. **1** with examples of exclusionary zones **2100***a-e*. As illustrated, an exclusionary zone may define the position of, for example, the tracks **80***a* and **80***b* of the rope shovel, a power cable reel **2105** of the rope shovel, a hopper **2110** that the rope shovel **10** loads with won ore, a truck **2115** that the rope shovel loads with won ore, a power supply station **2120**, or another obstacle that the dipper should avoid contacting. The power cable reel **2105** is a reel for a power supply cable **2122** that powers the rope shovel **10**. As illustrated, the power supply cable **2122** is coupled to the power supply station **2120**. The power supply station **2120** may include a pole extending vertically from a base. The pole may include a mechanical coupling to secure the power supply cable **2122** at an elevated position. Several power supply stations **2120** may be provided to support the power supply cable **2122** in the air across the mine site from a power source (e.g., a transformer).

[0153] The exclusionary zone **2100***a* corresponds to the power cable reel **2105**, the exclusionary zone **2100***b* corresponds to the hopper **2110**, the exclusionary zone **2100***c* corresponds to the truck **2115**, the exclusionary zone **2100***d* corresponds to the power supply station **2120**, and the exclusionary zone **2100***e* corresponds to the tracks **80***a* and **80***b*. The exclusionary zones **2100***a-e* may be generically referred to as an exclusionary zone **2100** and collectively referred to as the exclusionary zones **2100**. Additionally, in some embodiments, the track models described with respect to the method of FIG. **8** may be used as an exclusionary zone (see, e.g., track models **1100***a* and **1100***b* in FIG. **11**). Additionally, although the exclusionary zones appear as two-dimensional areas in the top-down view of FIG. **21**, the exclusionary zones may be three dimensional volumes, similar to the track models **1100***a* and **1100***b* in FIG. **11**.

[0154] Returning to FIG. **20**, the method **2000** is described with respect to the rope shovel **10**, dipper **34**, exclusionary zones **2100**, and the electronic processor **250**; however, in some embodiments, the method **2000** is implemented with respect to other rope shovels or mining machines having dippers with crowd, hoist, and swing motions and with respect to a different arrangement of exclusionary zones **2100**. Additionally, although actions within the method **2000** are described as being carried out by the electronic processor **250**, the actions may also be described, for example, as being carried out by the electronic controller **200** having the electronic processor **250**. Furthermore, in some embodiments, the controller **200** and electronic processor **250** implementing the method **2000** are included in the rope shovel **10** as original equipment (e.g., installed at the time of manufacture of the rope shovel **10**) and, in some embodiments, one or more of the controller **200**, the electronic processor **250**, and the software included thereon are included in an aftermarket control system installed in the rope shovel **10** to implement the method **2000**.

[0155] In block **2005**, the electronic processor **250** moves the dipper to a plurality of positions associated with an exclusionary zone, such as one of the exclusionary zones **2100***a-e* (generically referred to as the exclusionary zone **2100**). For example, using the dipper motion command input devices **305**, a rope shovel operator may input a command for moving the dipper **34** to positions **2125** associated with the exclusionary zone **2100** (e.g., the four positions **2125** of the exclusionary zone **2100***c* or the five positions **2125** of the exclusionary zone **2100***d*). The electronic processor **250** receives the operator input signals from the dipper motion command input devices **305** and translates the signals to corresponding motion commands for the dipper drives **310**. In response to receiving the motion commands from the electronic processor **250**, the dipper drives **310** control movement of the dipper **34** to iteratively move the dipper to each of the positions **2125** associated with the exclusionary zone **2100**.

[0156] In block **2010**, the electronic processor **250** determines data points for the exclusionary zone, each data point associated with a position of the plurality of positions. Each data point may include, but is not limited to, one or more measurements taken by the dipper position sensors **315** while the dipper **34** is located at a corresponding position of the plurality of positions. For example, the electronic processor **250** may determine, based on measurements taken by the dipper position sensors **315**, the extent to which the dipper **34** is crowded, the extent to which the dipper **34** is hoisted, and/or the rotational position of the dipper **34** while the dipper **34** is located at each of the positions **2125** for a particular exclusionary zone. The crowd, hoist, and rotation measurements taken by the dipper position sensors **315** may be included in and/or stored in association with each data point. In addition, the electronic processor **250** may be configured to determine a set of (x, y, z) coordinates representing each of the positions **2125** for the exclusionary zone **2100**, which may be included and/or stored in association with each respective data point. As described above with respect to the rope shovel's local coordinate system **400** in FIG. **4**, the electronic processor **250** may be configured to determine, or derive, the (x, y, z) coordinates for each of the positions **2125** based on the (x, y, z) coordinates of a particular dipper reference point **410**. Therefore, the (x, y, z) coordinates of the each of the positions **2125** may be derived from the (x, y, z) coordinates of a particular dipper reference point **410** while the dipper **34** is located at each respective position **2125**.

[0157] In block **2015**, the electronic processor **250** generates a virtual model of the exclusionary zone by extrapolating virtual boundaries of the exclusionary zone from the data points. For example, like in block **825** of FIG. **8**, the electronic processor **250** may be configured to extrapolate virtual boundaries of the exclusionary zone **2100** from the data included in the data points. The virtual boundaries of the exclusionary zone **2100** collectively form a virtual model of the exclusionary zone **2100** and define a three-dimensional volume representing the exclusionary zone **2100** in the rope shovel's local coordinate system **400**. In some embodiments, the electronic processor **250** may be further configured to combine the data points with dimensional data stored in memory **255** when extrapolating virtual boundaries of the exclusionary zone **2100**. In other words, in some embodiments, a portion of the data points that form virtual boundaries are presumed based on known or presumed dimensions or symmetries of certain objects (e.g., trucks, hoppers, etc.), rather than taught to the electronic processor **250** using actions like in blocks **2005** and **2010**. Further explanation of techniques for extrapolating a virtual model from data points is provided above with respect to generating a virtual track model in block **825** of FIG. **8**.

[0158] In block **2020**, the electronic processor **250** receives dipper position data indicative of a position of the dipper **34**. The dipper position data is provided to the electronic processor **250** by one or more of the dipper position sensors **315**. For example, the dipper position data may include an output from one or more of the crowd sensor **315***a*, the hoist sensor **315***b*, and the swing sensor **315***c*. The output of the crowd sensor **315***a* indicates the crowd position of the dipper **34**, the hoist sensor **315***b* indicates the hoist position of the dipper **34**, and the swing sensor **315** indicates the swing position of the dipper **34**.

[0159] In block **2025**, the electronic processor **250** sets a motion command limit for a dipper motion based on a distance between the dipper **34** and the exclusionary zone **2100** of the mining machine inferred from the dipper position data, the dipper motion being selected from a group of a swing motion, a crowd motion, and a hoist motion. In some embodiments, to set the motion command limit based on the distance inferred from the dipper position data, the electronic processor **250** may determine a limit value using one or more of the limit functions **330** stored in the memory **255** (see FIG. 3B). For example, in some embodiments, the limit functions **330** include distance-based functions that define the motion command limit based on the distance between the dipper **34** and the exclusionary zone **2100** such that they use the distance as an input and provide a limit value as an output. As another example, in some embodiments, the limit functions **330** include position-based functions that define the motion command limit based on the dipper position data, where such a position-based function is defined based on relationships between (i) potential dipper positions and (ii) associated distances between the potential dipper positions and the exclusionary zone **2100**. In other words, the distance between each potential position of the dipper **34** and the exclusionary zone **2100** may be determined in advance (e.g., in a setup stage); then, at a later stage during operation, when the dipper **34** is determined to be at a particular position, the distance between the dipper **34** and exclusionary zone **2100** is presumed based on the prior determined relationship. The position-based function may be generated based on these underlying relationships between the position of the dipper **34** and the associated distance between the dipper **34** and the exclusionary zone **2100** that results. Accordingly, the position-based functions use the current position of the dipper **34** indicated by the dipper position data as an input (and as a proxy for the distance between the dipper **34** and the exclusionary zone **2100**) and provide a limit value as an output. Then, after determining the limit value, the electronic processor **250** may store the limit value in the memory **255** (see FIG. 3B) as the motion command limit for the dipper motion (e.g., as one or more of the crowd limit **335**, hoist limit **340**, and swing limit **345**).

[0160] As noted, the distance between the dipper **34** and the exclusionary zone **2100** may be used directly as an input into the limit function(s) or may be used indirectly in advance to generate the limit function(s) such that the current position of the dipper **34** may be used as an input into the limit function(s). In some embodiments, the electronic processor **250** determines a distance between the dipper **34** and the exclusionary zone **2100** using similar techniques as described above with respect to the method **500** of FIG. **5** and determining a distance between the dipper **34** and the tracks **80**. For example, in some embodiments, the electronic processor **250** determines the current position of the dipper **34** (based on the dipper position data from block **2020**), determines the position of the exclusionary zone (from block **2015**), and then determines the shortest distance between the dipper **34** and the exclusionary zone **2100** (e.g., the distance between the two nearest points of the dipper **34** and the exclusionary zone **2100**). The electronic processor **250** may determine the shortest distance using a nearest neighbor algorithm, or similar known algorithm. The distance may be a length measurement across three dimensions of space (e.g., x, y, and z dimensions) and, accordingly, may be referred to as a three-dimensional distance.

[0161] In some embodiments, the exclusionary zone **2100** is associated with a slow region function and stop region function for the dipper motion. In such embodiments, the electronic processor **250** may select the stop region function for a dipper motion when the distance between the dipper and the exclusionary zone **2100** is below a stop region threshold for that dipper motion, and may select the slow region function for a dipper function in response when the distance between the dipper and the exclusionary zone **2100** is above the stop region threshold, but below the slow region threshold for that dipper motion. When the distance between the dipper and the exclusionary zone **2100** is above the slow region threshold, the electronic processor **250** may return the default limit value for the motion command limit. In some embodiments, the slow region thresholds, stop region thresholds, and default limit values for each of the hoist, crowd, and swing motions are stored in the memory **255** (e.g., as part of the limit function **330**). In some embodiments, the slow region function and stop region function associated with the exclusionary zone **2100** are similar to the functions shown in FIGS. **7**A and **7**B (and combined in FIG. 7C).

[0162] In block **2030**, the electronic processor **250** controls the dipper motion according to a dipper motion command limited by the motion command limit. Block **2030** may be implemented in a similar manner as described above with respect to block **520** in FIG. **5**. For example, in response to operator operation of one of the motion command input devices **305** (see FIG. 3B), the electronic processor **250** receives a dipper motion command input (e.g., a hoist, crowd, or swing command input). The electronic processor **250** then determines the lower of (a) the motion command limit (set in block **2025**) and (b) the dipper motion command input. The electronic processor **250** then provides a dipper motion command to the dipper drives **310** associated with the motion command limit (e.g., a hoist drive **220**), where the dipper motion command is the lower of (a) the motion command limit and (b) the dipper motion command input. The dipper drive **310** that receives the motion command then controls the dipper motion of the dipper **34** according to the command. For example, when the electronic processor **250** provides a crowd motion command to the crowd drive **215** to crowd in at 20% speed, the crowd drive **215** controls the dipper **34** to crowd in at 20% speed.

[0163] In some embodiments of the method **2000**, in block **2025**, rather than setting a motion command limit for one dipper motion, the electronic processor **250** sets a motion command limit for two or three dipper motions based on the distance between the dipper **34** and the exclusionary zone **2100**, where the dipper motions are selected from the group of the swing motion, the crowd motion, and the hoist motion. In these embodiments, a similar process used to set the motion command limit for one dipper motion is used to set the dipper motion for the other dipper motions. Accordingly, in these embodiments, in block **2030**, the electronic processor **250** is configured to control the dipper motion of the dipper **34** according to dipper motion commands (e.g., crowd, hoist, and swing commands) limited by each of the crowd limit, hoist limit, and swing limit.

[0164] In some embodiments, after block **2030**, the electronic processor **250** loops back to block **2005** such that the electronic processor **250** repeatedly executes the method **2000**. By repeatedly executing the method **2000**, the electronic processor **250** may account for changes over time in the position of the dipper **34** and in the dipper motion command received via the dipper motion command input device **305**. Thus, in some embodiments, the electronic processor **250** repeatedly updates the motion command limits based on the distance between the dipper **34** and the exclusionary zone **2100** (or between multiple exclusionary zones **2100**) over time as the dipper **34** moves and, in turn, controls the dipper motion based on the updated motion command limit.

[0165] In light of the above discussion, it should be apparent that, as the dipper **34** is controlled to be closer to the exclusionary zone **2100**, as a general rule, the motion commands are further limited. As a result, in some embodiments, when the dipper **34** is very close to the exclusionary zone **2100**, one or more of the dipper motions are restricted such that the dipper **34** moves slowly or not at all in response to motion command inputs from an operator. Additionally, in some embodiments, when the dipper **34** is controlled to crowd in (or hoist down) quickly by the operator towards the exclusionary zone **2100**, the electronic processor **250** will limit the crowd (or hoist) motion command more and more such that the dipper **34** is gradually slowed to prevent a collision with the exclusionary zone **2100** or at least mitigate the impact of a collision with the tracks **80**.

[0166] Each exclusionary zone may be associated with a particular set of limit functions **330**. For example, the exclusionary zone **2100*b*** for the hopper **2110** may be associated with six limit functions **330**, including a separate slow region function and stop region function for each of the hoist, crowd, and swing motions. Similarly, each other exclusionary zone **2100** may be respectively associated with six further limit functions **330**, including a separate slow region function and stop region function for each of the hoist, crowd, and swing motions. Ini some embodiments, the limit functions **330** for one of the exclusionary zones **2100** is more restrictive than the limit functions **330** for another of the exclusionary zones **2100**. For example, the exclusionary zones **2100*d*** and **2100*a*** may be more restrictive than the other exclusionary zones **2100*b***, **2100*c***, and **2100*e*** because the exclusionary zones **2100*a*** and **2100*d*** are for objects having high voltage power (the power supply cable **2122**). For example, with reference to FIG. **7**C, such limit functions **330** that are more restrictive may have stop region thresholds and slow region thresholds that are higher (i.e., such that motion command limits start when the dipper **34** is further away from the exclusionary zone **2100**). Additionally, such limitation functions **330** that are more restrictive may prevent or block motion commands directing the dipper **34** towards the exclusionary zone **2100** (rather than reduce to a non-zero value) when in the stop region.

[0167] In some embodiments, blocks **2005**, **2010**, and **2015** are executed multiple times to teach multiple exclusionary zones **2100** to the electronic processor **250**. In such embodiments, after the virtual model of each exclusionary zone **2100** is generated, the electronic processor **250** proceeds to block **2020**, **2025**, and **2030**. As such, in block **2025**, the electronic processor **250** may determine the limit value for each exclusionary zone **2100** (based on the associated limit functions **330** for each exclusionary zone **2100**), and then set the motion command limit to the lowest (i.e., most restrictive) limit value from the various exclusionary zones **2100**. In some embodiments, this limit selection is repeated for each dipper motion (e.g., for the hoist, crowd, and swing motions) such that each dipper motion has a respective motion command limit set that is the lowest limit value by the limit functions **330** for the various exclusionary zones **2100** associated with the particular dipper motion.

[0168] In effect, at least in some embodiments, the limit functions **330** of the rope shovel **10** define virtual three-dimensional fields around the exclusionary zones **2100** for each of the swing, crowd, and hoist dipper motions. When one or more of these virtual fields of the dipper **34**, which may be mapped onto the coordinate system **400** around the virtual dipper **605**, overlaps the exclusionary zone **2100**, the one or more dipper motions associated with the one or more overlapping virtual fields is limited.

[0169] Accordingly, embodiments described herein provide systems and methods for preventing and mitigating collisions between a dipper and tracks of a mining machine, such as a rope shovel.

What is claimed is:

1. A method for preventing and mitigating collisions between a dipper and an exclusionary zone that is taught to a mining machine, the method comprising:

moving, by an electronic processor, the dipper to a plurality of positions associated with the exclusionary zone;

determining, by the electronic processor, data points for the exclusionary zone, each data point associated with a position of the plurality of positions;

generating, by the electronic processor, a virtual model of the exclusionary zone by extrapolating virtual boundaries of the exclusionary zone from the data points;

receiving, by the electronic processor, dipper position data indicative of a position of the dipper;

setting, by the electronic processor, a motion command limit for a dipper motion based on a distance between the dipper and the exclusionary zone of the mining machine inferred from the dipper position data, the dipper motion being selected from a group of a swing motion, a crowd motion, and a hoist motion; and

controlling, by the electronic processor, the dipper motion according to a dipper motion command limited by the motion command limit.

2. The method of claim **1**, wherein the exclusionary zone is at least one selected from the group of: tracks of the mining machine; a power cable reel of the mining machine; a power supply station; a hopper configured to receive a load from the dipper; and a truck configured to receive a load from the dipper.

3. The method of claim 1, further comprising:
moving, by an electronic processor, the dipper to a second plurality of positions associated with a second exclusionary zone, the second exclusionary zone including a power supply line for the mining machine;
determining, by the electronic processor, further data points for the second exclusionary zone, each further data point associated with a position of the second plurality of positions;
generating, by the electronic processor, a second virtual model of the second exclusionary zone by extrapolating virtual boundaries of the second exclusionary zone from the further data points;
receiving, by the electronic processor, further dipper position data indicative of an updated position of the dipper;
updating, by the electronic processor, the motion command limit for the dipper motion based on a distance between the dipper and the second exclusionary zone of the mining machine inferred from the further dipper position data; and
controlling, by the electronic processor, the dipper motion according to a further dipper motion command limited by the motion command limit that was updated based on the distance between the dipper and the second exclusionary zone.

4. The method of claim 3,
wherein setting the motion command limit for the dipper motion based on the distance includes reducing the motion command limit from an initial value to a reduced value according to a first function that is associated with the exclusionary zone and that defines the motion command limit to be lower as the distance is reduced, and
wherein updating the motion command limit for the dipper motion based on the distance includes reducing the motion command limit from an initial value to a reduced value according to a second function that is associated with the second exclusionary zone and that defines the motion command limit to be lower as the distance is reduced, wherein the second function is more restrictive to motion than the first function.

5. The method of claim 1, wherein, to set the motion command limit for the dipper motion based on the distance between the dipper and the exclusionary zone inferred from the dipper position data, the method further comprises at least one selected from the group of:
(i) calculating the distance and using the distance as an input to a distance-based function that defines the motion command limit based on the distance, and.
(ii) using the dipper position data as an input to a position-based function that defines the motion command limit based on the dipper position data, where the position-based function is defined based on relationships between potential dipper positions and associated distances between the potential dipper positions and the exclusionary zone.

6. The method of claim 1, further comprising:
determining, by the electronic processor, a position of a three-dimensional virtual dipper model in a three-dimensional coordinate system for the mining machine based on the dipper position data;
determining, by the electronic processor, a shortest distance between the three-dimensional virtual dipper model and the virtual model of the exclusionary zone, wherein the shortest distance represents the distance between the dipper and the exclusionary zone.

7. The method of claim 1, wherein the distance is a three-dimensional distance indicating a length across three dimensions of space.

8. The method of claim 1, wherein setting the motion command limit for the dipper motion based on the distance comprises:
when the distance is below a stop region threshold, setting the motion command limit according to a stop region function, and
when the distance is above the stop region threshold and below a slow region threshold, setting the motion command limit according to a slow region function.

9. The method of claim 1, wherein the dipper motion is the crowd motion and motion command limit is a crowd motion command limit, the method further comprising:
setting, by the electronic processor, a hoist motion command limit for the hoist motion based on the distance; and
setting, by the electronic processor, a swing motion command limit for the swing motion based on the distance.

10. The method of claim 1, further comprising:
repeatedly receiving, by the electronic processor, the dipper position data indicative of the position of the dipper over time as the dipper moves; and
updating the motion command limit based on the dipper position data as the dipper position data is repeatedly determined.

11. A mining machine with a collision prevention and mitigation system, the mining machine comprising:
a frame;
a dipper supported by the frame;
a dipper drive coupled to the dipper and configured to move the dipper in a dipper motion selected from a group of a swing motion, a crowd motion, and a hoist motion;
a dipper position sensor configured to determine a position of the dipper;
an electronic controller including an electronic processor and a memory, the electronic controller coupled to the dipper drive and the dipper position sensor, the electronic controller configured to:
move the dipper to a plurality of positions associated with an exclusionary zone;
determine data points for the exclusionary zone, each data point associated with a position of the plurality of positions;
generate a virtual model of the exclusionary zone by extrapolating virtual boundaries of the exclusionary zone from the data points;
receive dipper position data indicative of a position of the dipper;
set a motion command limit for a dipper motion based on a distance between the dipper and the exclusionary zone of the mining machine inferred from the dipper position data, the dipper motion being selected from a group of a swing motion, a crowd motion, and a hoist motion; and
control the dipper motion according to a dipper motion command limited by the motion command limit.

12. The mining machine of claim 11, wherein the exclusionary zone is at least one selected from the group of: tracks

of the mining machine; a power cable reel of the mining machine; a power supply station; a hopper configured to receive a load from the dipper; and a truck configured to receive a load from the dipper.

13. The mining machine of claim **11**, wherein the electronic controller is further configured to:

move the dipper to a second plurality of positions associated with a second exclusionary zone, the second exclusionary zone including a power supply line for the mining machine;

determine further data points for the second exclusionary zone, each further data point associated with a position of the second plurality of positions;

generate a second virtual model of the second exclusionary zone by extrapolating virtual boundaries of the second exclusionary zone from the further data points;

receive further dipper position data indicative of an updated position of the dipper;

update the motion command limit for the dipper motion based on a distance between the dipper and the second exclusionary zone of the mining machine inferred from the further dipper position data; and

control the dipper motion according to a further dipper motion command limited by the motion command limit that was updated based on the distance between the dipper and the second exclusionary zone.

14. The mining machine of claim **13**,

wherein setting the motion command limit for the dipper motion based on the distance includes reducing the motion command limit from an initial value to a reduced value according to a first function that is associated with the exclusionary zone and that defines the motion command limit to be lower as the distance is reduced, and

wherein updating the motion command limit for the dipper motion based on the distance includes reducing the motion command limit from an initial value to a reduced value according to a second function that is associated with the second exclusionary zone and that defines the motion command limit to be lower as the distance is reduced, wherein the second function is more restrictive to motion than the first function.

15. The mining machine of claim **11**, wherein, to set the motion command limit for the dipper motion based on the distance between the dipper and the exclusionary zone inferred from the dipper position data, the electronic controller is further configured to at least one selected from the group of:

(i) calculate the distance and using the distance as an input to a distance-based function that defines the motion command limit based on the distance, and.

(ii) use the dipper position data as an input to a position-based function that defines the motion command limit based on the dipper position data, where the position-based function is defined based on relationships between potential dipper positions and associated distances between the potential dipper positions and the exclusionary zone.

16. The mining machine of claim **11**, wherein the electronic controller is further configured to:

determine a position of a three-dimensional virtual dipper model in a three-dimensional coordinate system for the mining machine based on the dipper position data;

determine a shortest distance between the three-dimensional virtual dipper model and the virtual model of the exclusionary zone, wherein the shortest distance represents the distance between the dipper and the exclusionary zone.

17. The mining machine of claim **11**, wherein the distance is a three-dimensional distance indicating a length across three dimensions of space.

18. The mining machine of claim **11**, wherein, to set the motion command limit for the dipper motion based on the distance, the electronic controller is configured to:

when the distance is below a stop region threshold, set the motion command limit according to a stop region function, and

when the distance is above the stop region threshold and below a slow region threshold, set the motion command limit according to a slow region function.

19. The mining machine of claim **11**, wherein the dipper motion is the crowd motion and motion command limit is a crowd motion command limit, wherein the electronic controller is further configured to:

set a hoist motion command limit for the hoist motion based on the distance; and

set a swing motion command limit for the swing motion based on the distance.

20. The mining machine of claim **11**, wherein the electronic controller is further configured to:

repeatedly receive the dipper position data indicative of the position of the dipper over time as the dipper moves; and

update the motion command limit based on the dipper position data as the dipper position data is repeatedly determined.

21. A collision prevention and mitigation control system for a mining machine having a frame, a dipper supported by the frame, a dipper drive coupled to the dipper and configured to move the dipper in a dipper motion selected from a group of a swing motion, a crowd motion, and a hoist motion, a dipper position sensor configured to determine a position of the dipper, the control system comprising:

an electronic controller including an electronic controller and a memory, the electronic controller coupled to the dipper drive and the dipper position sensor, the electronic controller configured to:

move the dipper to a plurality of positions associated with an exclusionary zone;

determine data points for the exclusionary zone, each data point associated with a position of the plurality of positions;

generate a virtual model of the exclusionary zone by extrapolating virtual boundaries of the exclusionary zone from the data points;

receive dipper position data indicative of a position of the dipper;

set a motion command limit for a dipper motion based on a distance between the dipper and the exclusionary zone of the mining machine inferred from the dipper position data, the dipper motion being selected from a group of a swing motion, a crowd motion, and a hoist motion; and

control the dipper motion according to a dipper motion command limited by the motion command limit.

22. The control system of claim **21**, wherein the exclusionary zone is at least one selected from the group of: tracks of the mining machine; a power cable reel of the mining machine; a power supply station; a hopper configured to receive a load from the dipper; and a truck configured to receive a load from the dipper.

23. The control system of claim **21**, wherein the electronic controller is further configured to:

move the dipper to a second plurality of positions associated with a second exclusionary zone, the second exclusionary zone including a power supply line for the mining machine;

determine further data points for the second exclusionary zone, each further data point associated with a position of the second plurality of positions;

generate a second virtual model of the second exclusionary zone by extrapolating virtual boundaries of the second exclusionary zone from the further data points;

receive further dipper position data indicative of an updated position of the dipper;

update the motion command limit for the dipper motion based on a distance between the dipper and the second exclusionary zone of the mining machine inferred from the further dipper position data; and

control the dipper motion according to a further dipper motion command limited by the motion command limit that was updated based on the distance between the dipper and the second exclusionary zone.

24. The control system of claim **23**,

wherein setting the motion command limit for the dipper motion based on the distance includes reducing the motion command limit from an initial value to a reduced value according to a first function that is associated with the exclusionary zone and that defines the motion command limit to be lower as the distance is reduced, and

wherein updating the motion command limit for the dipper motion based on the distance includes reducing the motion command limit from an initial value to a reduced value according to a second function that is associated with the second exclusionary zone and that defines the motion command limit to be lower as the distance is reduced, wherein the second function is more restrictive to motion than the first function.

25. The control system of claim **21**, wherein, to set the motion command limit for the dipper motion based on the distance between the dipper and the exclusionary zone inferred from the dipper position data, the electronic controller is further configured to at least one selected from the group of:

(iii) calculate the distance and using the distance as an input to a distance-based function that defines the motion command limit based on the distance, and.

(iv) use the dipper position data as an input to a position-based function that defines the motion command limit based on the dipper position data, where the position-based function is defined based on relationships between potential dipper positions and associated distances between the potential dipper positions and the exclusionary zone.

26. The control system of claim **21**, wherein the electronic controller is further configured to:

determine a position of a three-dimensional virtual dipper model in a three-dimensional coordinate system for the mining machine based on the dipper position data;

determine a shortest distance between the three-dimensional virtual dipper model and the virtual model of the exclusionary zone, wherein the shortest distance represents the distance between the dipper and the exclusionary zone.

27. The control system of claim **21**, wherein the distance is a three-dimensional distance indicating a length across three dimensions of space.

28. The control system of claim **21**, wherein, to set the motion command limit for the dipper motion based on the distance, the electronic controller is configured to:

when the distance is below a stop region threshold, set the motion command limit according to a stop region function, and

when the distance is above the stop region threshold and below a slow region threshold, set the motion command limit according to a slow region function.

29. The control system of claim **21**, wherein the dipper motion is the crowd motion and motion command limit is a crowd motion command limit, wherein the electronic controller is further configured to:

set a hoist motion command limit for the hoist motion based on the distance; and

set a swing motion command limit for the swing motion based on the distance.

30. The control system of claim **21**, wherein the electronic controller is further configured to:

repeatedly receive the dipper position data indicative of the position of the dipper over time as the dipper moves; and

update the motion command limit based on the dipper position data as the dipper position data is repeatedly determined.

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