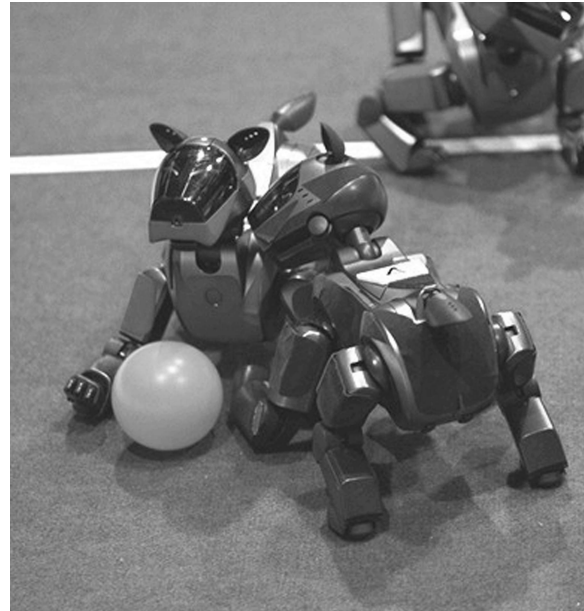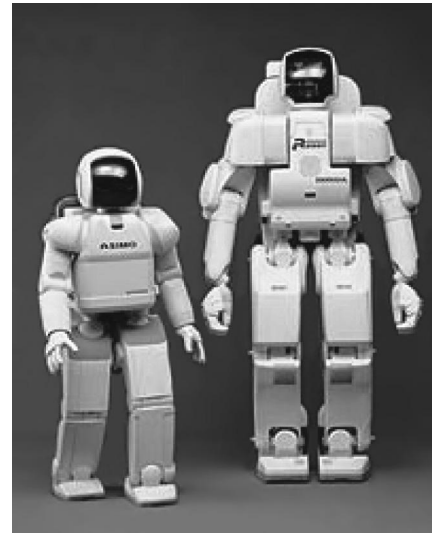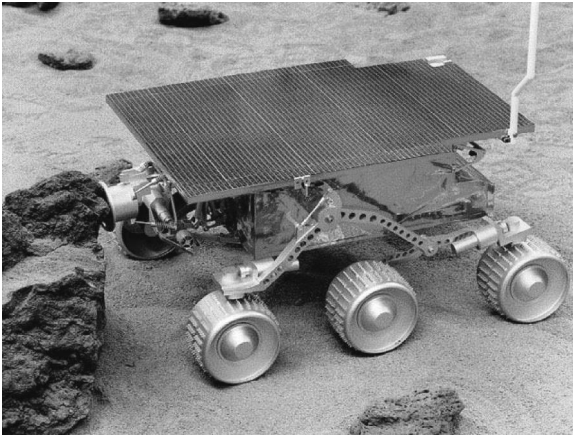# Robotics

Chapter 25

Outline

Robots, Effectors, and Sensors
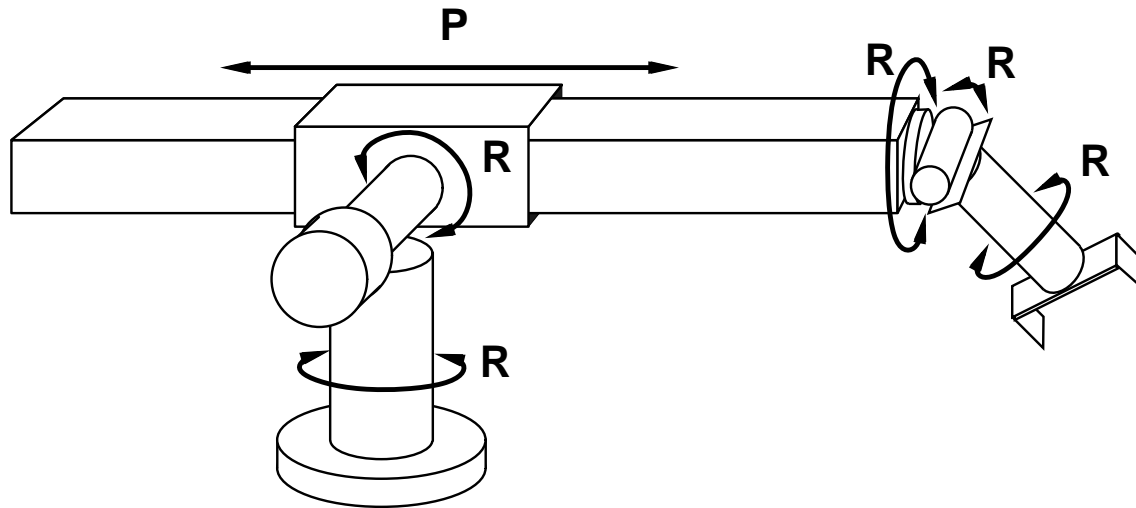
Localization and Mapping

Motion Planning

Mobile Robots
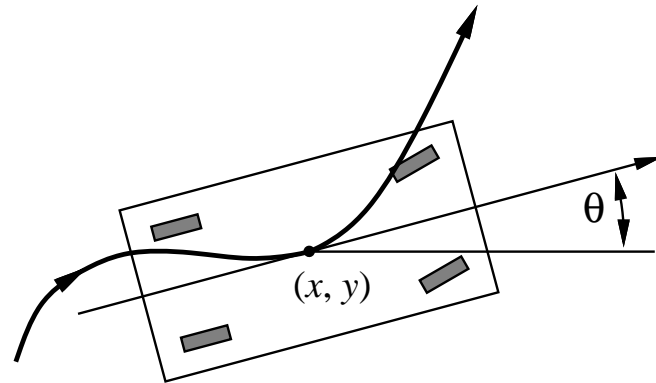
Manipulators

Configuration of robot specified by 6 numbers

   $\Rightarrow$ 6 degrees of freedom (DOF)

6 is the minimum number required to position end-effector arbitrarily.
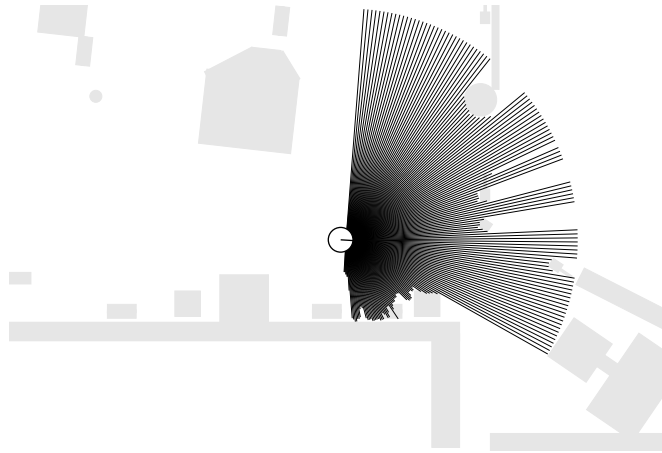For dynamical systems, add velocity for each DOF.

Non-holonomic robots

A car has more DOF (3) than controls (2), so is non-holonomic;
cannot generally transition between two infinitesimally close configurations

Sensors

Range finders: sonar (land, underwater), laser range finder, radar (aircraft), tactile sensors, GPS
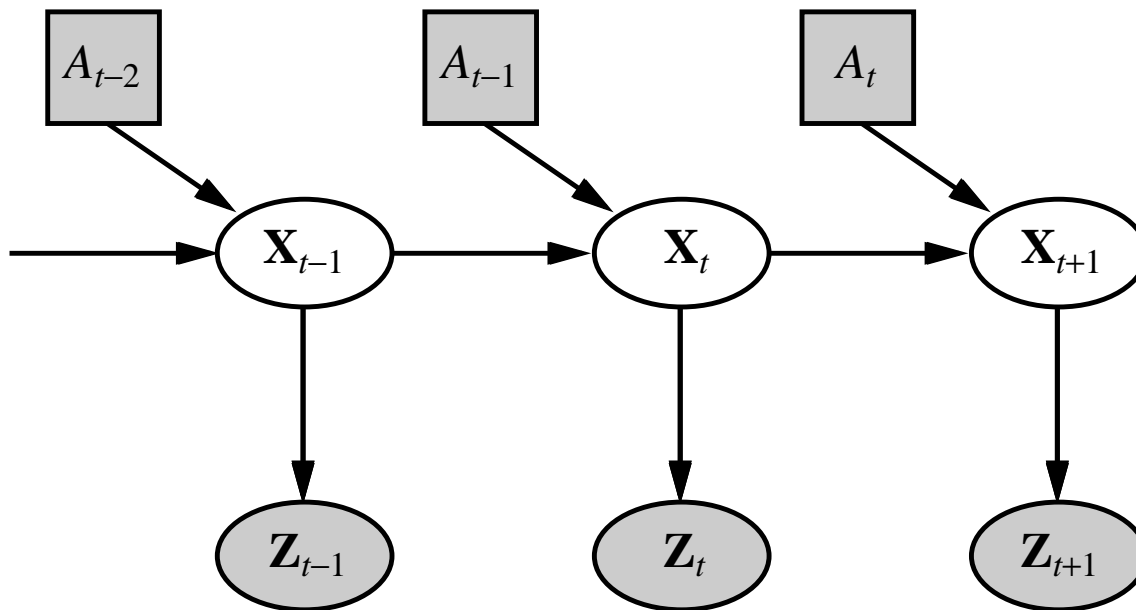
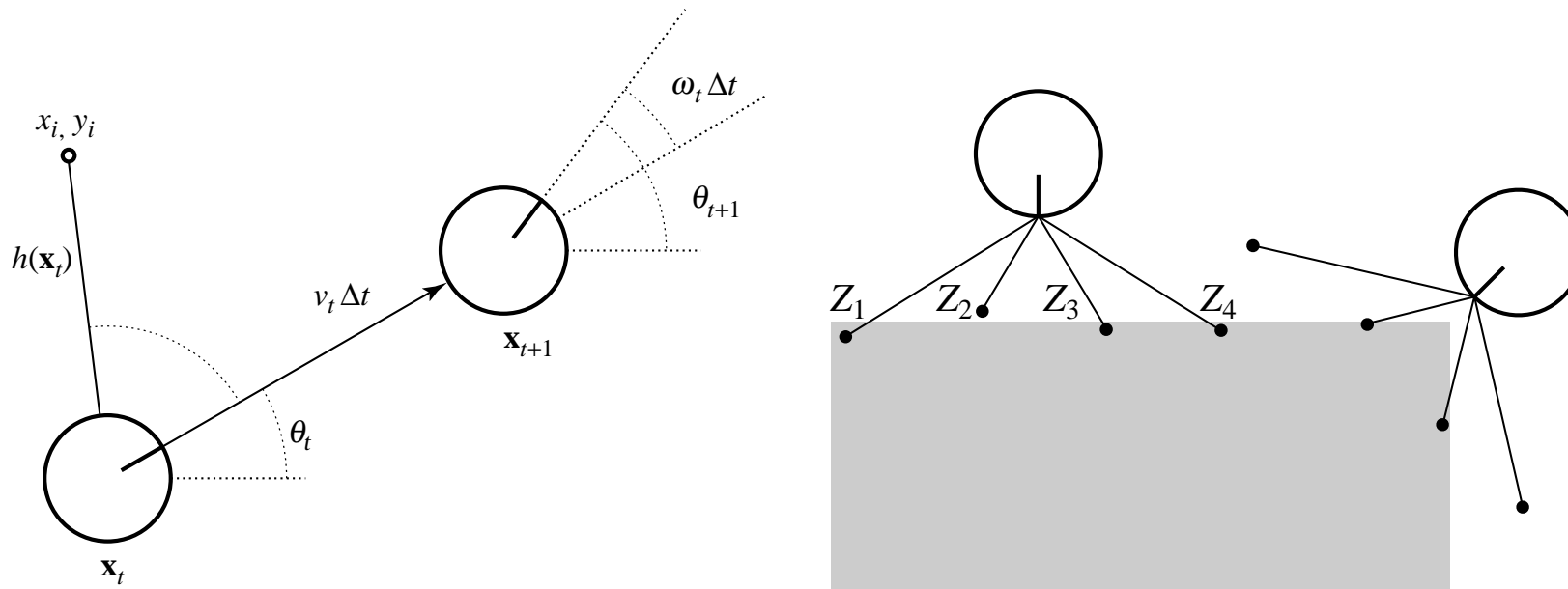

Imaging sensors: cameras (visual, infrared)
Proprioceptive sensors: shaft decoders (joints, wheels), inertial sensors, force sensors, torque sensors

Localization—Where Am I?

Compute current location and orientation (pose) given observations:
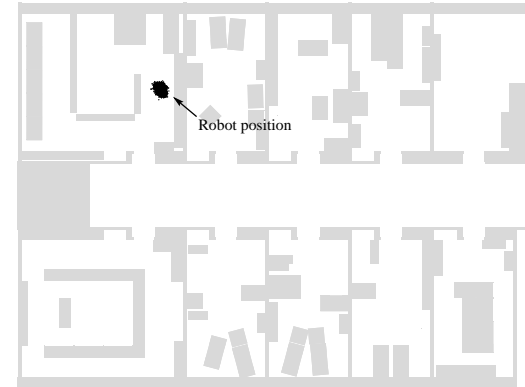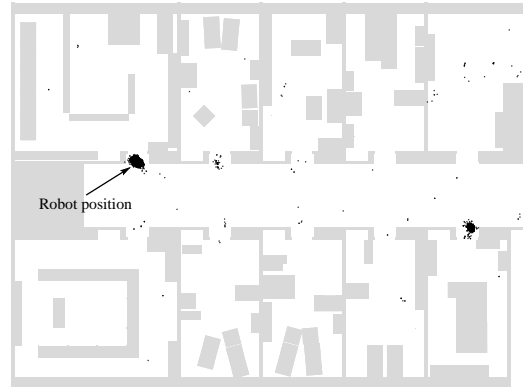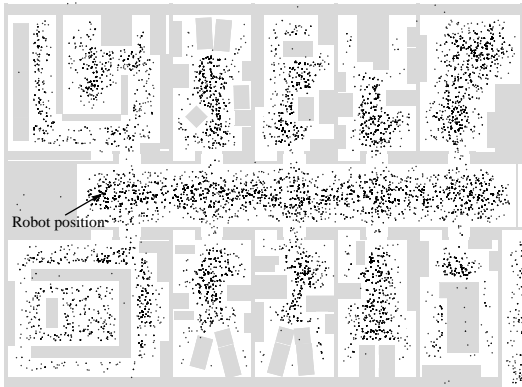
Localization contd.

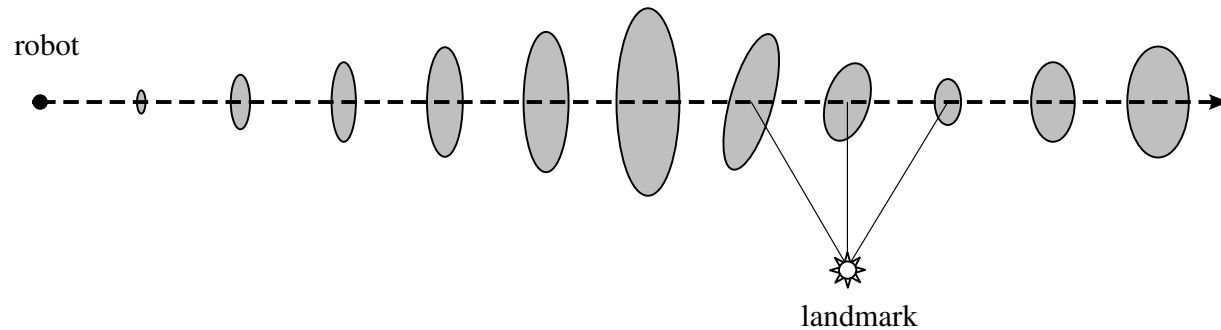Assume Gaussian noise in motion prediction, sensor range measurements

Localization contd.

Can use particle filtering to produce approximate position estimate

Localization contd.

Can also use extended Kalman filter for simple cases:

robot

landmark

Assumes that landmarks are *identifiable*—otherwise, posterior is multimodal

Mapping

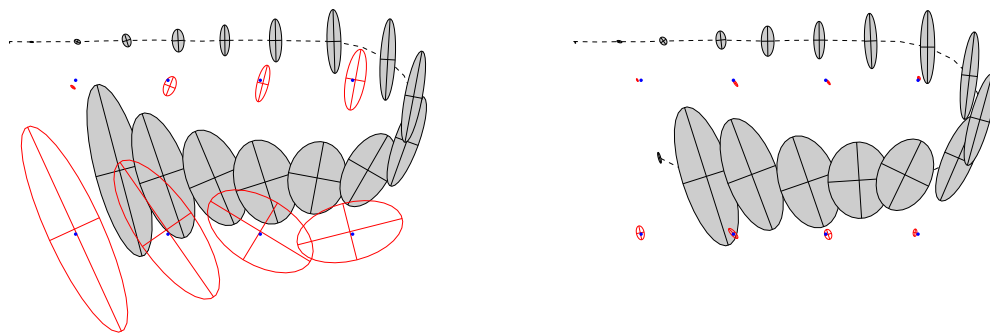Localization: given map and observed landmarks, update pose distribution
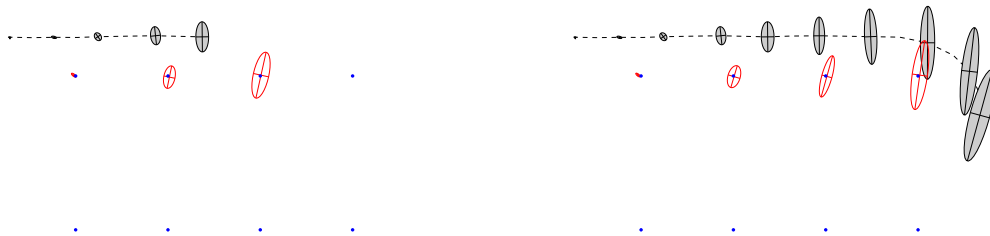
Mapping: given pose and observed landmarks, update map distribution

SLAM: given observed landmarks, update pose and map distribution
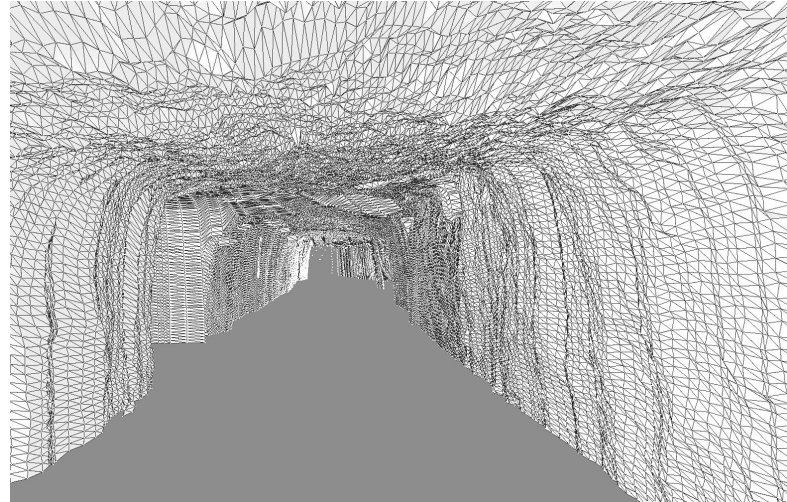
Probabilistic formulation of SLAM:
    add landmark locations $L_1, \ldots, L_k$ to the state vector,
    proceed as for localization
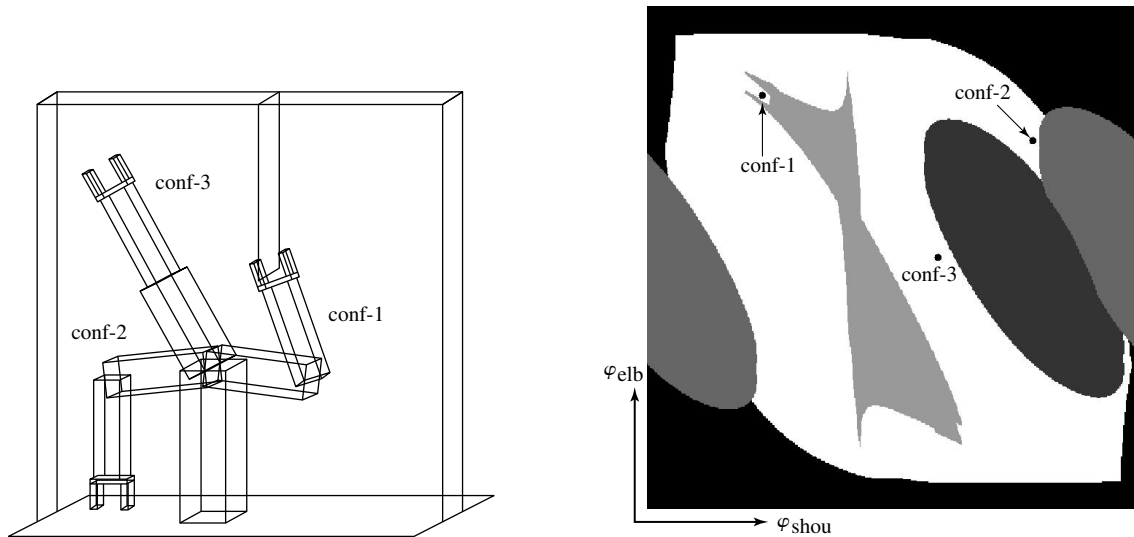
Mapping contd.

3D Mapping example

Motion Planning

Idea: plan in configuration space defined by the robot's DOFs

Solution is a point trajectory in free C-space

Configuration space planning

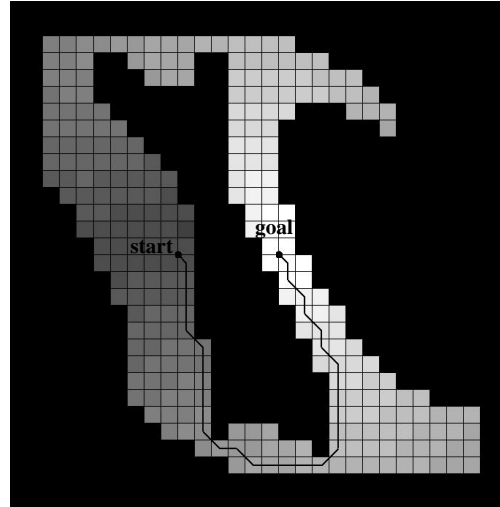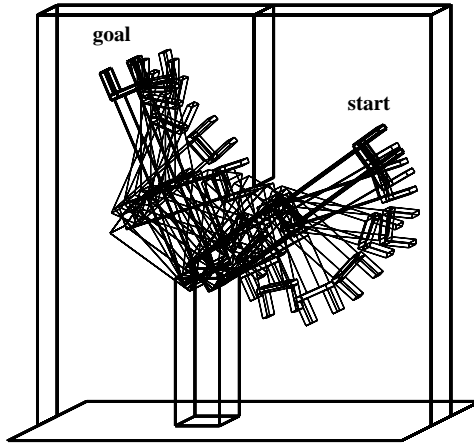Basic problem: ∞^d states! Convert to **finite** state space.

Cell decomposition:
    divide up space into simple cells,
    each of which can be traversed "easily" (e.g., convex)

Skeletonization:
    identify finite number of easily connected points/lines
    that form a graph such that any two points are connected
    by a path on the graph
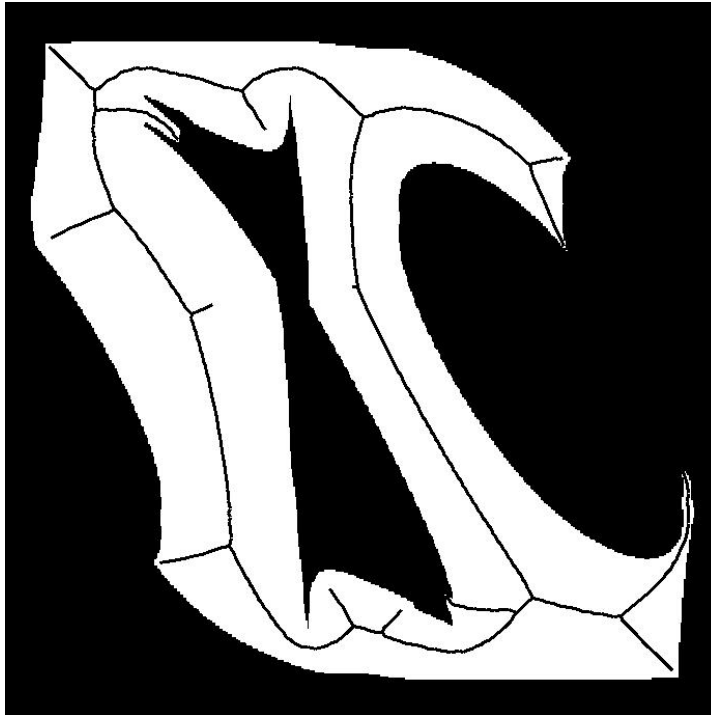
Cell decomposition example

Problem: may be no path in pure freespace cells
Solution: recursive decomposition of mixed (free+obstacle) cells
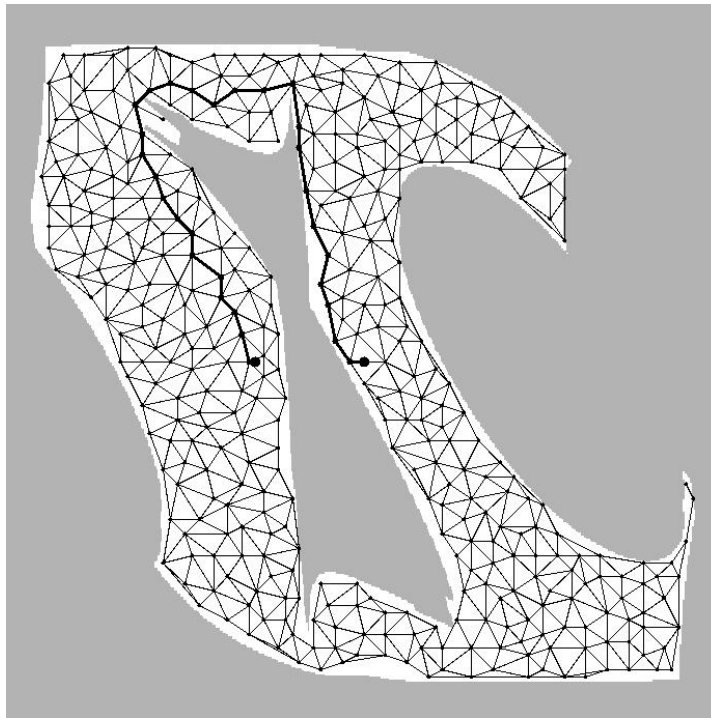
Skeletonization: Voronoi diagram

Voronoi diagram: locus of points equidistant from obstacles

Problem: doesn't scale well to higher dimensions

Skeletonization: Probabilistic Roadmap

A probabilistic roadmap is generated by generating random points in C-space and keeping those in freespace; create graph by joining pairs by straight lines

Problem: need to generate enough points to ensure that every start/goal pair is connected through the graph

Summary

The rubber hits the road

Mobile robots and manipulators

Degrees of freedom to define robot configuration

Localization and mapping as probabilistic inference problems
   (require good sensor and motion models)

Motion planning in configuration space
   requires some method for finitization