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Expressive Musical Robots: Building, Evaluating, and Interfacing with an Ensemble of Mechatronic Instruments

By:

JIM MURPHY

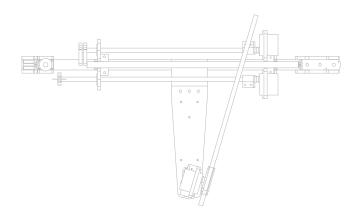
A THESIS SUBMITTED TO THE VICTORIA UNIVERSITY OF
WELLINGTON IN FULFILMENT OF THE REQUIREMENTS FOR THE
DEGREE OF DOCTOR OF PHILOSOPHY

Victoria University of Wellington

Supervisory Committee

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- Co-Supervisor: Dr. Dale A. Carnegie (Victoria University of Wellington School of Engineering and Computer Science)

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"Merlin himself, their elderly creator, said he had devoted years to these machines, his favorites, still unfinished."

James Gleick

Abstract

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An increase in the number of parameters of expression on musical robots can result in an increase in their expressivity as musical instruments. This thesis focuses on the design, construction, and implementation of four new robotic instruments, each designed to add more parametric control than is typical for the current state of the art of musical robotics. The principles followed in the building of the four new instruments are scalable and can be applied to musical robotics in general: the techniques exhibited in this thesis for the construction and use of musical robotics can be used by composers, musicians, and installation artists to add expressive depth to their own works with robotic instruments.

Accompanying the increase in parametric depth applied to the musical robotics is an increase in difficulty in interfacing with them: robots with a greater number of actuators require more time to program. This document aims to address this problem in two ways: the use of closed-loop control for low-level adjustments of the robots and the use of a parametric encoding-equipped musical robot network to provide composers with intuitive musical commands for the robots.

The musical robots introduced, described, and applied in this thesis were conceived of as musical instruments for performance and installation use by artists. This thesis closes with an exhibition of the performance and installation uses of these new robots and with a discussion of future research directions.

Acknowledgements

Many thanks to my PhD advisors, who have guided me somewhere I have never traveled. Dr. Ajay Kapur, who has aided and encouraged me in my work, deserves my abundant thanks for his tireless guidance. From my first day at CalArts, he has selflessly helped me to appreciate and realise my artistic and academic goals, and has taught me that the two need not be mutually exclusive.

Thanks also to Dr. Dale A. Carnegie, my secondary supervisor, for the open-mindedness with which my he has approached my inter-disciplinary status. It is my strong belief that his supervision has lent a rigor and dignity to my work of which I am very proud. The attention to detail he pays to his students' work is inspiring: I aspire to treat my own (future) students' work with as much care and thoughtfulness as he treats his.

Through their assistance, the faculty and staff at Victoria University of Wellington's School of Engineering and Computer Science and the New Zealand School of Music have enabled the work presented here to occur. Thanks to Drs. Will Browne, Dugal McKinnon, and Ted Apel for intriguing conversations, opportunities, and ideas, and to Tim Exley, Sean Anderson, and Jason Edwards for deep technical expertise, thoughtful advice, and patience. Thanks also to Victoria University of Wellington's Faculty of Graduate Research for providing me with the Victoria Doctoral Scholarship and to VUW and NZSM as a whole.

My friends and colleagues who I've met during my studies in Wellington have provided me with help and thoughtful ideas pertaining to this work: double thanks to Mo Zareei, Brett Ryan, Blake Johnston, Timothy Barraclough, and Patrick Herd. Thanks also to the SELCT crew for putting up with my ongoing musical robot evaluations and for your artistic and technical help.

Finally, my deepest thanks to Richard Vindriis, Paul Mathews, and James McVay. Your help with my projects has turned all of this work from an abstraction into something real.

I owe special thanks to fellow researchers and artists in the field of musical robotics (and computer music in general). Thanks to Ge Wang and all the developers of Chuck. Thanks to Gil Weinberg for articulating the need for robotic musicianship and to the Logos Foundation for inspiring me with fantastic robotic instruments. Thanks to Eric Singer for paving the way and setting a high standard against which I continue to measure my work. Thanks to Aengus Martin (and the UTS team) for inspiring me with your work on the feedback guitar. Also, thanks to Nicholas Baginsky, Edgar Berdahl,

George Tzanetakis, Andrew McPherson, the Waseda musical robotic team, and to all of the other innovators and researchers whose work I cite in this document.

To my friends and teachers from CalArts (and environs): Michael Darling (for turning me from a "maker" into a sculptor), Curtis Bahn (for showing me that, with enough patience, robots and humans can make beautiful music together), Martijn Zwartjes (for being a good enough friend and teacher to motivate me to finish projects that I start), and Perry Cook (for giving epic ChucK talks and being rapidly responsive to my DSP emails). Also to Carl Burgin (for making me question my work in the best possible way), Dimitri Diakopoulos (for HIDUINO, endless help over the last three years, and being a great friend and generally thoroughly inspiring individual), and to Jordan Hochenbaum and Owen Vallis (both of you were there on the ground floor, helping me to make my PhD into a real thing).

Thanks to Trimpin for his generosity: his openness with his knowledge has catalysed this research. I am humbled and inspired by his work, and am honoured to consider him a friend and mentor.

Mr. Evans, Ms. Chase, and Ms. Kempter: to call you my teachers is insufficient: you are my Zhuangzi; you taught me to wander where there is no path. Such open-minded wandering has led to this work, and for that I owe you my thanks.

To Kate and Chris. For being wonderful people and making me lucky enough to start this thesis-related work with only one sibling and letting me finish with two.

To my parents: while these words can't convey my gratitude to your sacrifices which have directly led to this work, I hope that you see on each of the pages in this work an indelible stamp of my thanks.

Also, Bridget. Without you, I would have been a pair of ragged claws, scuttling across the floors of silent seas...

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To my family, friends, and teachers.