

Introduction

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Robot

- From the Czech word *robita* meaning *forced labor*.
- first appeared in 1920 in the play *R.U.R.* '*Rossum's Universal Robots*' by writer Karl Čapek



Source: <http://www.umich.edu/engb415/literature/pontee/RUR/RURsmry.html>

Autonomy / Autonomous Robot

Autonomous: from the Greek words *auto* (self) and *nomos* (law). Today is interpreted as self governed.



Definitions of Robot

Wikipedia a machine – especially one programmable by a computer – capable of carrying out a complex series of actions automatically
(<https://en.wikipedia.org/wiki/Robot>).

Merriam-Webster a machine that resembles a living creature in being capable of moving independently (as by walking or rolling on wheels) and performing complex actions (such as grasping and moving objects)
(<https://www.merriam-webster.com/dictionary/robot>)

RIA A robot is defined as a reprogrammable, multifunctional manipulator designed to move material, parts, tools, or specialized devices through various programmed motions for the performance of a variety of tasks (RIA, 1979).

Video Interlude...



Robot Taxonomies

Mobility

- aerial
- wheeled
- legged
- marine

Applications

- industrial
- service
- medical
- field
- social



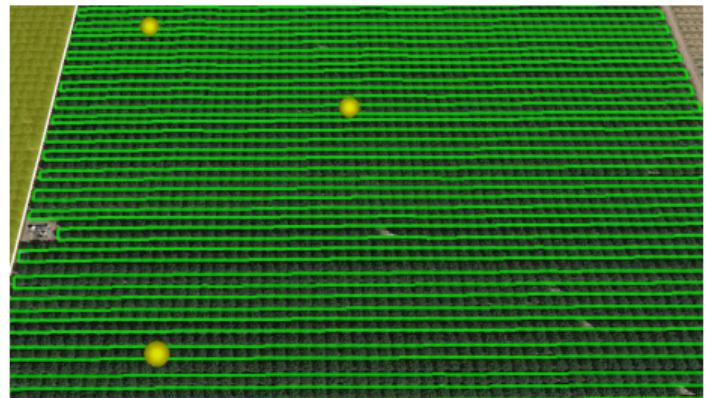
Mobile Robots

- a robot not constrained to remain in a preassigned area
- not a formal or exhaustive definition
- may operate in a structured or unstructured environment



Functionalities

- Planning
- Localization
- Navigation and Obstacle Avoidance



Robots Feature Multiple Interacting Subsystems



Open loop operation

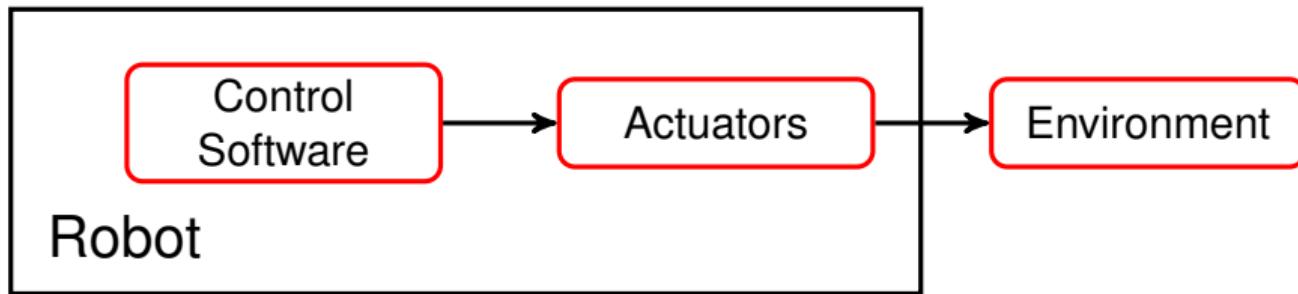


Figure: A robot operating in open loop.



Robot Modeling: Agent View

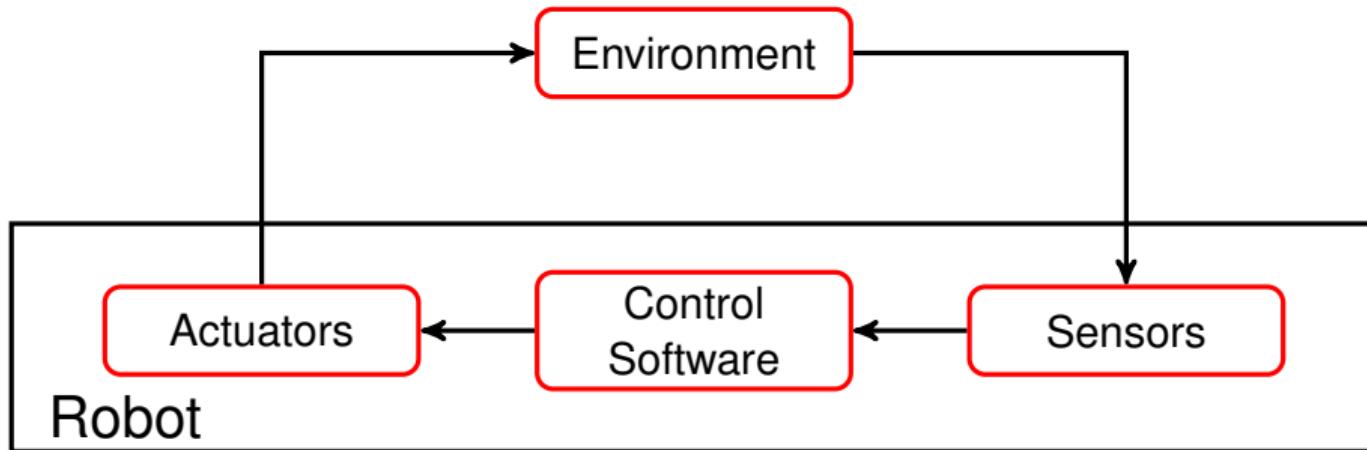


Figure: An agent view of a mobile robot.



Robot Modeling: Dynamical System View

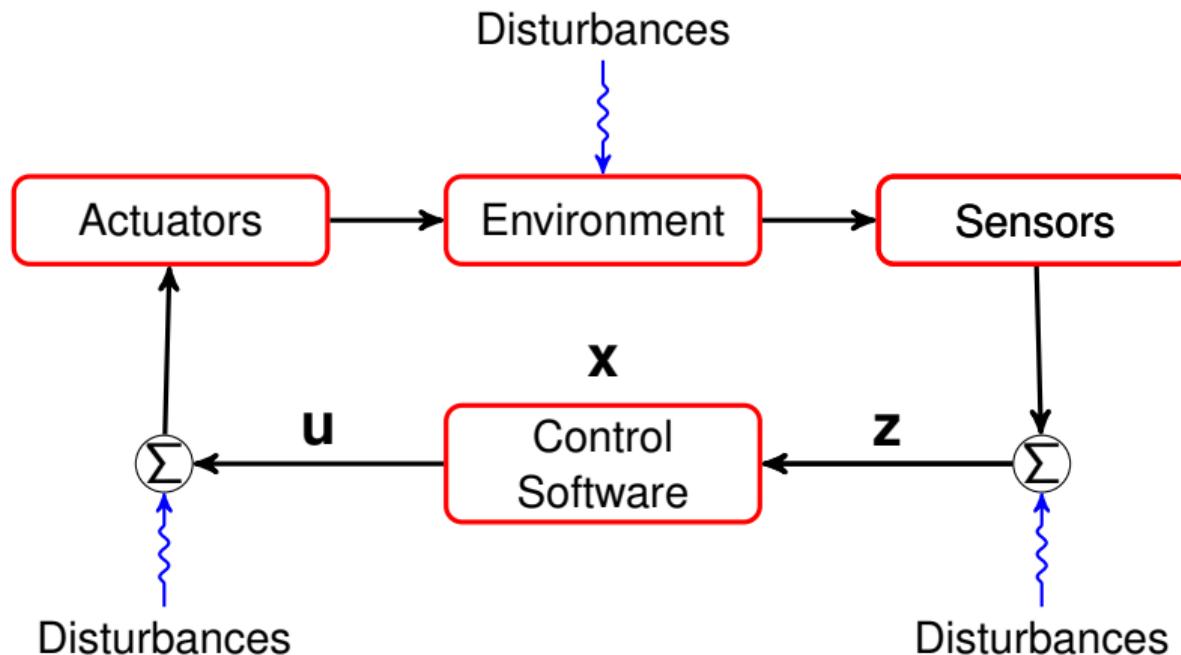
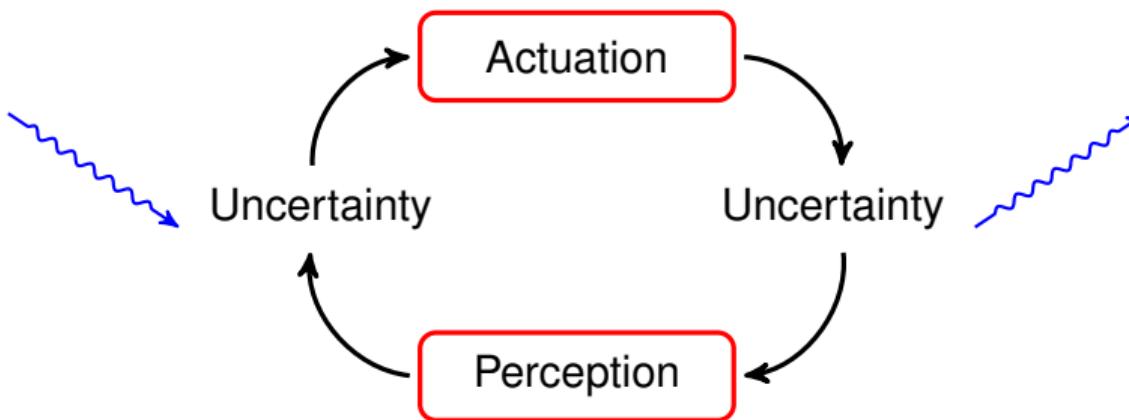


Figure: A dynamical system view of a mobile robot.



Uncertainty Cycle



Dynamical Systems Model

Dynamical system : a system whose behavior changes over time

Feedback : coupling between two systems influencing each other

State of a robot: position, velocity, joint values, ...

- ✗ state of the system
- ✗ input given to the system (actuators)
- ✗ information extracted from the system (sensors)

Dynamical system equations

Continuous time model:

$$\dot{\mathbf{x}} = f(\mathbf{x}, \mathbf{u}, t) \quad (1)$$

$$\mathbf{z} = h(\mathbf{x}, \mathbf{u}, t) \quad (2)$$

Eq. (1) is the state transition equation and Eq. (2) is the state observation equation

Discrete time model:

$$\mathbf{x}_t = f(\mathbf{x}_{t-1}, \mathbf{u}_t, t) \quad (3)$$

$$\mathbf{z}_t = h(\mathbf{x}_t, \mathbf{u}_t, t). \quad (4)$$

Time Invariant Systems

Continuous equations

$$\dot{\mathbf{x}} = f(\mathbf{x}, \mathbf{u}) \quad (5)$$

$$\mathbf{z} = h(\mathbf{x}, \mathbf{u}) \quad (6)$$

Discrete equations

$$\mathbf{x}_t = f(\mathbf{x}_{t-1}, \mathbf{u}_t) \quad (7)$$

$$\mathbf{z}_t = h(\mathbf{x}_t, \mathbf{u}_t) \quad (8)$$

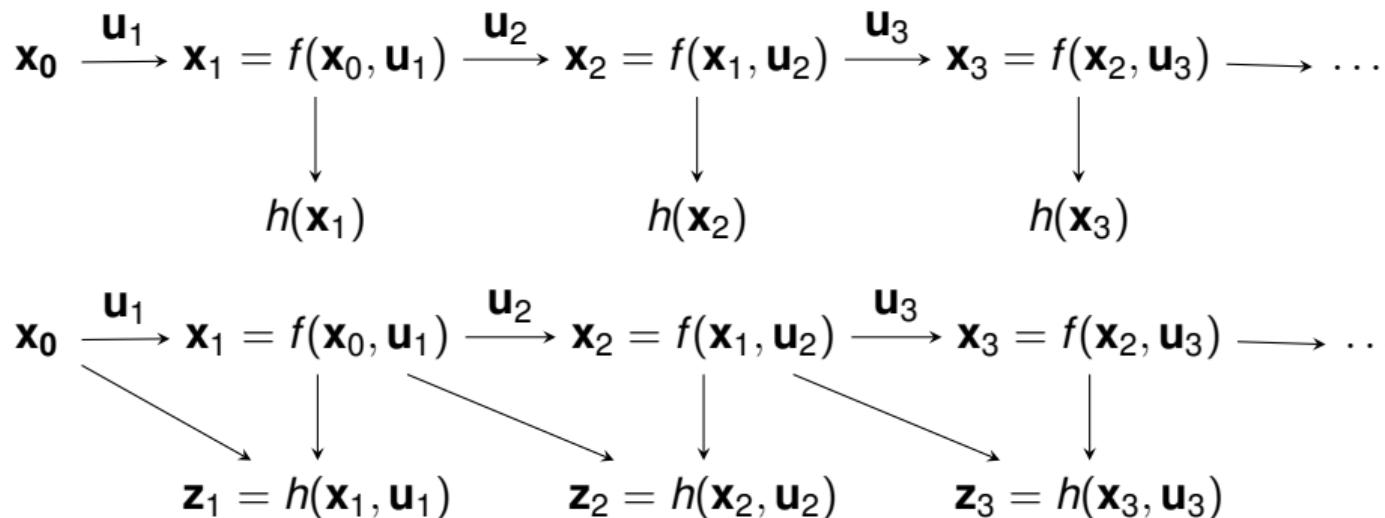
Assumption of sensor reading independent from the input

$$\mathbf{z}_t = h(\mathbf{x}_t) \quad (9)$$

State evolution

$$\mathbf{x}_0 \xrightarrow{\mathbf{u}_1} \mathbf{x}_1 = f(\mathbf{x}_0, \mathbf{u}_1) \xrightarrow{\mathbf{u}_2} \mathbf{x}_2 = f(\mathbf{x}_1, \mathbf{u}_2) \xrightarrow{\mathbf{u}_3} \mathbf{x}_3 = f(\mathbf{x}_2, \mathbf{u}_3) \rightarrow \dots \rightarrow \mathbf{x}_n = f(\mathbf{x}_{n-1}, \mathbf{u}_n)$$


State and sensor acquisition



Robot (software) Controller

- our eventual high level objective would be to get a function π that defines the action to take in each state so that the robot reaches a desired state (planning view)

$$\pi(\mathbf{x}_t) = \mathbf{u}_{t+1}$$

- the state, however, is almost invariably not known with certainty. So we also need an algorithm to determine the state (estimation view)

$$\mathbf{x}_t = g(\mathbf{x}_1, \dots, \mathbf{x}_{t-1}, \mathbf{z}_1, \dots, \mathbf{z}_{t-1})$$

- these functions are computed by the algorithms/programs we will study in this course
- must be pursued in parallel**

Robot Software Architecture

- principle for modular decomposition of a complex software system
- multiple approaches and solutions
- ROS based architectures emphasize data exchange and asynchronous interactions between modules

