Final Presentation

Semester Project at LCAV

Ecole Polytechique Fédérale de Lausanne

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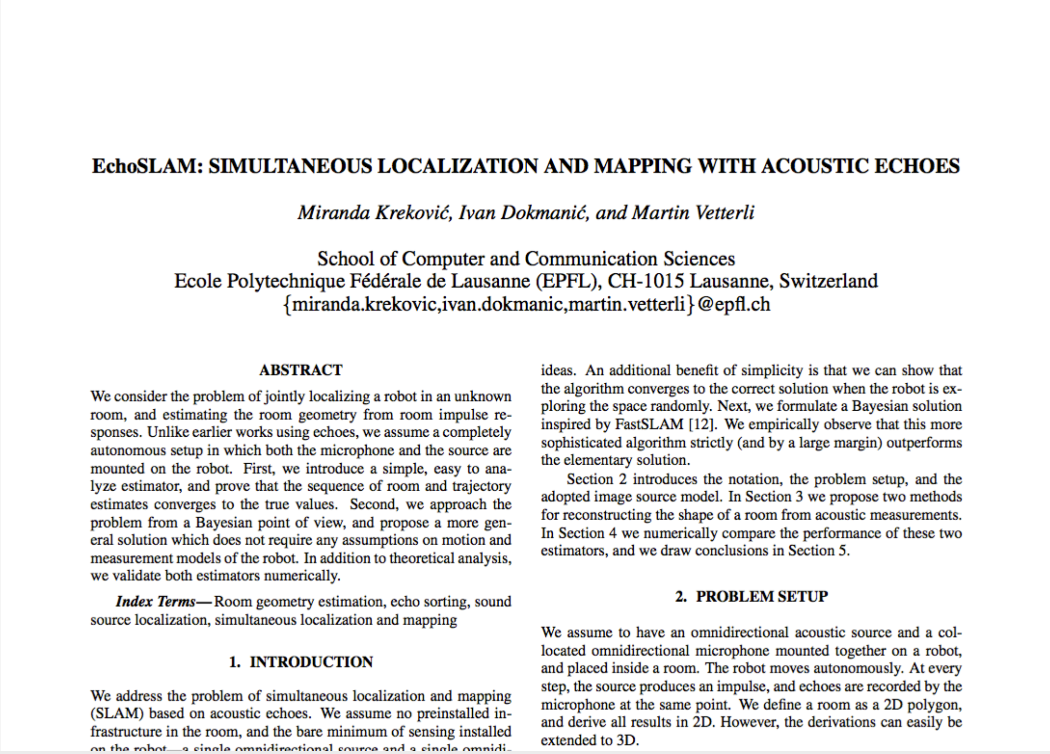
Experimental Setup of Sound Emitting and Processing Robot for Acoustic-Based SLAM Applications

Introduction

Motivation – Echolocation for Navigation



EchoSLAM: SIMULTANEOUS LOCALIZATION AND MAPPING WITH ACOUSTIC ECHOES

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ABSTRACT

We consider the problem of jointly localizing a robot in an unknown room, and estimating the room geometry from room impulse responses. Unlike earlier works using echoes, we assume a completely autonomous setup in which both the microphone and the source are mounted on the robot. First, we introduce a simple, easy to analyze estimator, and prove that the sequence of room and trajectory estimates converges to the true values. Second, we approach the problem from a Bayesian point of view, and propose a more general solution which does not require any assumptions on motion and measurement models of the robot. In addition to theoretical analysis, we validate both estimators numerically.

Index Terms— Room geometry estimation, echo sorting, sound source localization, simultaneous localization and mapping

1. INTRODUCTION

We address the problem of simultaneous localization and mapping (SLAM) based on acoustic echoes. We assume no preinstalled infrastructure in the room, and the bare minimum of sensing installed on the robot—a single omnidirectional source and a single omnidi-

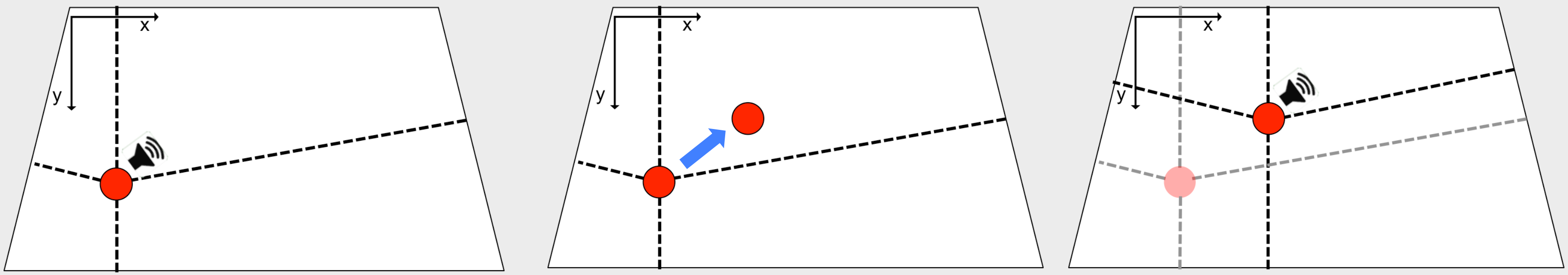
ideas. An additional benefit of simplicity is that we can show that the algorithm converges to the correct solution when the robot is exploring the space randomly. Next, we formulate a Bayesian solution inspired by FastSLAM [12]. We empirically observe that this more sophisticated algorithm strictly (and by a large margin) outperforms the elementary solution.

Section 2 introduces the notation, the problem setup, and the adopted image source model. In Section 3 we propose two methods for reconstructing the shape of a room from acoustic measurements. In Section 4 we numerically compare the performance of these two estimators, and we draw conclusions in Section 5.

2. PROBLEM SETUP

We assume to have an omnidirectional acoustic source and a collocated omnidirectional microphone mounted together on a robot, and placed inside a room. The robot moves autonomously. At every step, the source produces an impulse, and echoes are recorded by the microphone at the same point. We define a room as a 2D polygon, and derive all results in 2D. However, the derivations can easily be extended to 3D.

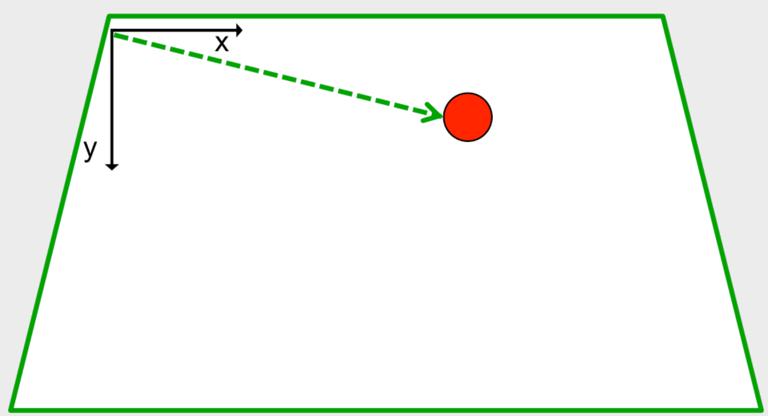
Introduction
Goal – Experimental Framework



Visual localization
ground truth

Odometry
relative position

EchoSLAM
absolute position
and room geometry

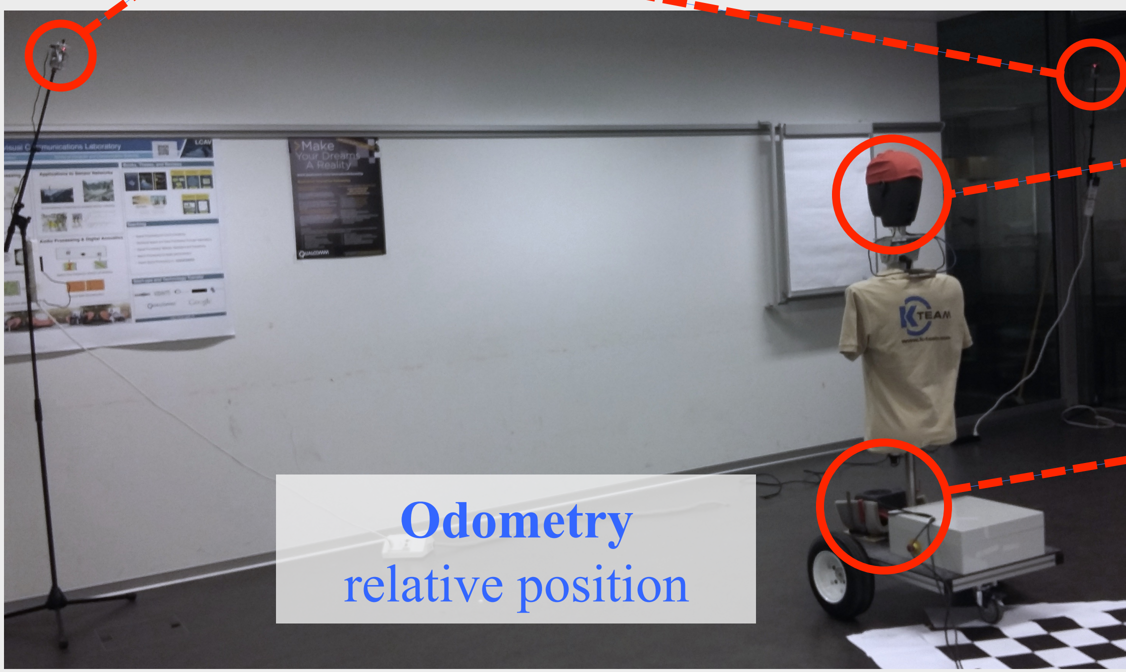


Experimental Setup

Overview

Visual localization
ground truth

EchoSLAM
absolute position
and room geometry



Odometry
relative position

Room Impulse Response (RIR)
Experimental Procedure

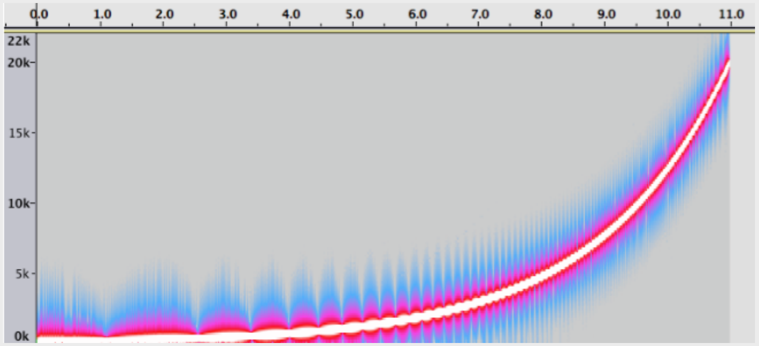


Fig. 1: Spectogram of sine sweep used

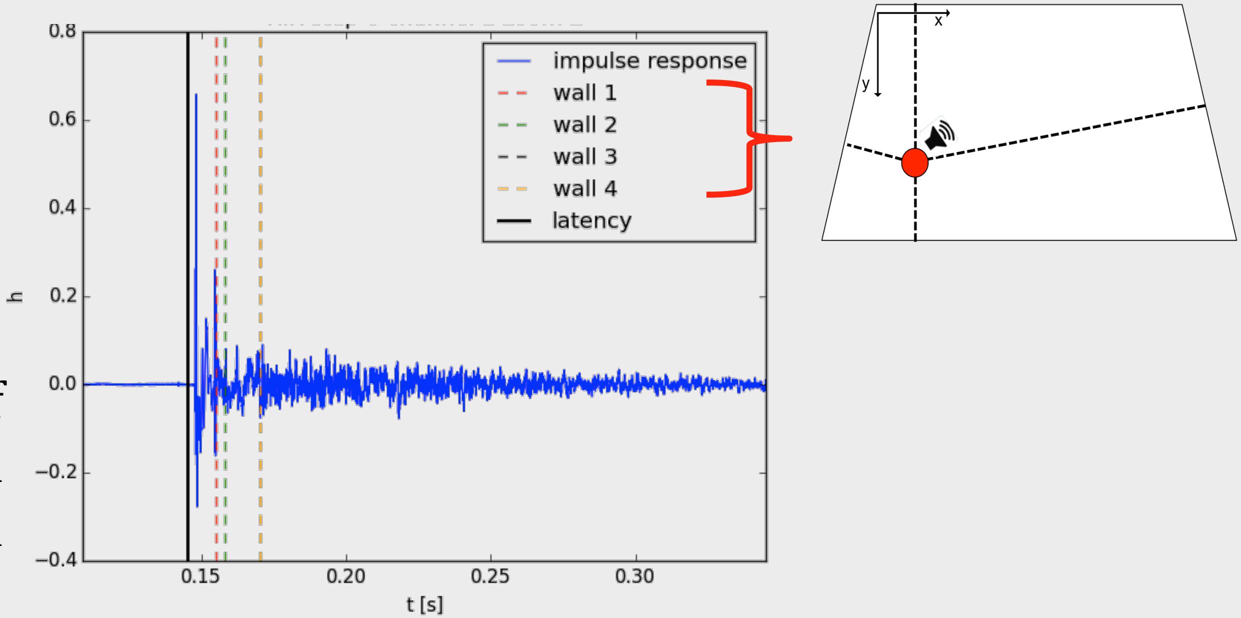


Fig. 2: RIR of channel 1 obtained by deconvolution

Room Impulse Response (RIR)
Experimental Results

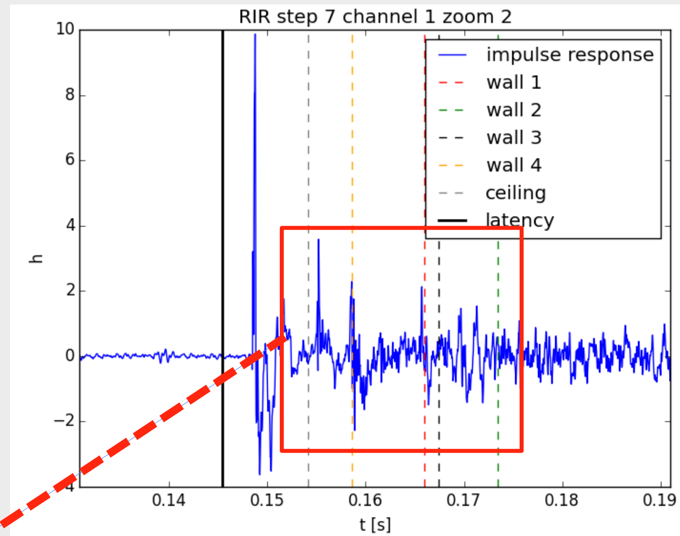
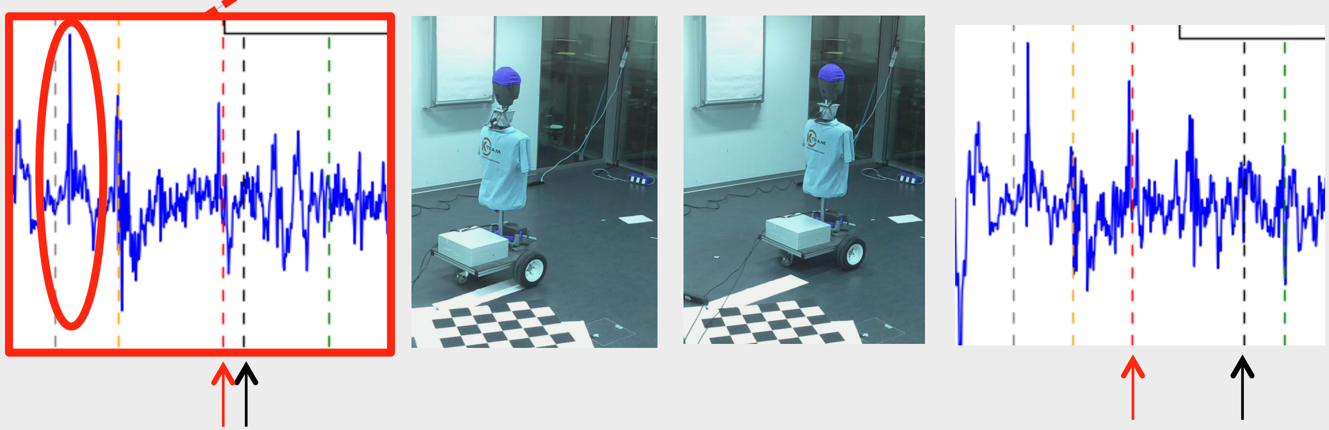
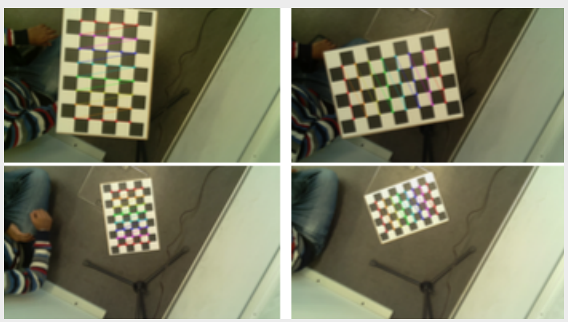
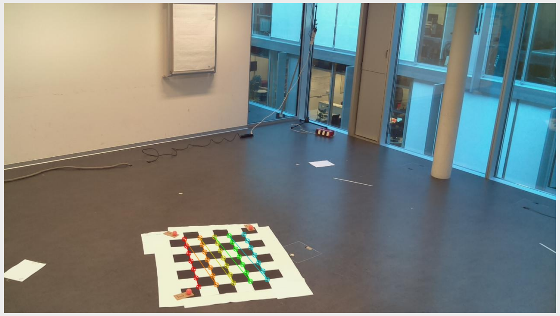


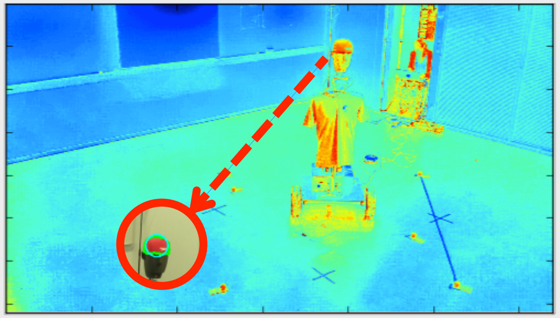
Fig. 1: RIR at position 7



Visual Localization
Experimental Procedure







given pictures of checkerboard

$\longrightarrow$ C and distortion coeff.

given positions X, Y, Z of N_{pts} = 5 x 7 points

$\longrightarrow$ R, **t**

given (u_j, v_j) *for j cameras,* ***Z optional***

$\longrightarrow$ X, Y, (Z)

$$s_i \begin{bmatrix} u_i \\ v_i \\ 1 \end{bmatrix} = C \begin{bmatrix} R & | & \mathbf{t} \end{bmatrix} \begin{bmatrix} X_i \\ Y_i \\ Z_i \\ 1 \end{bmatrix}, \quad \text{for } i = 1 \cdots N_{pts},$$

Visual Localization
Experimental Results

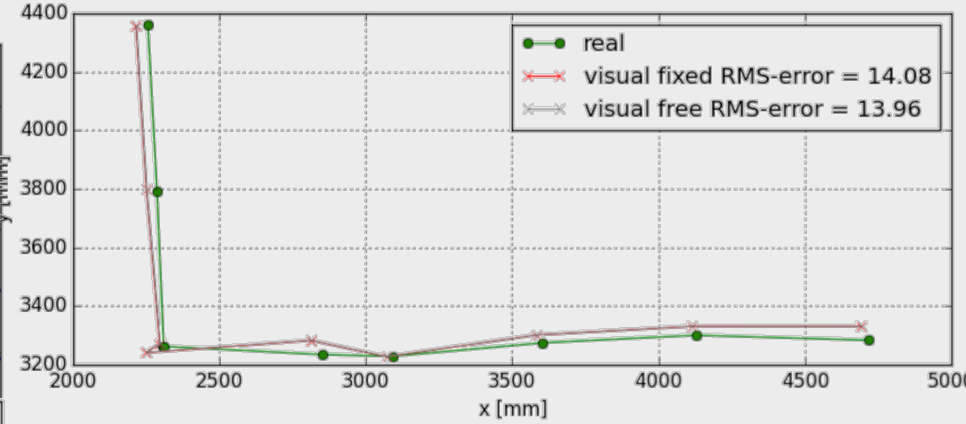


Fig. 2: Results using all cameras

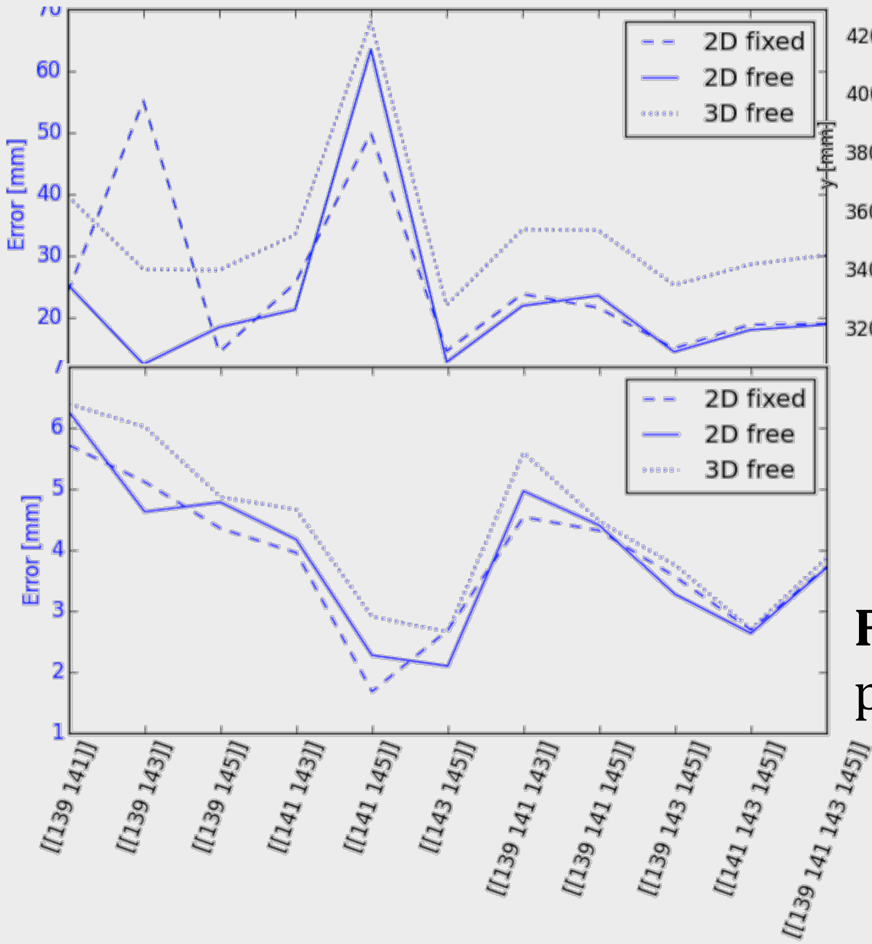


Fig. 1: Robot (top) and reference point (bottom) error

Robot Movement and Odometry
Procedure and Results

Fig. 1: Command blocks

```
0    f
2    s
0    f
2    s
0    r
3    s
```

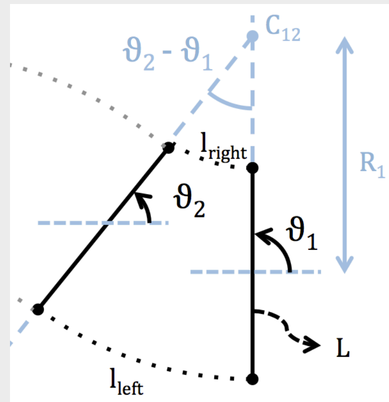


Fig. 2: Odometry geometry considerations

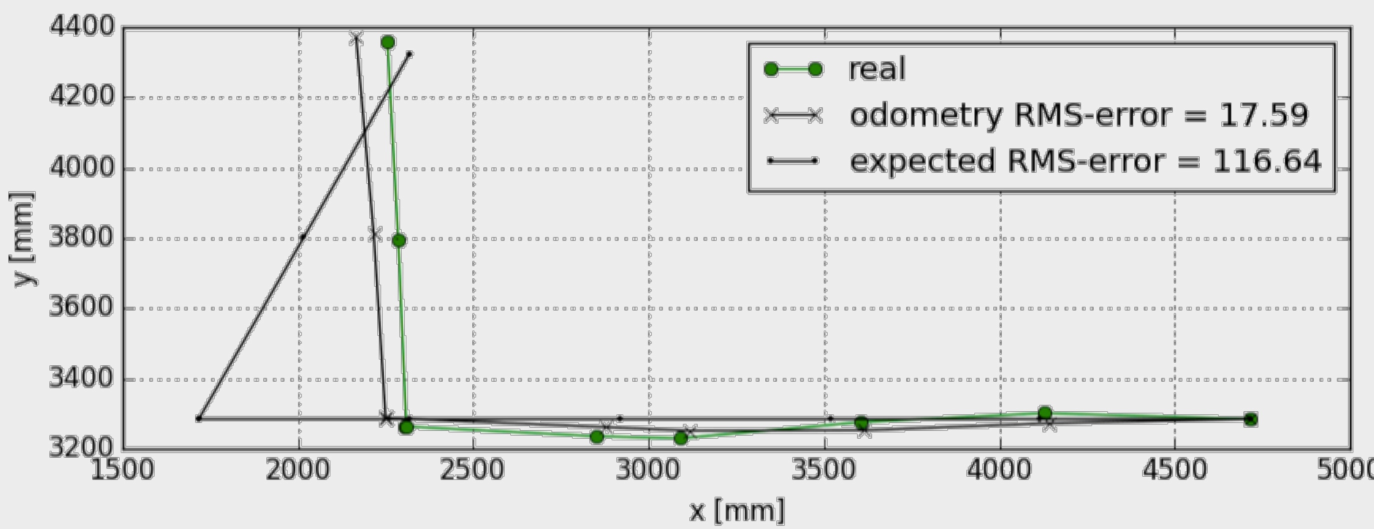


Fig. 3: Robot positions

Experimental Results

Summary

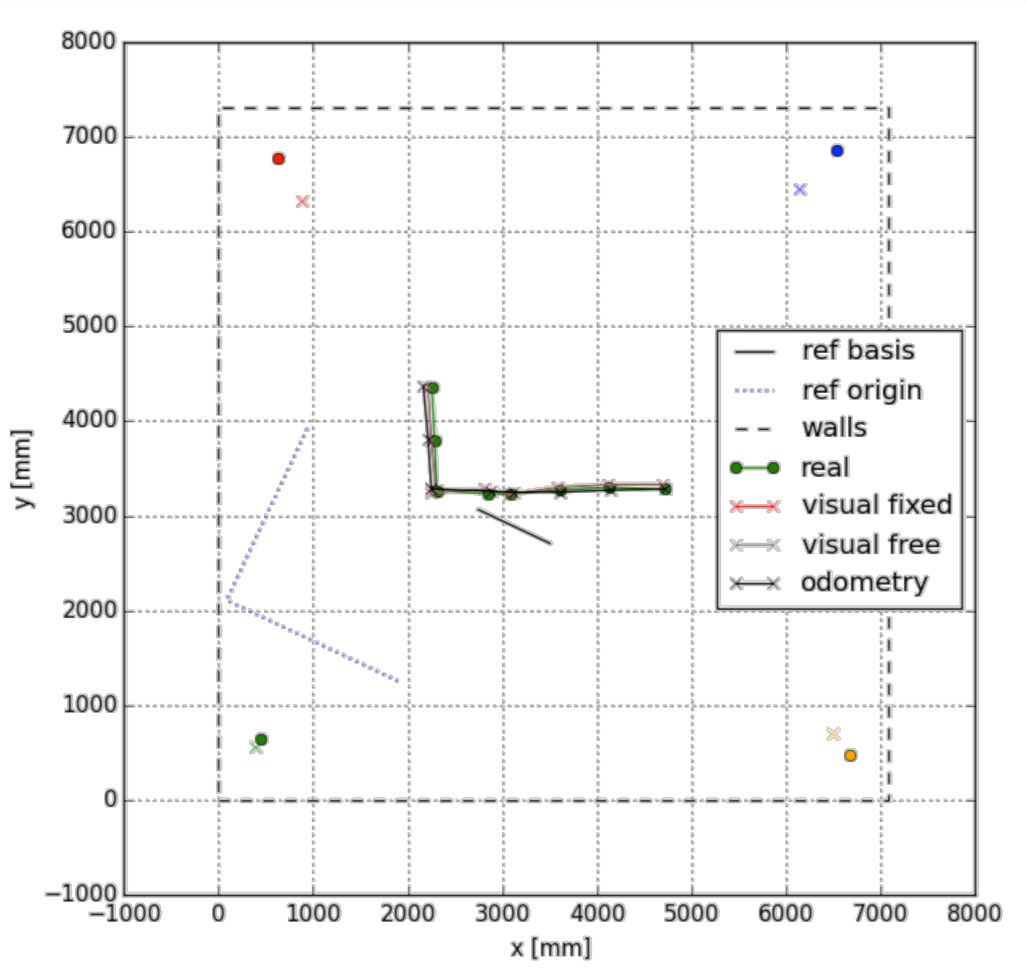


Fig. 1: Results using all cameras in room reference

Conclusion
Achievements

- Experimental framework (both **Hardware and Software**) tested and validated
  - Visual localization with precision up to 1 cm
  - Odometry analysis implemented
  - Room impulse response recording and deconvolution working
- Setup **instructions** and code **documentation** available online for later use

Conclusion
Suggested Improvements

- Smaller or more accurate **target point** for visual localization (checkerboard / *QR code*)
- Add **fisheye** lenses for wider views
- More robust robot **movement** and **audio control**
- Improve **signal processing** for reliable echolocation (e.g. averaging)

Thank you

Experimental Setup
Visual Localization Procedure

- Governing equation

$$s_i \begin{bmatrix} u_i \\ v_i \\ 1 \end{bmatrix} = C \begin{bmatrix} R & | & \mathbf{t} \end{bmatrix} \begin{bmatrix} X_i \\ Y_i \\ Z_i \\ 1 \end{bmatrix}, \quad \text{for } i = 1 \cdots N_{pts},$$

- C and distortion coefficients obtained by **intrinsic calibration**
- Two different cases are treated:
  - Positioning of cameras (R, **t**) based on image-object space correspondances
  - Localization of point given its image in 4 cameras.
- Minimization of **reprojection error**