Learning Ground Traversability from Simulations

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***Abstract*— This paper proposes a deep-learning approach to estimate traversability for a non wheel robot on different terrain. We train a deep convolutional neural network to classify ground patches generated in multiple simulations, we then evaluated the model performance on real ground scenarios. In patch is treated independent without any notion of time.**

I. INTRODUCTION

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II. RELATED WORK

A. Features based approach

B. Deep Learning approach

III. DATASET GENERATION

Similar to CITE OMAR, we used syntethic generate heighmaps in the simulation to generated the train set, while using real-world scenario to evaluate the model.

A. Heightmaps

We generated 15 heighmaps of 513x513 pixels with a resolution of 2cm per pixel to train the model. Those maps are DIRE CHE SONO LE STESSE DI OMAR. Those maps present a wide array of interesting scenarios such as bumps, holes, walls and slopes. The maps can be found HERE

*This work was not supported by any organization

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B. Simulation Pipeline

We used Webots to simulate the robot in the different scenarios. For each map we, select k obstacle-free spawns points by select k in k cluster generate by K-Means on all the possible points that allows the spawn without hitting an obstacle. This reduce noise in the training sets avoid the situation in which the robot directly spawns on an obstacle, in addition, this approach mimic a real world simulation in which usually the robot is placed into a traversable patch with obstacle in front of it.

For each maps we runs 100 simulation of a maximum of 20 seconds each, we stop a simulation if the robot felts outside the maps boundaries.

C. Patch extraction

IV. MODEL SELECTION

A. Vanilla CNN

B. ResNet Variant

V. EXPERIMENTS AND RESULTS

VI. CONCLUSION

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$$\alpha + \beta = \chi \tag{1}$$

Note that the equation is centered using a center tab stop. Be sure that the symbols in your equation have been defined before or immediately following the equation. Use (1), not Eq. (1) or equation (1), except at the beginning of a sentence: Equation (1) is . . .

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- The word data is plural, not singular.
- The subscript for the permeability of vacuum ?0, and other common scientific constants, is zero with subscript formatting, not a lowercase letter o.
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- The abbreviation i.e. means that is, and the abbreviation e.g. means for example.

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TABLE I
AN EXAMPLE OF A TABLE

One	Two
Three	Four

Figure Labels: Use 8 point Times New Roman for Figure labels. Use words rather than symbols or abbreviations when writing Figure axis labels to avoid confusing the reader. As

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Fig. 1. Inductance of oscillation winding on amorphous magnetic core versus DC bias magnetic field

an example, write the quantity Magnetization, or Magnetization, M, not just M. If including units in the label, present them within parentheses. Do not label axes only with units. In the example, write Magnetization (A/m) or Magnetization A[m(1)], not just A/m. Do not label axes with a ratio of quantities and units. For example, write Temperature (K), not Temperature/K.

VIII. CONCLUSIONS

A conclusion section is not required. Although a conclusion may review the main points of the paper, do not replicate the abstract as the conclusion. A conclusion might elaborate on the importance of the work or suggest applications and extensions.

APPENDIX

Appendixes should appear before the acknowledgment.

ACKNOWLEDGMENT

The preferred spelling of the word acknowledgment in America is without an e after the g. Avoid the stilted expression, One of us (R. B. G.) thanks . . . Instead, try R. B. G. thanks. Put sponsor acknowledgments in the unnumbered footnote on the first page.

References are important to the reader; therefore, each citation must be complete and correct. If at all possible, references should be commonly available publications.

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