Claims:

1. A system for inspecting a workpiece that includes a workpiece defect and a workpiece surface, comprising:

an ultrasonic inspection system comprising an ultrasonic transducer that directs sound waves along a first trajectory to the workpiece defect, wherein the sound waves contact the workpiece surface at a workpiece surface location; and

a laser pointer connected to the ultrasonic inspection system, wherein the laser pointer directs a laser beam along a second trajectory and against the workpiece surface to visually annunciate the workpiece surface location;

wherein the first trajectory is substantially parallel to the second trajectory.

2. The system of claim 1, wherein the laser pointer comprises a water-resistant laser pointer.

3. The system of claim 1, wherein the laser beam contacts the workpiece surface at the workpiece surface location.

4. The system of claim 1, wherein the laser beam contacts the workpiece surface at a second workpiece surface location located a distance from the workpiece surface location.

5. The system of claim 1, wherein the laser beam is one of a plurality of laser beams directed from the laser pointer against the workpiece surface by the laser pointer, wherein each laser beam contacts the workpiece surface at a respective second workpiece surface location, and wherein the workpiece surface location is centered between the second workpiece surface locations.

6. The system of claim 1, wherein the laser pointer comprises a laser pointer housing mounted to the ultrasonic transducer.

7. The system of claim 6, wherein the laser pointer further comprises a plurality of lasers connected to the laser pointer housing, and arranged circumferentially around the ultrasonic transducer.

8. The system of claim 6, wherein the laser pointer further comprises a laser connected to the laser pointer housing, and arranged coaxially with the ultrasonic transducer.

9. The system of claim 1, further comprising a manipulator system to which the ultrasonic transducer is connected.

10. The system of claim 9, wherein the manipulator comprises a robotic multi-axis manipulator system.

11. A system for non-contact inspecting a workpiece that includes a workpiece surface, comprising:

a manipulator system;

an ultrasonic inspection system comprising an ultrasonic transducer that is connected to the manipulator system, that directs sound waves along a first trajectory into the workpiece, and that senses reflected sound waves to detect a workpiece defect, wherein the sound waves intersect the workpiece surface at a workpiece surface location; and

a laser pointer connected to the ultrasonic transducer, wherein the laser pointer directs a laser beam along a second trajectory and against the workpiece surface to visually mark the workpiece surface location associated with and indicative of the workpiece defect;

wherein the first trajectory is substantially parallel to the second trajectory.

12. The system of claim 11, wherein the laser pointer comprises a water-resistant laser pointer.

13. The system of claim 11, wherein the laser beam contacts the workpiece surface at the workpiece surface location.

14. The system of claim 11, wherein the laser beam contacts the workpiece surface at a second workpiece surface location disposed a distance from the workpiece surface location.

15. The system of claim 11, wherein the laser beam is one of a plurality of laser beams directed against the workpiece surface by the laser pointer, wherein each laser beam contacts the workpiece surface at a respective second workpiece surface location, and wherein the workpiece surface location is located between the second workpiece surface locations.

16. The system of claim 11, wherein the laser pointer comprises a plurality of lasers connected to a laser pointer housing, and arranged circumferentially around the ultrasonic transducer.

17. The system of claim 11, wherein the laser pointer comprises a laser connected to a laser pointer housing, and arranged coaxially with the ultrasonic transducer.

18. The system of claim 11, wherein the manipulator system comprises a robotic multi-axis manipulator.

Claims:

1. A system for inspecting a workpiece that includes a workpiece defect and a workpiece surface, comprising:

an ultrasonic inspection system comprising an ultrasonic transducer that directs sound waves along a first trajectory to the workpiece defect, wherein the sound waves contact the workpiece surface at a workpiece surface location; and

a laser pointer connected to the ultrasonic inspection system, wherein the laser pointer directs a laser beam along a second trajectory and against the workpiece surface to visually annunciate the workpiece surface location;

wherein the first trajectory is substantially parallel to the second trajectory and wherein the laser beam is one of a plurality of laser beams directed from the laser pointer against the workpiece surface by the laser pointer, wherein each laser beam contacts the workpiece surface at a respective second workpiece surface location, and wherein the workpiece surface location is centered between the second workpiece surface locations.

2. The system of claim 1, wherein the laser pointer comprises a water-resistant laser pointer.

3. The system of claim 1, wherein the laser beam contacts the workpiece surface at the workpiece surface location.

4. The system of claim 1, wherein the laser beam contacts the workpiece surface at a second workpiece surface location located a distance from the workpiece surface location.

5. The system of claim 1, wherein the laser pointer comprises a laser pointer housing mounted to the ultrasonic transducer.

6. The system of claim 5, wherein the laser pointer further comprises a plurality of lasers connected to the laser pointer housing, and arranged circumferentially around the ultrasonic transducer.

7. The system of claim 5, wherein the laser pointer further comprises a laser connected to the laser pointer housing, and arranged coaxially with the ultrasonic transducer.

8. The system of claim 1, further comprising a manipulator system to which the ultrasonic transducer is connected.

9. The system of claim 8, wherein the manipulator comprises a robotic multi-axis manipulator system.

10. A system for non-contact inspecting a workpiece that includes a workpiece surface, comprising:

a manipulator system;

an ultrasonic inspection system comprising an ultrasonic transducer that is connected to the manipulator system, that directs sound waves along a first trajectory into the workpiece, and that senses reflected sound waves to detect a workpiece defect, wherein the sound waves intersect the workpiece surface at a workpiece surface location; and

a laser pointer connected to the ultrasonic transducer, wherein the laser pointer directs a laser beam along a second trajectory and against the workpiece surface to visually mark the workpiece surface location associated with and indicative of the workpiece defect;
wherein the first trajectory is substantially parallel to the second trajectory and wherein the laser beam is one of a plurality of laser beams directed against the workpiece surface by the laser pointer, wherein each laser beam contacts the workpiece surface at a respective second workpiece surface location, and wherein the workpiece surface location is located between the second workpiece surface locations.

11. The system of claim 10, wherein the laser pointer comprises a water-resistant laser pointer.

12. The system of claim 10, wherein the laser beam contacts the workpiece surface at the workpiece surface location.

13. The system of claim 10, wherein the laser beam contacts the workpiece surface at a second workpiece surface location disposed a distance from the workpiece surface location.

14. The system of claim 10, wherein the laser pointer comprises a plurality of lasers connected to a laser pointer housing, and arranged circumferentially around the ultrasonic transducer.

15. The system of claim 10, wherein the laser pointer comprises a laser connected to a laser pointer housing, and arranged coaxially with the ultrasonic transducer.

16. The system of claim 10, wherein the manipulator system comprises a robotic multi-axis manipulator.