Sapienza Università di Roma

Department of Computer, Control and Management Engineering

Real-Time Safe Bipedal Robot Navigation using Linear Discrete Control Barrier Functions

Autonomous and Mobile Robotics

Students:

Eugenio Bugli

Damiano Imola

Salvatore Michele Rago

Academic Year 2024/2025

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1 Introduction

Eugenio:
Humanoid robots are inherently underactuated thanks to to unilateral ground contacts thus a strong coupling exists between path planning and gait control. A path is considered safe if the robot does not collide with any obstacle and its dynamics and physical limitations are respected. Due to the high complexity of humanoids, we cannot decouple path planning from motion control without taking into account the dynamics. We should solve gait optimization problems based on the robot's full order model or the reduced one. Due to computational complexity, reduced order models such the Linear Inverted Pendulum (LIP) are often employed. In our case, since Control Barrier Functions are employed to ensure safety in path planning, we will pre-compute heading angles ans use approximated linead DCBFs. This is needed since we may have problems at computation level due to the non linearity of kinematics and path constraints.

Salvatore:
The term *humanoid* refers to a robot with structure and kinematics similar to a human body. It is designed for locomanipulation and represent the best choice to navigate and interact in an environment that is structured for humans.
Real-time safe navigation is a crucial task for humanoid robots in real-world applications. A path is considered safe if it does not collide with any obstacle while fulfilling the robot's dynamics and physical constraints. In order to carry out such complex task in real-time, path planning is usually decoupled from gait control, resulting in a significant reduction of the computational load.
The aim of this work is to implement the solution proposed by Peng et al. in "Real-Time Safe Bipedal Robot Navigation using Linear Discrete Control Barrier Functions", which consists in a unified safe path and gait planning framework to be executed in real-time. It models the humanoid's walking dynamics by a Linear Inverted Pendulum, and leverages Model Predictive Control and Control Barrier Functions to deliver a collision-free path while satisfying specific constraints.
In the following chapters, we will delve into the details of this approach, discuss the results, and propose some improvements.

2 LIP

Eugenio:
This reduced model assumes that during the motion the Center of Mass (CoM) will have a constant height H.

$$\dot{v}_x = \frac{g}{H}(p_x - f_x) \qquad \dot{v}_y = \frac{g}{H}(p_y - f_y) \tag{1}$$

With (p_x, p_y) we denote the position of the CoM and with (v_x, v_y) its velocity with respect to the x-axis and y-axis. The stance foot position, which is the position in which both feets are in contact with the ground, is denoted with (f_x, f_y).

Given the position (p_{x_k}, p_{y_k}) and velocities (v_{x_k}, v_{y_k}) of the CoM at the k-th step, the closed-form solutions of the step-to-step discrete dynamics can be written as follows :

$$\begin{bmatrix} p_{x_{k+1}} \\ v_{x_{k+1}} \end{bmatrix} = A_d \begin{bmatrix} p_{x_k} \\ v_{x_k} \end{bmatrix} + B_d f_{x_k} \qquad \begin{bmatrix} p_{y_{k+1}} \\ v_{y_{k+1}} \end{bmatrix} = A_d \begin{bmatrix} p_{y_k} \\ v_{y_k} \end{bmatrix} + B_d f_{y_k} \tag{2}$$

Where $\beta = \sqrt{\frac{g}{H}}$ and the two matrices are:

$$A_d = \begin{bmatrix} cosh(\beta T) & \frac{sinh(\beta T)}{\beta} \\ \beta sinh(\beta T) & cosh(\beta T) \end{bmatrix} \qquad B_d = \begin{bmatrix} 1 - cosh(\beta T) & -\beta sinh(\beta T) \end{bmatrix} \tag{3}$$

By defining the state of our system as $x = [p_x, v_x, p_y, v_y, \theta]^T \in \mathbb{R}^5$ and the control input as $u = [f_x, f_y, \omega]^T \in \mathbb{R}^3$, where θ is the heading angle and ω is its turning rate, the step-to-step dynamics of the 3D-LIP model is written as follows:

$$x_{k+1} = A_L x_k + B_L u_k \tag{4}$$

Where the two matrices are defined as follows:

$$A_L = \begin{bmatrix} A_d & 0 & 0 \\ 0 & A_d & 0 \\ 0 & 0 & 1 \end{bmatrix} \qquad B_d = \begin{bmatrix} B_d & 0 & 0 \\ 0 & B_d & 0 \\ 0 & 0 & T \end{bmatrix} \tag{5}$$

3 3D-LIP Model with Heading Angles

Salvatore:
If the full dynamic model of the humanoid is used to simulate its motion, it becomes computationally impossible to perform joint path and gait planning, due to its high dimensionality and non-linearity. Therefore, a simplifying model must be used. For this scope Peng et al. introduced the "3D-LIP Model with Heading Angle", which describes the discrete dynamics of the Center of Mass (CoM) similarly to the one of an inverted pendulum in three dimensions.

3.1 Local Robot Reference Frame

The state $\mathbf{x}$ and the input $\mathbf{u}$ of the dynamic model are defined as:

$$\mathbf{x} := \left(p_x,\ v_x,\ p_y,\ v_y,\ \theta\right)^T \in X \subset \mathbb{R}^5,$$
$$\mathbf{u} := \left(f_x,\ f_y,\ \omega\right)^T \in U \subset \mathbb{R}^3,$$

where (p_x, v_x) are the CoM position and translational velocity along the x-axis, f_x is the x-coordinate of the stance foot position, θ and ω are the humanoid's orientation and turning rate, respectively. X is the set of the allowed states, while U is the set of the admissible inputs.

Both the state and the input are expressed in the local coordinates of the robot. It means that (p_x, p_y) represents the position of the CoM in the reference frame (RF) that originates from the CoM position at the previous time step. The RF at the next time step will be rotated by an angle θ around the z-axis with respect to the previous frame. The relation between the vectors in different reference frames is represented in Figure 1.

The reference frame at time step 0 is considered the "inertial" or "global" frame. A transformation between the inertial and moving frames is necessary to obtain the position of the humanoid in the global map and to deal with obstacles. Transformations are performed as follows:

$$T_k = \begin{pmatrix} \cos\theta_k & -\sin\theta_k & p_{x,\,k,\,\mathrm{glob}} \\ \sin\theta_k & \cos\theta_k & p_{y,\,k,\,\mathrm{glob}} \\ 0 & 0 & 1 \end{pmatrix},$$

$$\begin{pmatrix} f_{x,\,k,\,\mathrm{glob}} \\ f_{y,\,k,\,\mathrm{glob}} \\ 1 \end{pmatrix} = T_k \begin{pmatrix} f_{x,\,k,\,\mathrm{loc}} \\ f_{y,\,k,\,\mathrm{loc}} \\ 1 \end{pmatrix},$$

$$\begin{pmatrix} p_{x,\,k+1,\,\mathrm{glob}} \\ p_{y,\,k+1,\,\mathrm{glob}} \\ 1 \end{pmatrix} = T_k \begin{pmatrix} p_{x,\,k+1,\,\mathrm{loc}} \\ p_{y,\,k+1,\,\mathrm{loc}} \\ 1 \end{pmatrix},$$

$$\begin{pmatrix} v_{x,\,k+1,\,\mathrm{glob}} \\ v_{y,\,k+1,\,\mathrm{glob}} \end{pmatrix} = \begin{pmatrix} \cos\theta_k & -\sin\theta_k \\ \sin\theta_k & \cos\theta_k \end{pmatrix} \begin{pmatrix} v_{x,\,k+1,\,\mathrm{loc}} \\ v_{y,\,k+1,\,\mathrm{loc}} \end{pmatrix},$$

$$\theta_{k+1,\mathrm{glob}} = \theta_{k,\mathrm{glob}} + \theta_{k+1,\mathrm{loc}}, \qquad \omega_{\mathrm{glob}} = \omega_{\mathrm{loc}}.$$

The positional vectors are roto-translated using a 3×3 homogeneous matrix. The velocity vectors are only rotated around the z-axis (indeed, a translation would change their magnitude) using a rotation matrix. The global robot's orientation is obtained by summing the latest local variation to the previous global angle. The angular velocity does not need to be transformed because it is along the z-axis, which is fixed.

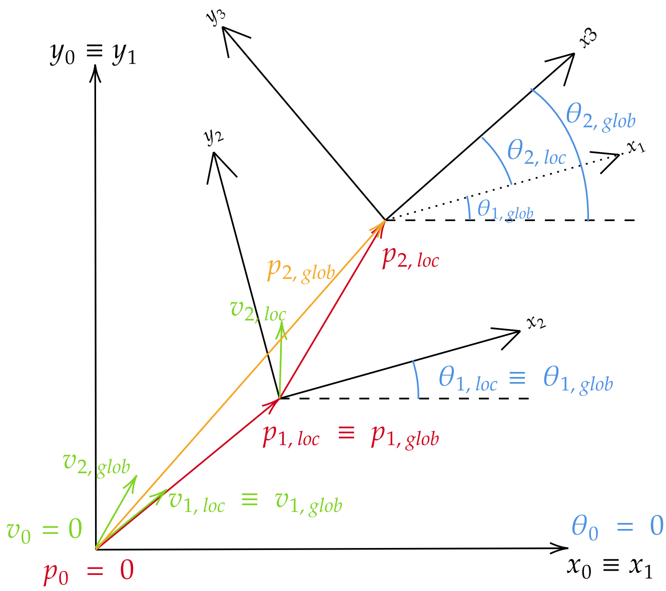

Figure 1: An example of the evolution of the 3D-LIP model's state, highlighting the relationship between local and global coordinates. The initial state is $\mathbf{0}$ and the RF $(x_0,\, y_0)$ is the inertial frame. The local RF translates and rotates: the position of the RF $(x_2,\, y_2)$ related to time step 1 is given by the position of $p_{1,\text{glob}}$, while its orientation is given by $\theta_{1,glob}$. The pose of the successive frames is computed analogously.

3.2 Model Definition

4 Conclusion

This is the conclusion.

References

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