# CSE 276A HW1

Tingyu Shi(A59023729)
Jiajun Li(A16635772)

December 26, 2024

## 1 Video URL

URL: https://youtu.be/wFwZRhoc9JA

## 2 Calibration Strategy

In this part, we investigated the relationship between the motor value and wheel's angular speed for each wheel. We used the following steps for the calibration:

1. For each wheel, test what motor value can make the wheel start to rotate. The following are the corresponding values:

| | Front Left | Front Right | Back Left | Back Right |
|---|---|---|---|---|
| Forward Rotate | 28 | 29 | 39 | 22 |
| Backward Rotate | -26 | -29 | -37 | -17 |

Table 1: motor Values that make wheels start to rotate

2. Find a set of motor values so the robot can move forward/backward straight. The following are the corresponding values:
   - Moving Forward: Front Left: 80 – Front Right: 72 – Back Left: 80 – Back Right: 72
   - Moving Backward: Front Left: -80 – Front Right: -72 – Back Left: -80 – Back Right: -72
3. Measure the velocities when the robot moves forward/backward straight. From our measurements, they are 0.3 m/s and -0.3 m/s. Since each wheel has a radius of 3 cm, each wheel's angular velocity is $\omega = \frac{0.3\ m/s}{0.03\ m} = 10\ rad/s$ and $\omega = \frac{-0.3\ m/s}{0.03\ m} = -10\ rad/s$
4. Now, we can come up with 4 piecewise linear functions for each wheel using linear regression.

### 2.1 Front Left Wheel

$$\omega_{fl} = \left\{ \begin{array}{lr} 0.19231c - 5.38462 & \text{if } c \geq 28 \\ 0.18519c + 4.81481 & \text{if } c \leq -26 \\ 0 & ELSE \end{array} \right\} \tag{1}$$

### 2.2 Front Right Wheel

$$\omega_{fr} = \begin{Bmatrix} 0.23256c - 6.74419 & \text{if } c \geq 29 \\ 0.23256c + 6.74419 & \text{if } c \leq -29 \\ 0 & ELSE \end{Bmatrix} \tag{2}$$

### 2.3 Back Left Wheel

$$\omega_{bl} = \begin{Bmatrix} 0.24390c - 9.51220 & \text{if } c \geq 39 \\ 0.23256c + 8.60465 & \text{if } c \leq -37 \\ 0 & ELSE \end{Bmatrix} \tag{3}$$

### 2.4 Back Right Wheel

$$\omega_{br} = \begin{Bmatrix} 0.20000c - 4.40000 & \text{if } c \geq 22 \\ 0.18182c + 3.09091 & \text{if } c \leq -17 \\ 0 & ELSE \end{Bmatrix} \tag{4}$$

## 3 Kinematic Model

We used the basic kinematic model for our project:

$$\begin{bmatrix} v_x \\ v_y \\ w_z \end{bmatrix} = \frac{r}{4} \begin{bmatrix} 1 & 1 & 1 & 1 \\ -1 & 1 & 1 & -1 \\ -\frac{1}{(l_x+l_y)} & \frac{1}{(l_x+l_y)} & -\frac{1}{(l_x+l_y)} & \frac{1}{(l_x+l_y)} \end{bmatrix} \begin{bmatrix} w_1 \\ w_2 \\ w_3 \\ w_4 \end{bmatrix}$$

where $w_i$ are the wheels' angular velocities $i \in \{1, 2, 3, 4\}$,
$r$ is the radius of the wheels,
$l_x$ is the half of the distance between front wheels,
$l_y$ is the half of the distance between front wheels and rear wheels,
$v_x, v_y$ are the linear velocity of the robot in the direction of $x$ and $y$,
$w_z$ is the angular velocity of the robot.

We measured the robot's parameters and got $l_x = 6.75cm, l_y = 5.5cm$ and $r = 3cm$. To make the robot move straight, we set a uniform value for $w_i$ at 10 $rad/s$, and the calculated forward speed was 0.3 $m/s$, which matched the measured speed. However, there were some errors when testing the rotation speed. The calculated rotation speed was 2.45 $rad/s$, but the robot experienced over-rotation when this speed was applied. The measured rotation speed was actually 2.06 $rad/s$ for clockwise rotation and 2.026 $rad/s$ for counterclockwise rotation. We used the measured rotation speed for HW1.

## 4 Navigation Algorithm

To move between 2 states($(x_i, y_i, \theta_i) \to (x_j, y_j, \theta_j)$), we simplify it into a 3-step procedure:

1. Rotate the robot from $\theta_i$ to $arctan(\frac{y_j - y_i}{x_j - x_i})$ – First Rotation

2. Move forward from $(x_i, y_i)$ to $(x_j, y_j)$

3. Rotate the robot from $arctan(\frac{y_j - y_i}{x_j - x_i})$ to $\theta_j$ – Second Rotation

```python
def angle_process(start_angle, end_angle, no_rotation_range):
    angle_diff = end_angle - start_angle
    angle_diff = (angle_diff + math.pi) % (2 * math.pi) - math.pi
    if (-no_rotation_range <= angle_diff <= no_rotation_range):
        rotate_angle = angle_diff
        direction = 'no'
    if angle_diff < -no_rotation_range:
        rotate_angle = -angle_diff
        direction = 'clockwise'
    else:
        rotate_angle = angle_diff
        direction = 'counterclockwise'
    return rotate_angle, direction
```

Function `angle_process` calculates how to rotate from `start_angle` to `end_angle` with the least amount of rotation, it returns the rotation angle and direction. Because the robot is not always precise, we can set a `no_rotation_range` so that if the rotation angle is so small, the robot will not rotate. The function is used for step 1 and 3.

```python
def get_movement_info(x0, y0, theta0, x1, y1, theta1, no_rotation_range,
   scaling_factor):
    dx = x1 - x0
    dy = y1 - y0
    distance = math.sqrt((dx ** 2) + (dy ** 2)) * scaling_factor
    target_angle = math.atan2(dy, dx)
    first_rotation_angle, first_rotation_direction = angle_process(theta0,
   target_angle, no_rotation_range)
    assert 0<= first_rotation_angle <= 2 * math.pi
    second_rotation_angle, second_rotation_direction = angle_process(
   target_angle, theta1, no_rotation_range)
    assert 0<= second_rotation_angle <= 2 * math.pi
    return distance, first_rotation_angle, first_rotation_direction,
   second_rotation_angle, second_rotation_direction
```

Given $(x_i, y_i, \theta_i)$ and $(x_j, y_j, \theta_j)$, function `get_movement_info` returns the rotation angle and direction of the first and the second rotation and the distance between $(x_i, y_i)$ and $(x_j, y_j)$. We can also set a `scaling_factor` to scale up/down the distance.
Given the angles and directions of the first and second rotations, along with the forward distance, we can determine the direction and execution time for each of the four motors based on the velocities mentioned in the kinematic model (forward: 0.3 m/s, backward: 0.3 m/s, clockwise: 2.06 rad/s, counterclockwise: 2.026 rad/s).

## 5 Code

We submitted the zipped `rb5_ros2_control` folder. You may find the following code files in path `rb5_ros2_control/rb5_ros2_control`:

- `wheel_start_test.py`: Measure the motor values that make wheels start to rotate.
- `forward_calibration.py`: Given a set of motor values that can make the robot move forward straight, measure the robot's moving velocity.

- `backward_calibration.py`: Given a set of motor values that can make the robot move backward straight, measure the robot's moving velocity.
- `clockwise_rotation_calibration.py`: Measure the robot's clockwise rotation angular velocity.
- `counterclockwise_rotation_calibration.py`: Measure the robot's counterclockwise rotation angular velocity.
- `hw1_code_version1.py`: Run this file for HW1.

## 6 Comments

The algorithm allows the robot to traverse between different waypoints. However, it deviates slightly for point (-2, 1, 0) and (-2, -2, -1.57). The deviation should be less than 10 cm.
The errors may come from the following aspects:

- Inaccurate measurement of robot rotation angular speeds and moving forward/backward speed.
- Motors may have different performance for different battery levels.

The following are possible improvements:

- We can measure more points for calibration.
- Currently, we set 4 motor values as hyperparameters and they do not change while the robot is moving. Later, we can design an algorithm to give different motor values to different wheels at different locations. This can allow the robot to traverse the waypoints more efficiently.