

FDS 2024: Field and service robotics
Homework 1

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Question 1: Consider the ATLAS robot from Boston Dynamics. If ATLAS actuators can produce unbounded torques, establish whether each of the following statements is true or not, and briefly justify your answer.



Figure 1: Atlas Robot

Part (a): While standing, ATLAS is fully actuated.

The Atlas robot is a bipedal robot; it takes the human body as its inspiration. As stated on the course slides[2]: "The human body has an incredible number of actuators (muscles), and in many cases has multiple muscles per joint;..." it is therefore possible to assume that similar to the human body, Atlas has a large number of actuators, which make it capable, in the condition of contact with the ground, of performing an instantaneous acceleration in an arbitrary direction in q , where q are the variables of the model (in this case position and orientation of the robot itself). Indeed, we recall that[2]: "... we will refer to underactuation as a property of the mathematical model used to model our robotic system." The ground contact condition is crucial for full actuation.

Therefore, Atlas is fully actuated while standing.

Part (b): While doing backflip, ATLAS is fully actuated.

As stated on the slides[2]: "[The human body] despite having more actuators than position variables, when we jump into the air there is no combination of muscle inputs that can change the ballistic trajectory of the centre of mass (apart from aerodynamic effects)." The same can be said for the Atlas robot. Underactuation and full actuation are closely related to the current state, time and constraints. In this case, the absence of the ground contact constraint makes the robot underactuated in this condition. Recall, however, that to define an underactuated system (course slide[2]): "a system is underactuated if it is underactuated in all states and times". So Atlas is not an underactuated system, but it is underactuated while doing a backflip.

Therefore, Atlas is not fully actuated while doing backflip.

Question 2: Consider the planar mechanism on the left and the spatial mechanism on the right. Determine the number of the degrees of freedom for each mechanism, comparing the result with your intuition about the possible motions of these mechanisms. For each mechanism, write its configuration space topology.

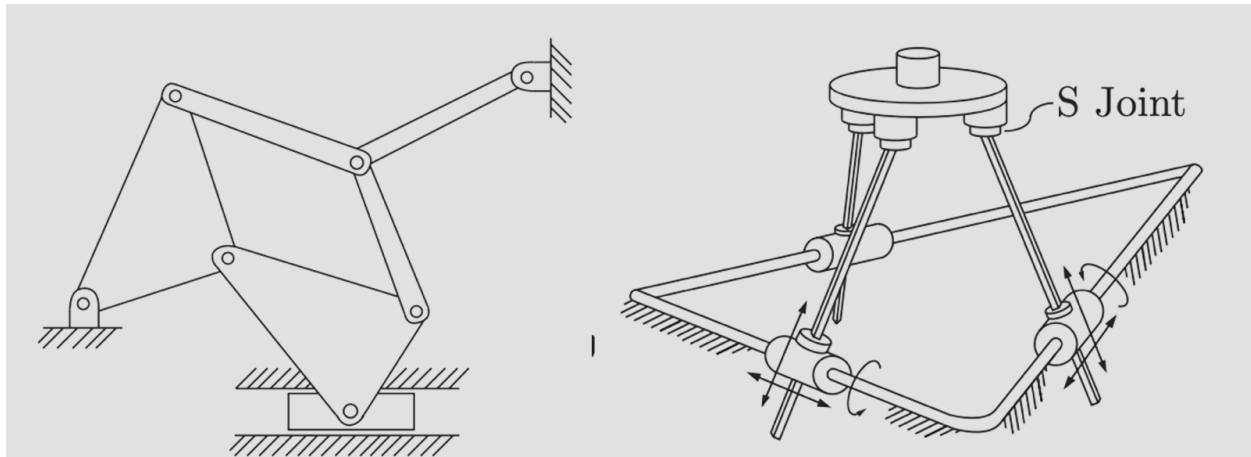


Figure 2: Mechanisms

To calculate the number of Dofs of the two mechanisms, Grübler's formula can be used

$$DoFs = m(N - 1 - J) + \sum (f_i)$$

For the the planar mechanism applies:

$$m = 3$$

$$N = 7$$

$$J = 9$$

8 Revolute joints ($f_i = 1$), 1 prismatic ($f_i = 1$).

So the Grübler's formula:

$$DoFs = 3(7 - 1 - 9) + 9 * (1) = 0$$

Since this formula holds only if all joint constraints are independent in this case the formula provides a lower bound on the number of DoFs. in fact, according to intuition, the mechanism does not appear to be a structure, rather it appears to have one degree of freedom.

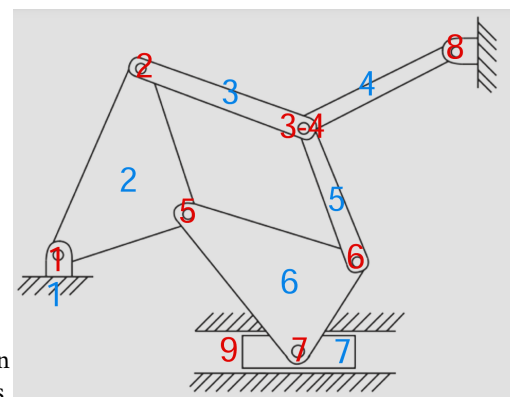


Figure 3: Planar mechanism

The configuration space topology

Being a structure, the topological space is null, no degrees of freedom.

For the the spatial mechanism applies:

$$m = 6$$

$$N = 8$$

$$J = 9$$

3 prismatic joints ($f_i = 1$), 3 Cylindrical ($f_i = 2$) 3 Spherical ($f_i = 3$).

So the Grübler's formula:

$$DoFs = 6(8 - 1 - 9) + 3 * (1) + 3 * (2) + 3 * (3) = 6$$

According to intuition, the mechanism would appear to have 6 degrees of freedom (complete freedom of the end-effector in space), as confirmed by the formula.

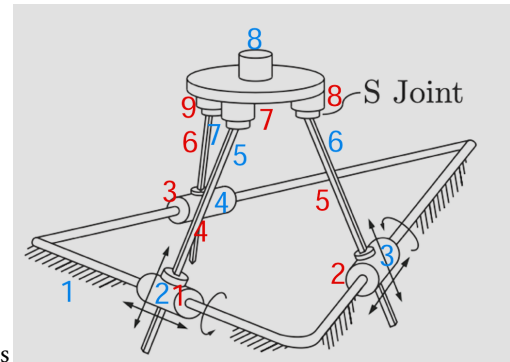


Figure 4: Spatial mechanism

The configuration space topology

$$R^3 * T^3$$

Since the mechanism has 6 Dofs, the topology space will have the same dimensions. It is possible to choose $n = 6$ variables to describe this space, these are some of the variable joints of the mechanism. $R^3 * T^3$ are the space of the 3 Cylindrical joints and have been chosen to describe the topology space of the mechanism.

Question 3: State whether the following sentences regarding underactuation or fully actuation are true or false. Briefly justify your answers.

Part (a): A car with inputs the steering angle and the throttle is underactuated.

Yes. The car cannot generate any acceleration in the space (cannot generate a lateral acceleration). From the slides[2]: "A car is underactuated because it has two control inputs (steering and forward/backward speed) but at least three DoFs given by the planar rigid body chassis".

Part (b): The KUKA youBot system on the slides is fully actuated.

Yes. The KUKA youBot is the combination of a wheeled robot with four independent actuators for each of the wheels and a 5Dofs Robotic arm. It can generate any acceleration in an arbitrary direction in q , by combination of the actuation given by the wheels and the actuation given by the arm joints, it can express any possible acceleration (between the joints max actuation torque) in an arbitrary direction in q (in this case it can be the end_effector variable).

Part (c): The hexarotor system with co-planar propellers is fully actuated.

No. The hexarotor system with co-planar propellers cannot generate any acceleration in the space (cannot generate a lateral acceleration).

Part (d): The 7-DoF KUKA iiwa robot is redundant.

Yes. The 7-DoF KUKA iiwa robot is intrinsically redundant, it has 7 DoFs in a 6 dimensional space, so intrinsically it has 1 Dof exceeding (according to the task it can have more than 1 Dof exceeding, functional redundancy).

Question 4: RRT method

The matlab script contains the solution with a brief explanation of the code. The file is on the github repository: <https://github.com/Andremorgh/FSR2024.git> [1]

The file is in the folder HW1 and it is named **HW1_es4.mlx**.

A high-level abstraction explanation of the implemented programming logic is given here. Run the matlab program directly to view the full operation of the code.

After importing the matrix map and defining some key variables, such as q_f and q_i , there is a while loop to implement the algorithm. The conditions of the while loop are such that the loop stops if the path is created correctly or if the number of iterations exceeds the maximum value. The main steps of the loop are as follows:

1. a random grand point is extracted from the map
2. the point closest to q_{rand} is extracted from the list of points (q_{near})
3. the line in the direction of q_{rand} of length δ starting from q_{near} is calculated
4. with a simple collision detection algorithm, the validity of all points belonging to the line is checked
5. If the collision detection check is successful the end point of the q_{new} line is added to the list of points
6. a check is made for the minimum distance of q_f from the points in the list, if a point is found to be at a distance less than δ an attempt is made to insert q_f into the list of points (checking for collisions on the join line), if the insertion is successful the while loop is aborted.

During the while loop the various points added to the list are printed on the screen on the map plot with the following result:

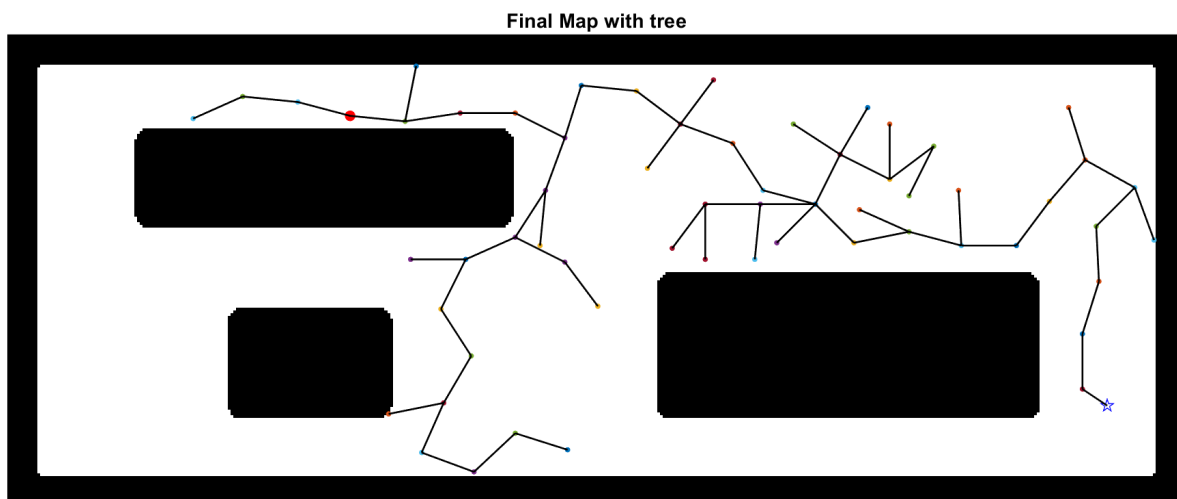


Figure 5: Final Map

If the algorithm is unsuccessful in the maximum number of iterations chosen, it is possible to increment the n_{exec} parameter and repeat the execution. It is also possible to vary the δ parameter to change the step length

Question 5: Numerical navigation method

The matlab script contains the solution with a brief explanation of the code. The file is on the github repository:
<https://github.com/Andremorgh/FSR2024.git> [1]

The file is in the folder HW1 and it is named **HW1_es5.mlx**.

A high-level abstraction explanation of the implemented programming logic is given here. Run the matlab program directly to view the full operation of the code.

First the map is defined as a matrix of 0 (obstacles) 1 (clear road) 2 (goal) 3 (initial position), then some supporting variables for execution. The program is structured of two main phases:

1. numbered map generation, starting from the box with numerical value i are placed in the adjacent boxes (4 or 8 depending on the choice) that do not contain obstacles the value $i+1$, the process is repeated until the map is completed or until the maximum number of iterations is reached (control precaution)
2. path calculation from start point to end point according to the optimal path (at each step we go to a lower numerical value box)

Once these steps are completed, the complete path map is plotted:

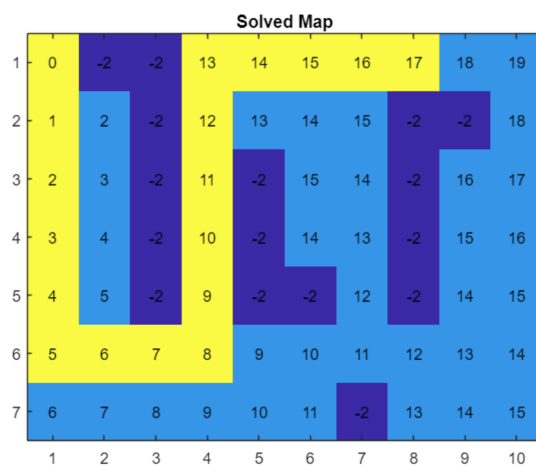


Figure 6: 4 diagonal square

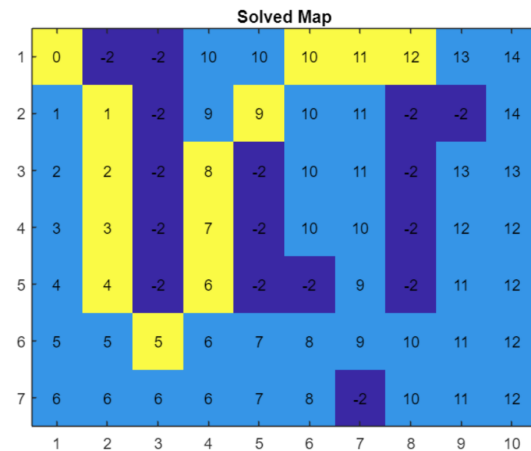


Figure 7: It is immediate to observe how the 8-adjacent box algorithm returns a better result (fewer steps to the goal) diagonal square

It is immediate to observe how the 8-adjacent box algorithm returns a better result (fewer steps to the goal).

References

- [1] Andrea Morghen. FSR2024. 2024. URL: <https://github.com/Andremorgh/FSR2024.git>.
- [2] PRISMA UNINA. FSR_Slides_2024. 2024.