Machine Learning-based Indoor Localization for Micro Aerial Vehicles

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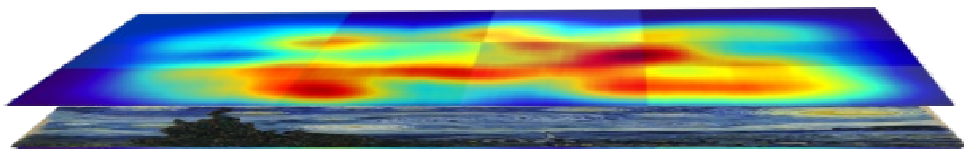
14th July 2016



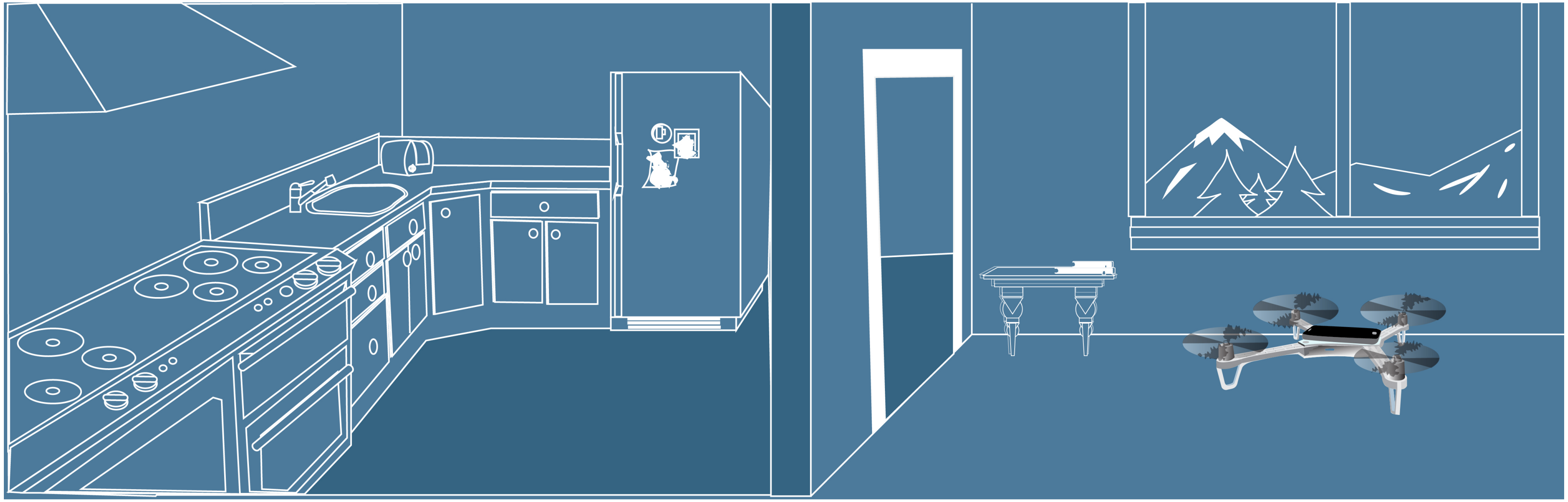
Radboud Universiteit

Louis Vuurpijl

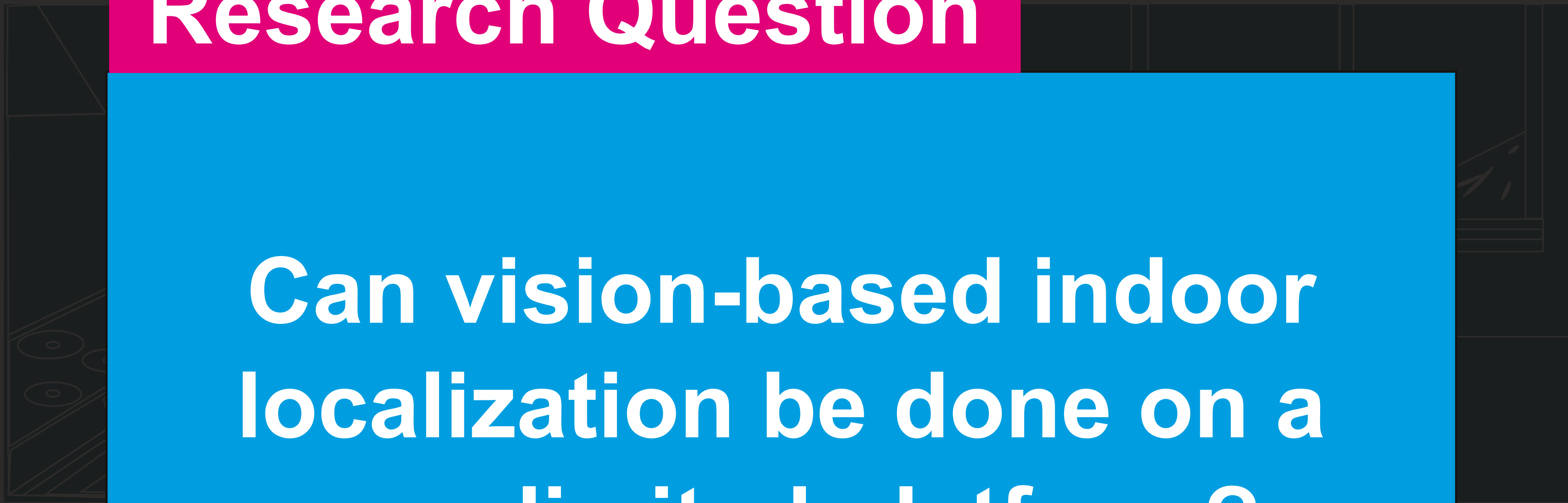
TU Delft
Delft University of Technology

Guido de Croon
Roland Meertens

MOTIVATION



MOTIVATION



Research Question

Can vision-based indoor localization be done on a very limited platform?

RESEARCH QUESTIONS

Research Question 1

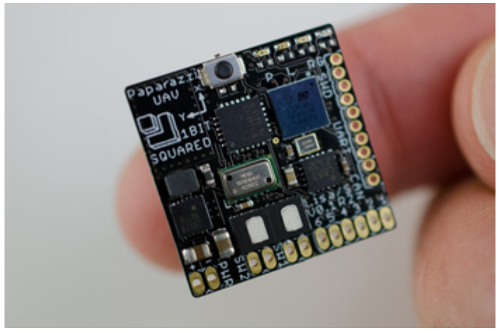
Can vision-based indoor localization be done on a very limited platform?

Research Question 2

Can we predict the suitability of an environment for the proposed localization algorithm?

x,y-coordinates in real time

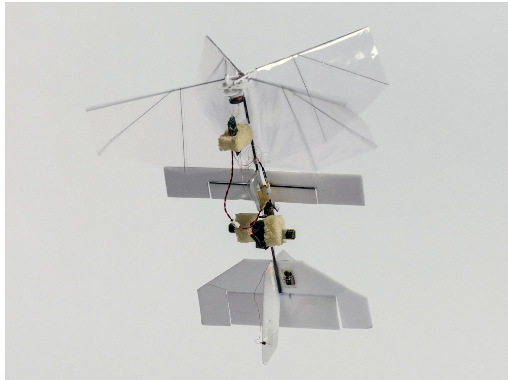
Micro Air Vehicle Lab



TU Delft Delft University of Technology

MAVLab

Miniaturization



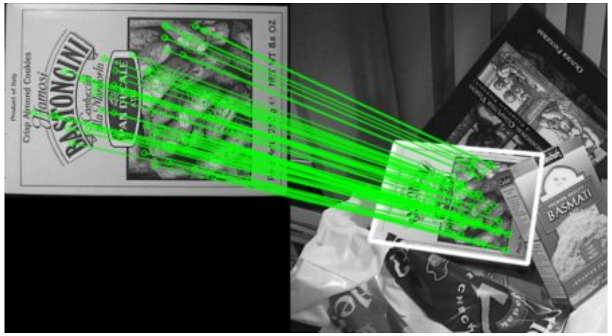
OUTLINE

- Existing Methods
- Machine Learning-based Approach
- Simulations & Flight Tests
- Discussion & General Discussion
- Conclusion & Future Work

OUTLINE

- Existing Methods
- Methods
- Experiments and Results
- Discussion
- Conclusion

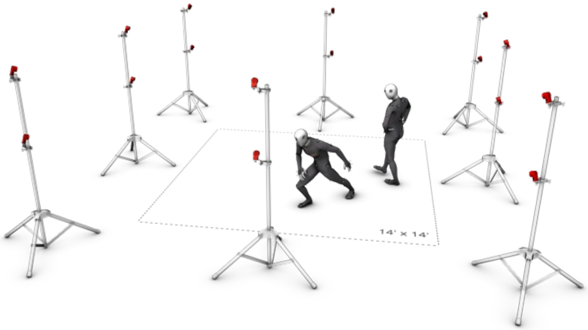
METHODS FOR INDOOR LOCALIZATION



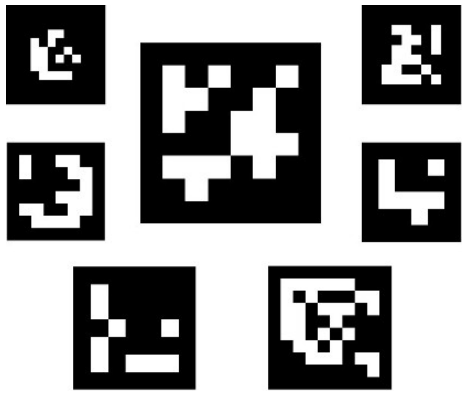
SIFT + homography finding

Laser range finder

Visual odometry
(acumulating
error)



Motion tracking system



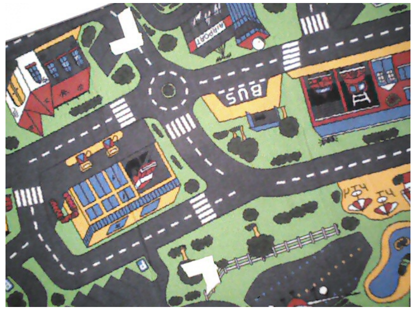
Markers

CHALLENGES / CONTRIBUTIONS

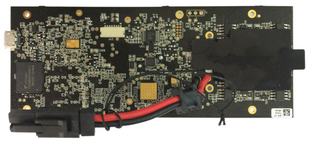
Low-performance platform

Ground truth estimation

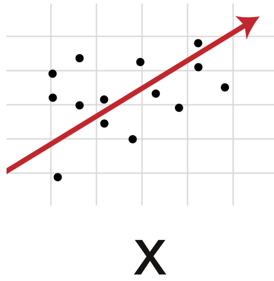
x?
y?

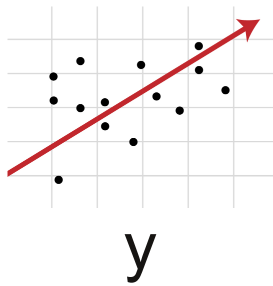


Low-level embedded programming (C)



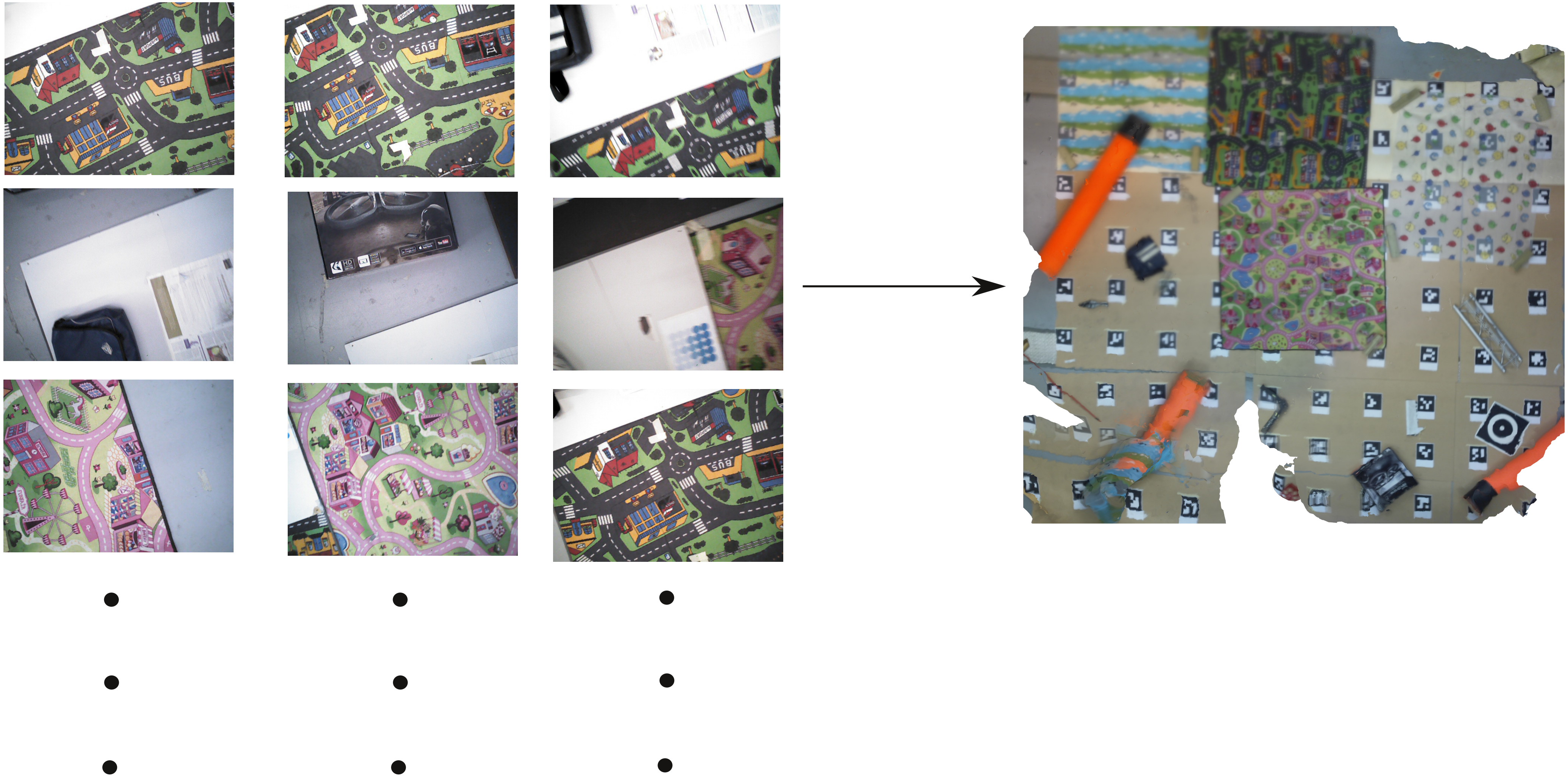
Regression with 2 dependent variables





GROUND TRUTH ESTIMATION

GROUND TRUTH ESTIMATION




allerhande
burgers & salades
fiësta!
homemade
happinez
LEKKER
pasta

APPROACH

Flight phase

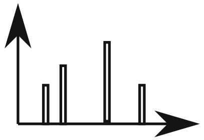
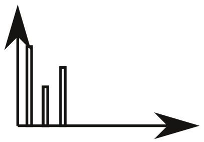
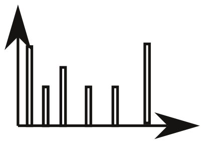
1 Image / sec

IDEA

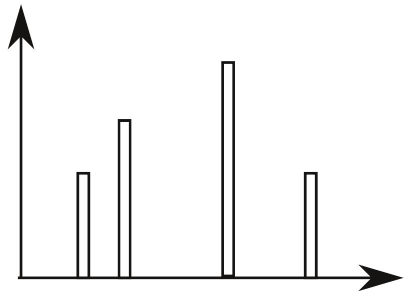
Preflight phase

(computational) effort

Training Data

frequencies	x	y
	200	300
	700	210
⋮	⋮	
	111	210

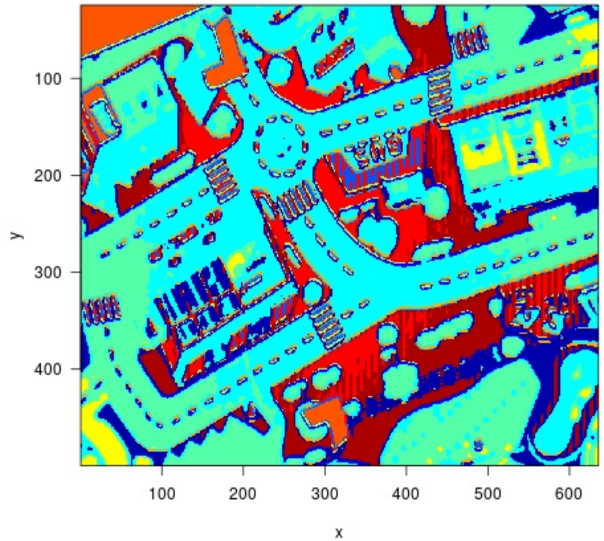
Flight phase

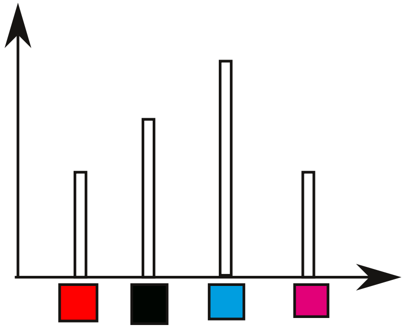


OUTLINE

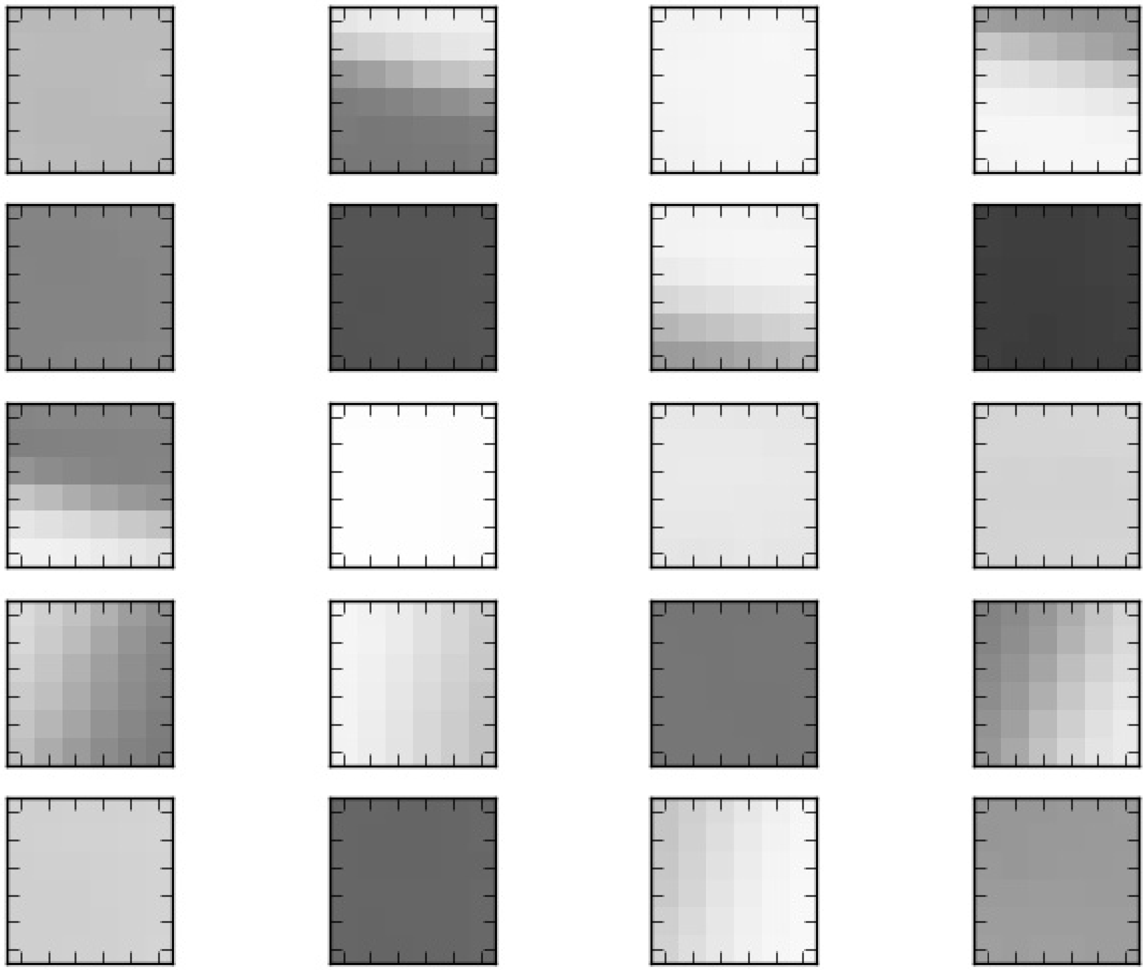
- Related Work
- Methods
- Experiments and Results
- Discussion
- Conclusion

TEXTONS

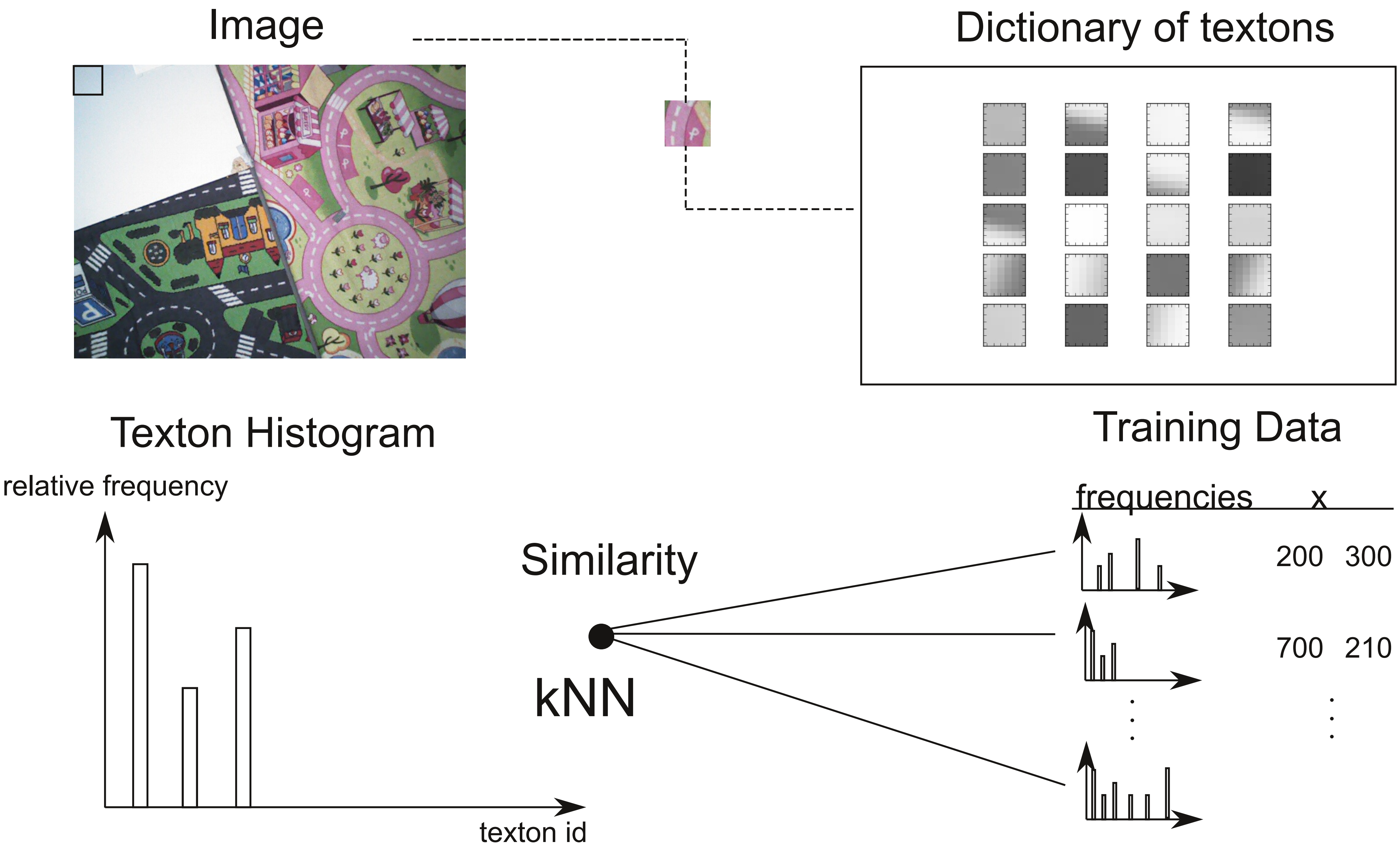




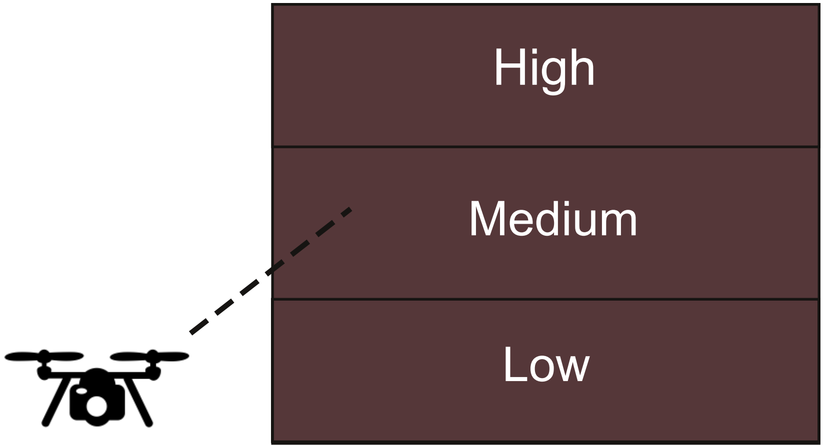
TEXTONS



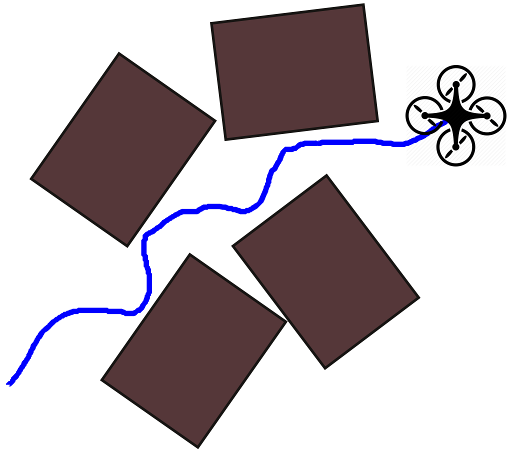
MACHINE-LEARNING APPROACH



FOUNDATION

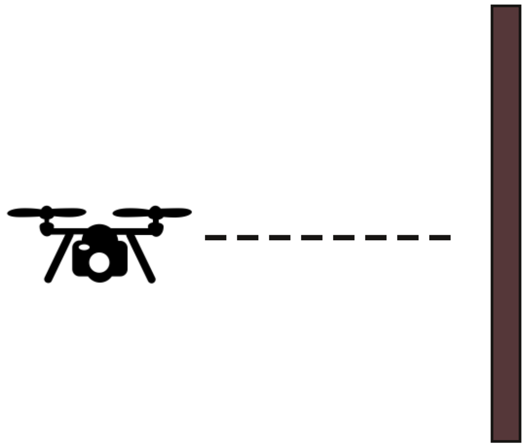


Height control



Obstacle Avoidance

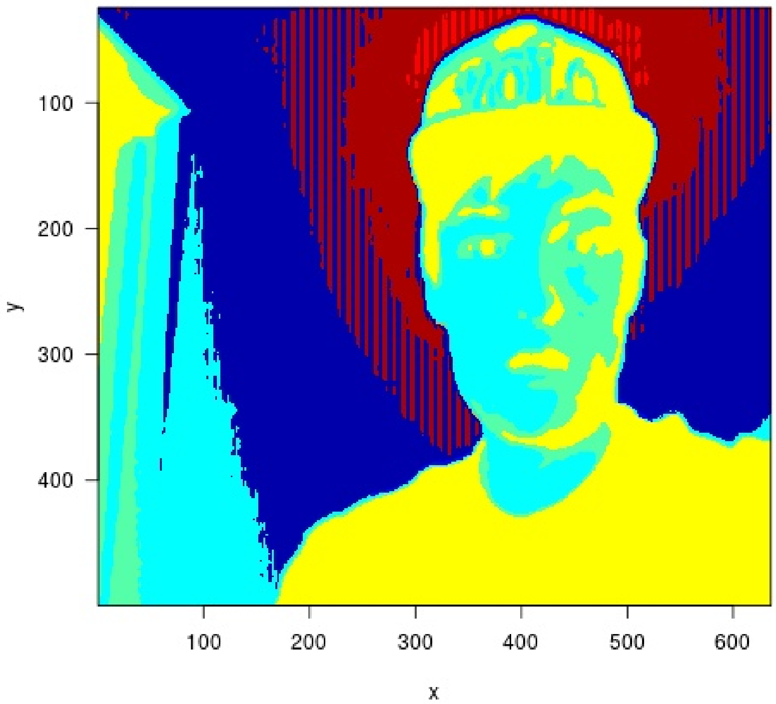
Safe Landing Spot Detection

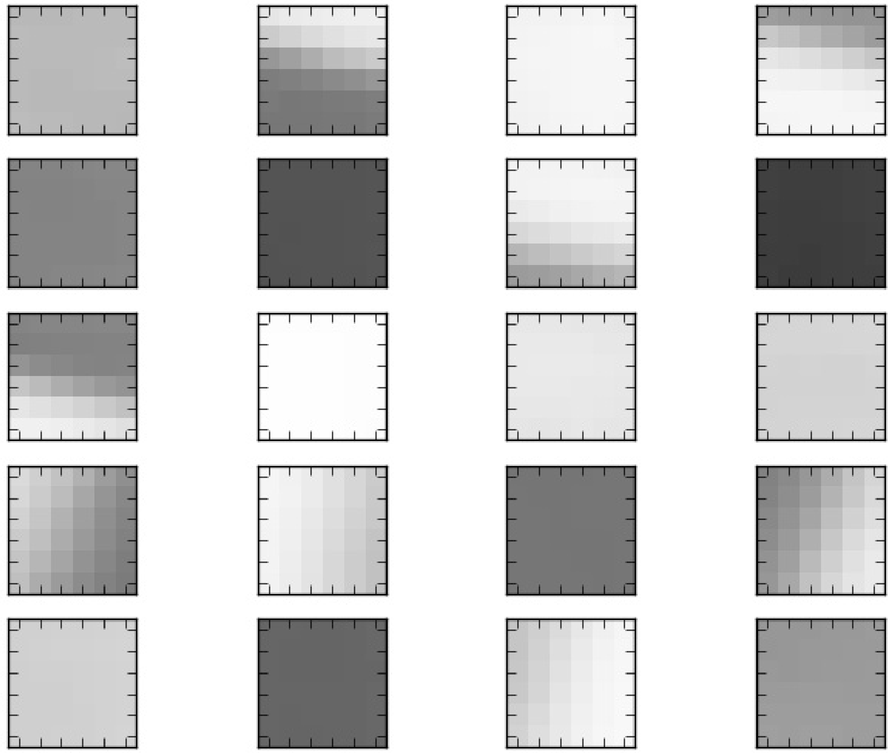


Distance Measurement

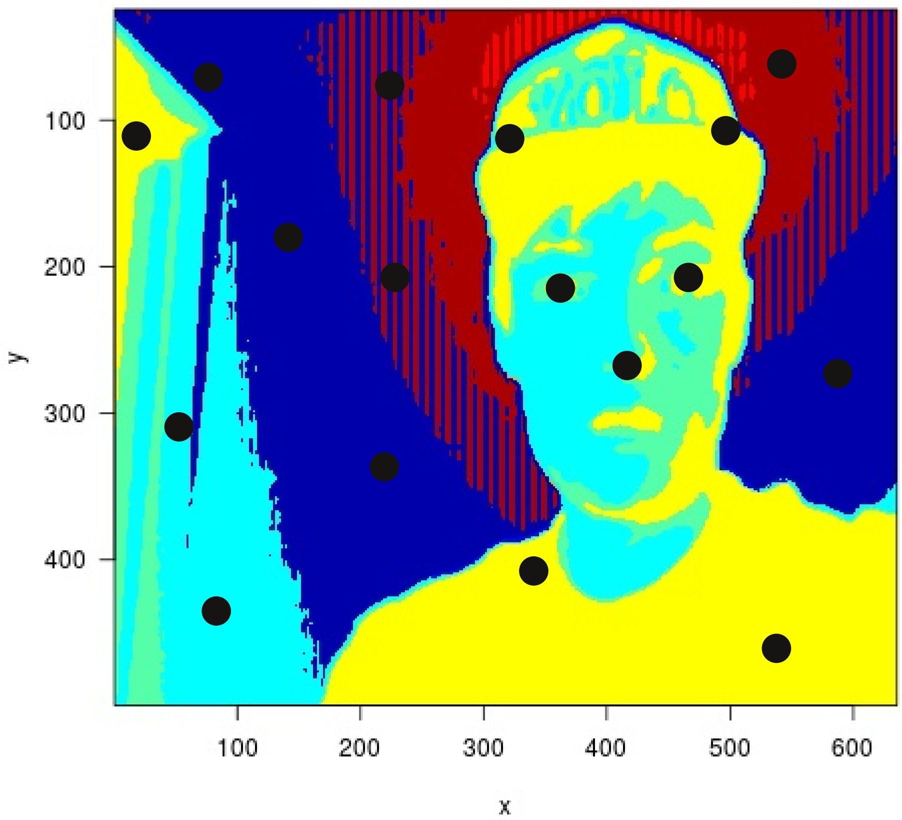
DUMMY: INSERT CYBERZOO_FLIGHT

MACHINE-LEARNING APPROACH

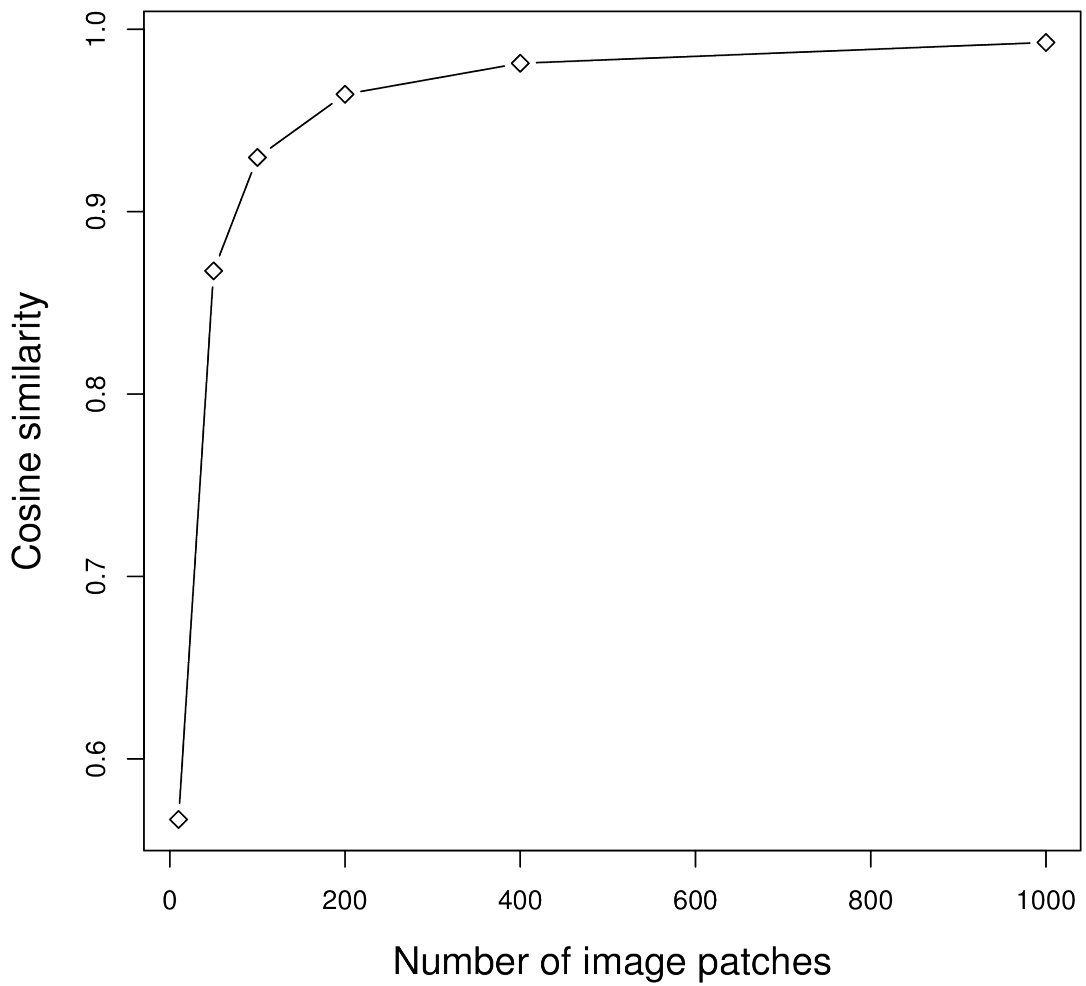




MACHINE-LEARNING APPROACH

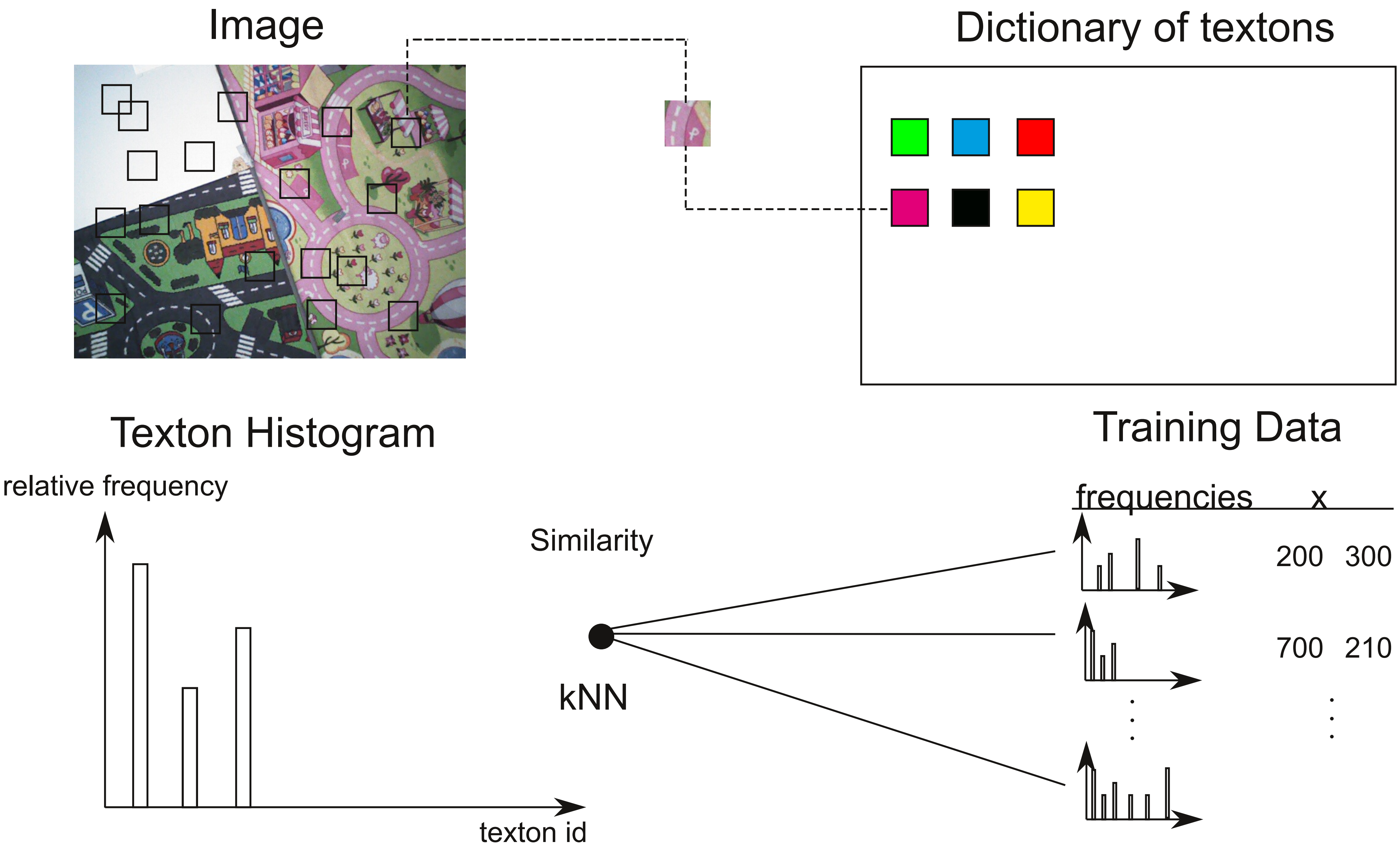


MACHINE-LEARNING APPROACH

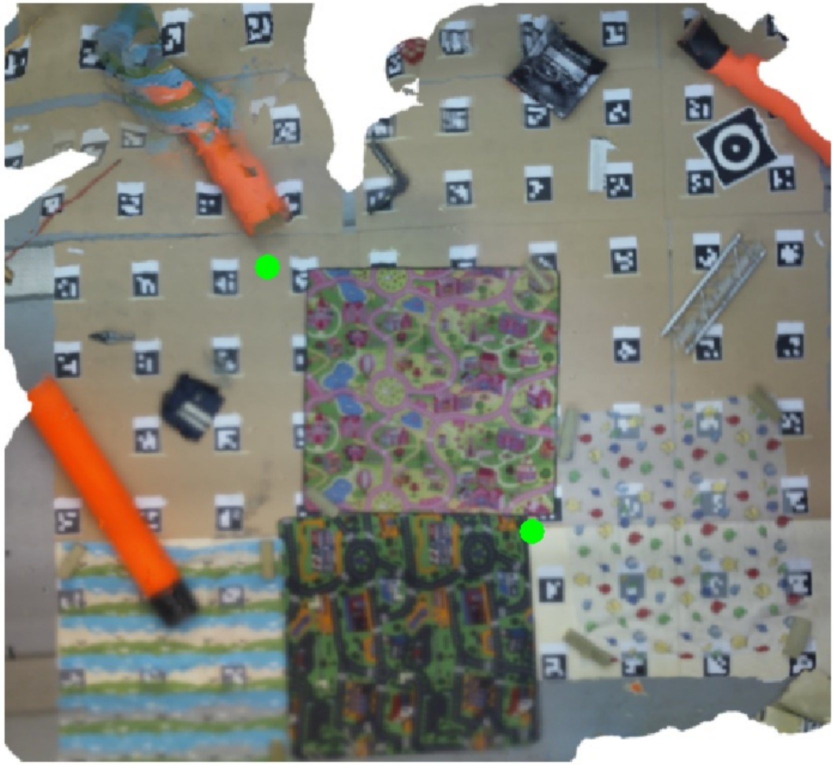


307200!

MACHINE-LEARNING APPROACH

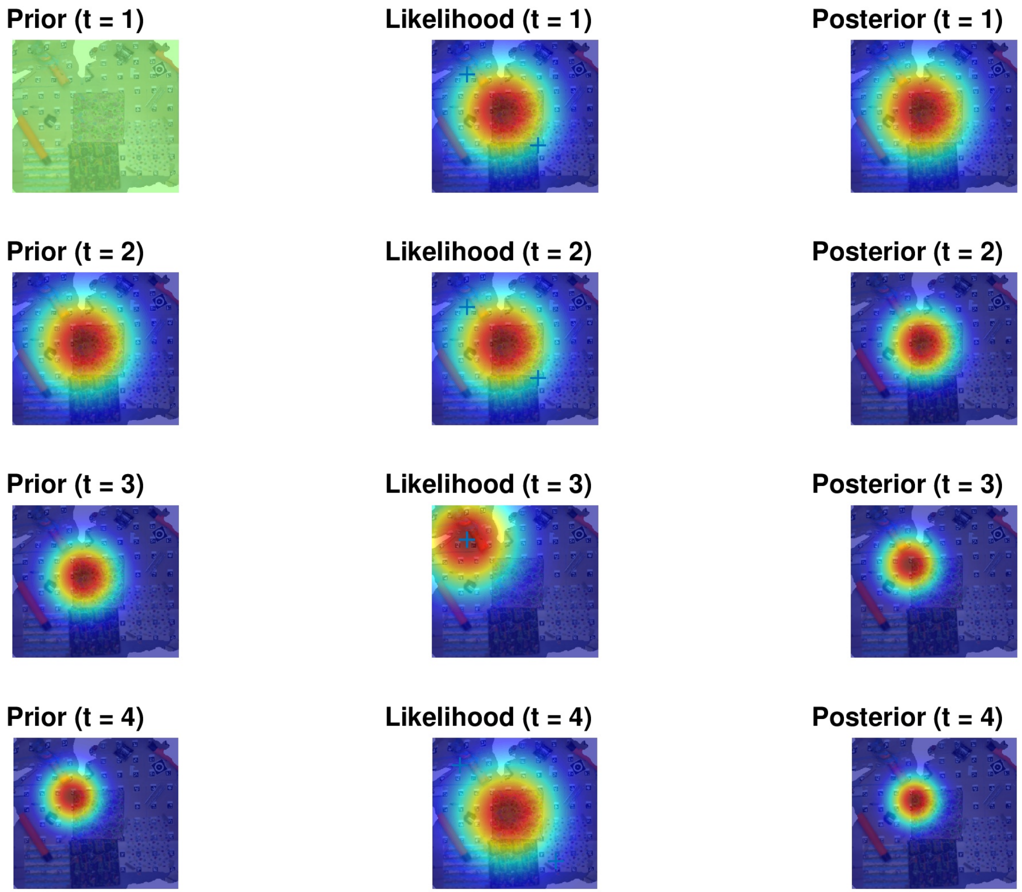


FILTERING

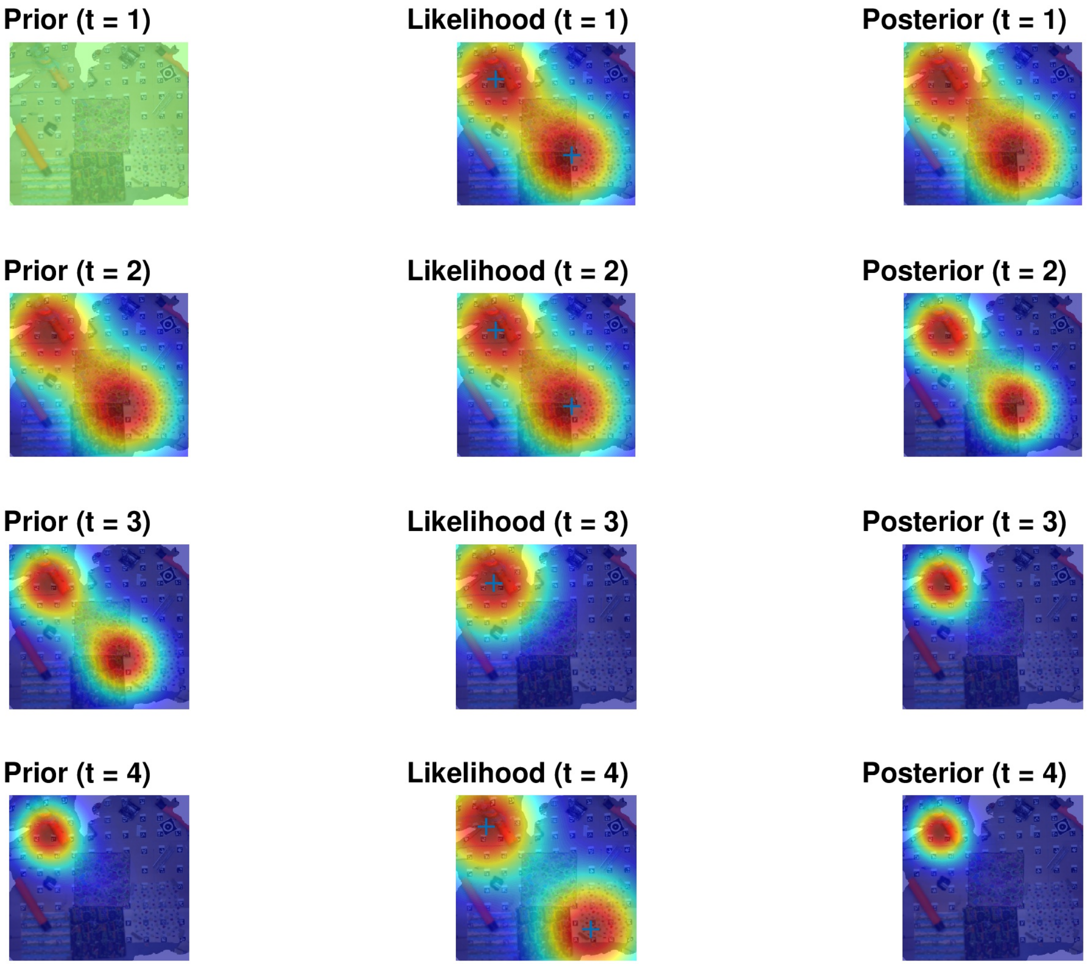


FILTERING

FILTERING


Prior (t = 1)
Likelihood (t = 1)
Posterior (t = 1)
Prior (t = 2)
Likelihood (t = 2)
Posterior (t = 2)
Prior (t = 3)
Likelihood (t = 3)
Posterior (t = 3)
Prior (t = 4)
Likelihood (t = 4)
Posterior (t = 4)

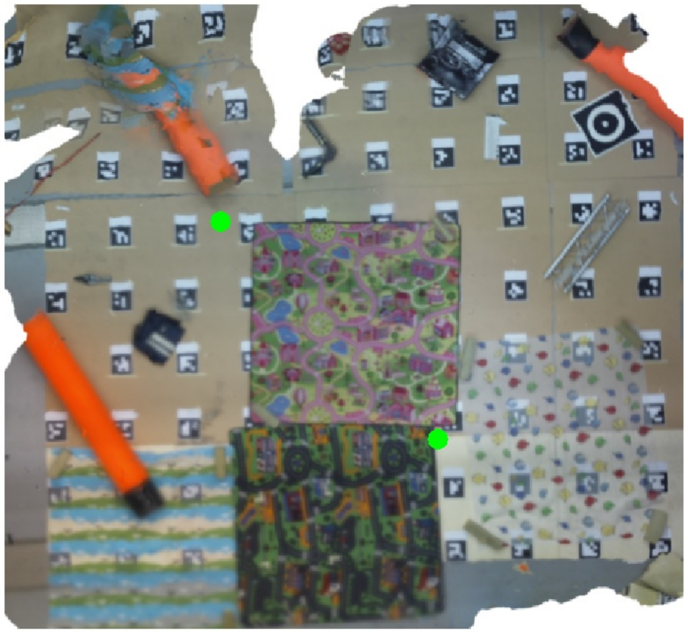
FILTERING


Prior (t = 1)
Likelihood (t = 1)
Posterior (t = 1)
Prior (t = 2)
Likelihood (t = 2)
Posterior (t = 2)
Prior (t = 3)
Likelihood (t = 3)
Posterior (t = 3)
Prior (t = 4)
Likelihood (t = 4)
Posterior (t = 4)

FILTERING

Particle Filter

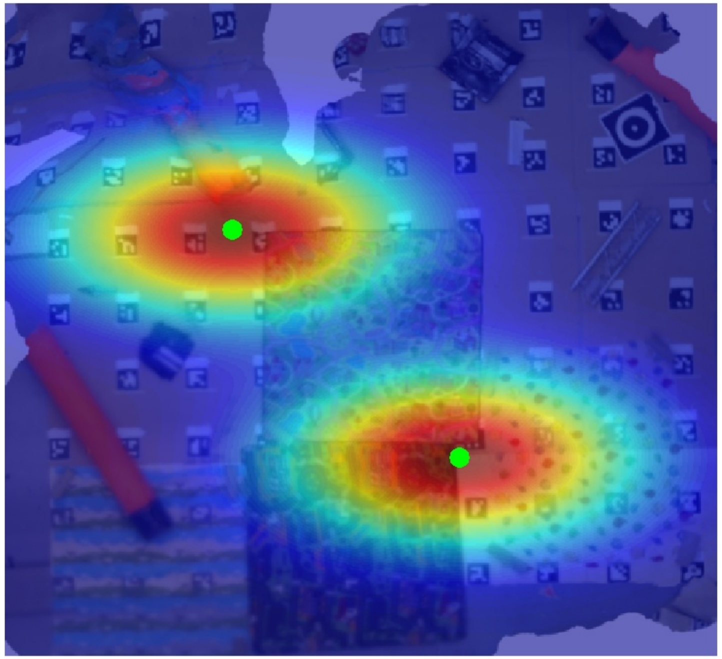
Sensor model



FILTERING

Particle Filter

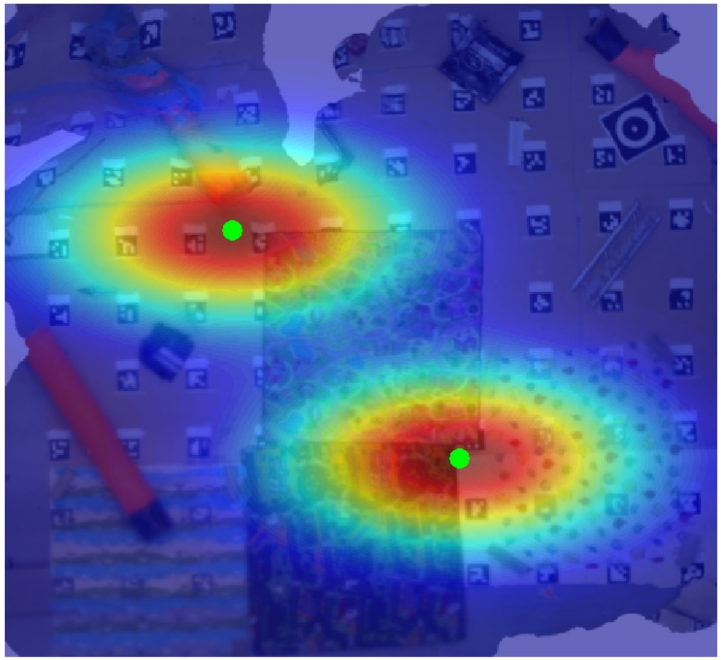
Sensor model



FILTERING

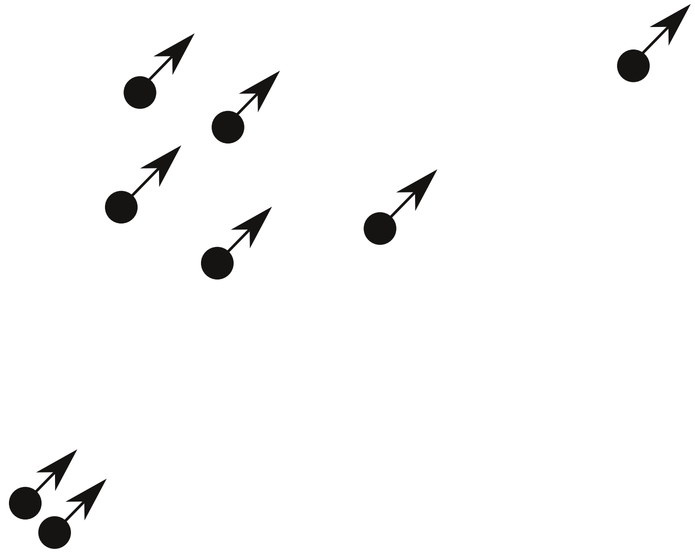
Particle Filter

Sensor model



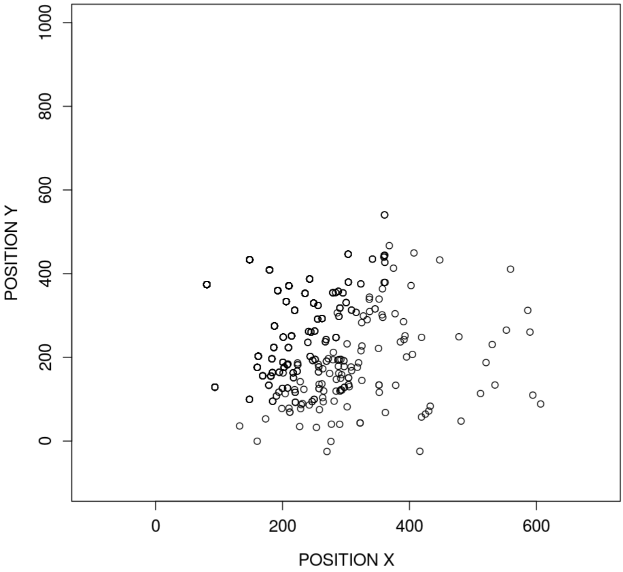
Motion model

Determine optical flow and add noise ~ N(0, 10)



FILTERING

GREAT
BUT
SLOW

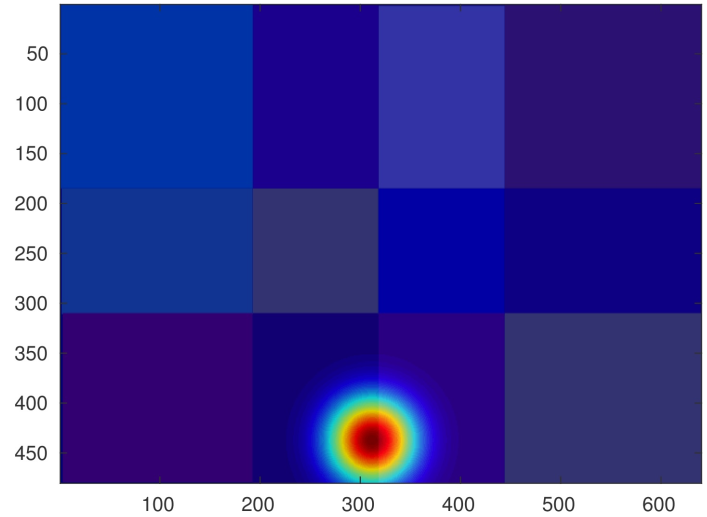


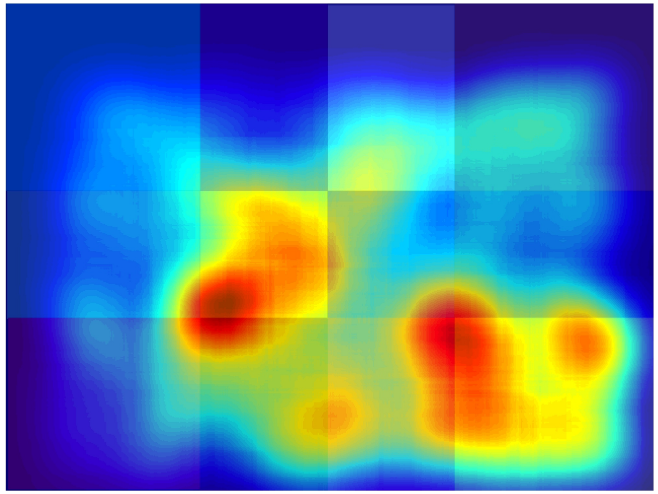
POSITION Y
0
200
400
600
800
1000
0
200
400
600
POSITION X

ENVIRONMENTAL MODIFICATION

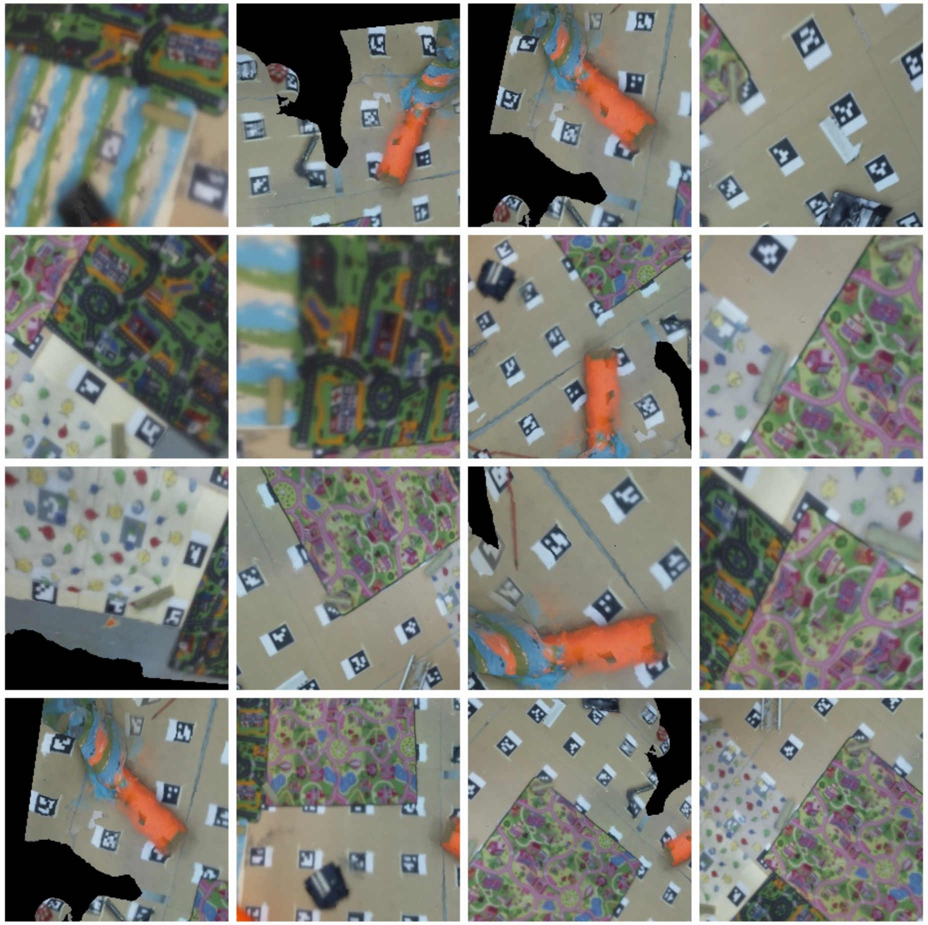
MAP EVALUATION

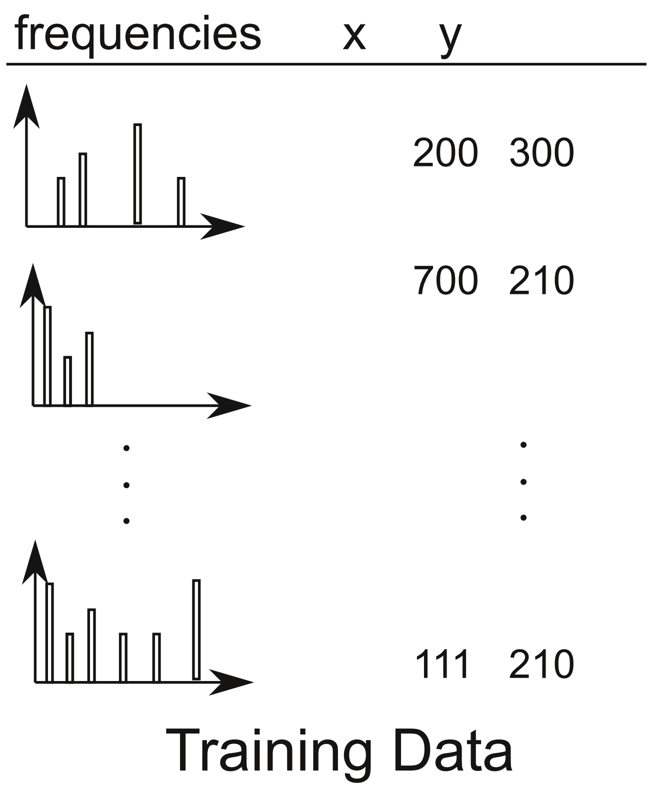
IDEAL SIMILARITY



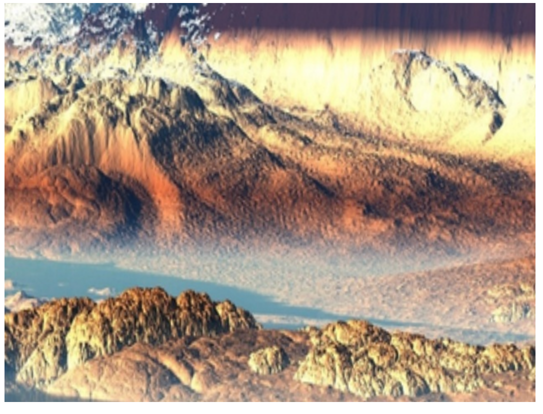


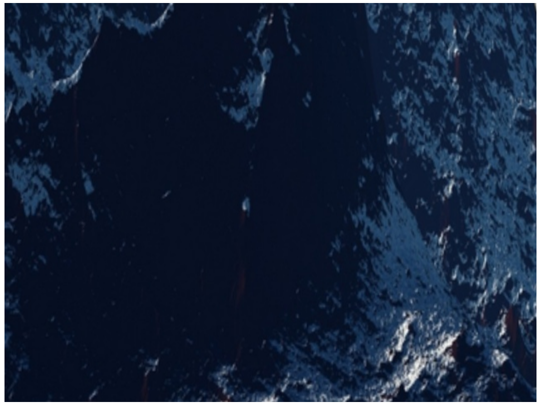
SYNTHETIC FLIGHT

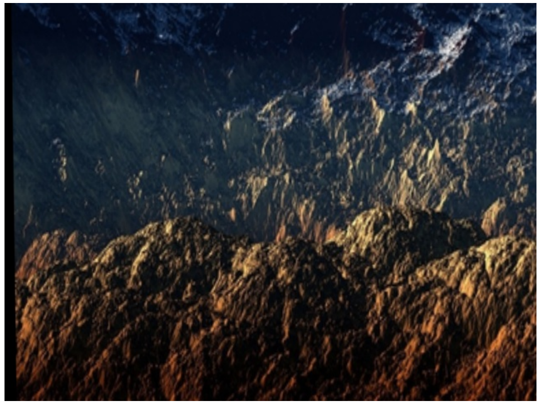




MAP EVALUATION







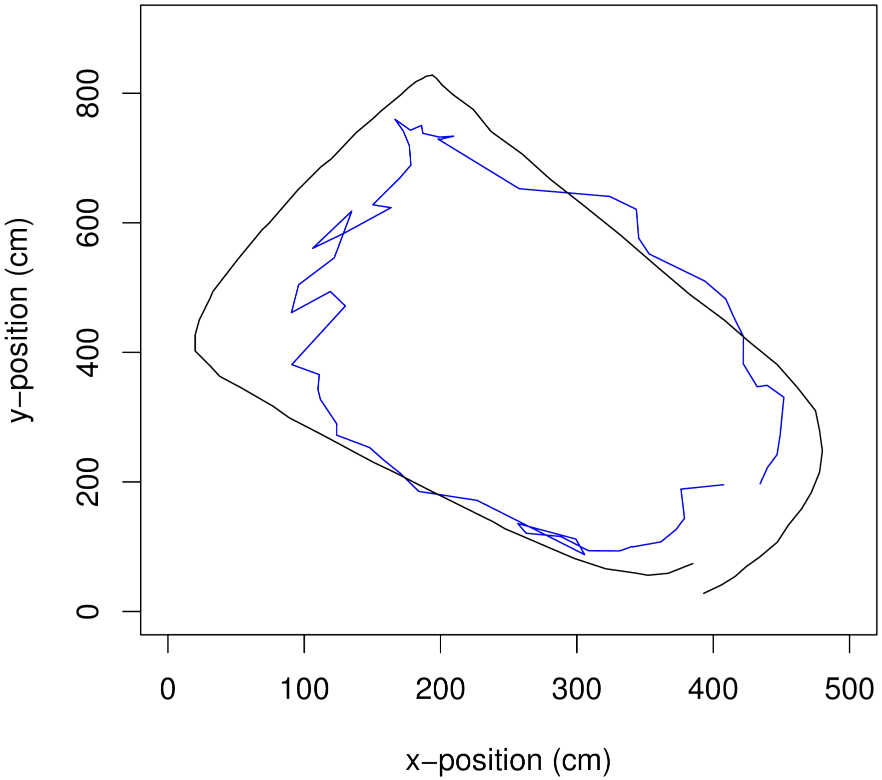
OUTLINE

- Related Work
- Methods
- **Experiments and Results**
- Discussion
- Conclusion

EXPERIMENTS

- Simulated flights
- Map evaluation
- Real-world Target Landing
- Real-world Navigation

FLIGHT ACCURACY



OptiTrack vs. treXton

Average distance

Standard deviation of errors

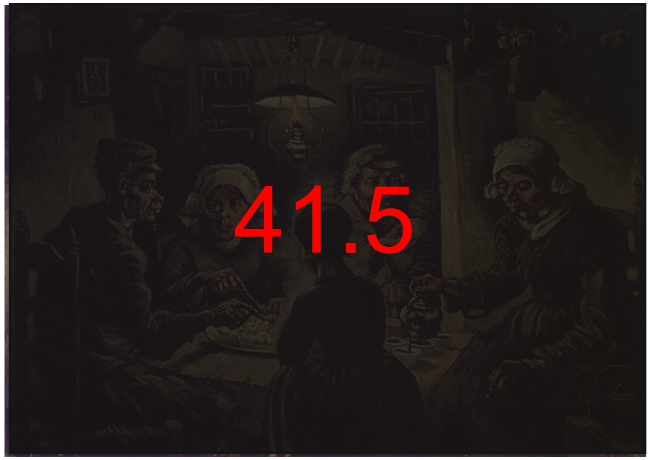
TRIGGERED LANDING

PLOT DELTA X Y OF SINGLE RUNS

OR USE TABLE

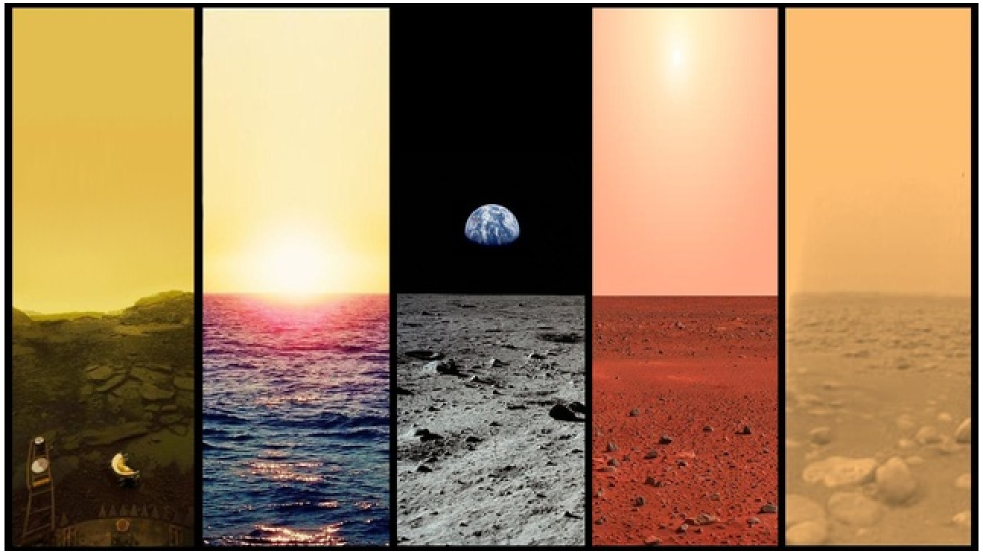
MAP EVALUATION

MAP EVALUATION



MAP EVALUATION

GOOD



BAD

RESEARCH QUESTIONS

Research Question 1

Can accurate indoor localization be done on a very limited platform?

Research Question 2

Can we predict the suitability of a given map for the proposed localization algorithm?

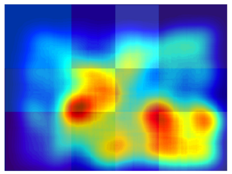
DISCUSSION

Implications:

- adaptable to different platforms

- robustness to motion blur

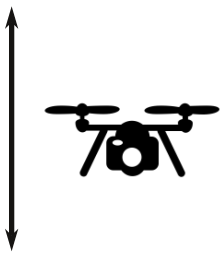
- detect safe landing spots

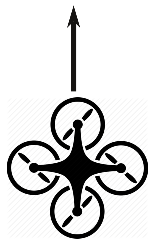


DISCUSSION

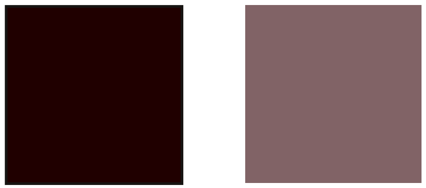
Limitations:

- assumes constant height and no rotations





- robustness to differerent lighting conditions



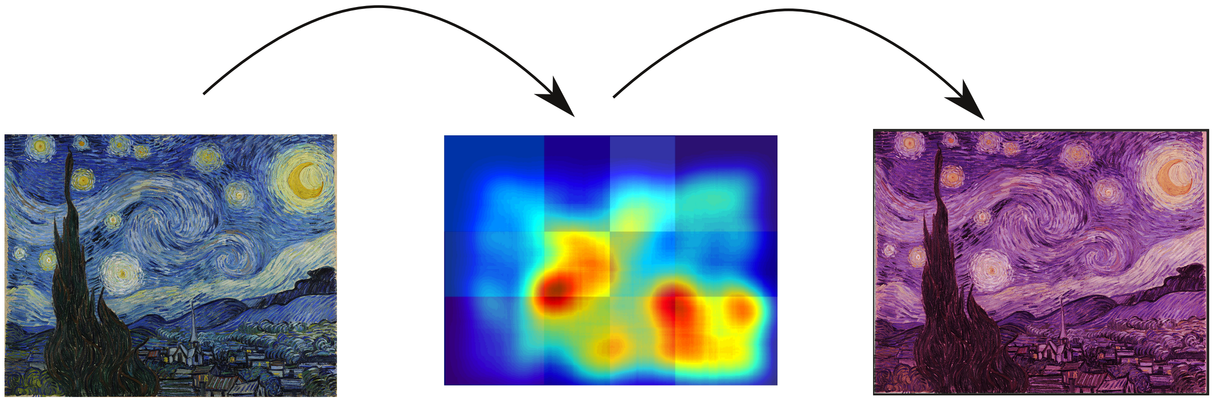
- Particle filter does not include velocity or heading

DISCUSSION

Future research:

- bridge reality gap

- automatic map generation (evolutionary algorithm)



CODE CONTRIBUTIONS

- Image augmentation with synthetic views (C++)

  https://github.com/Pold87/draug

- Map evaluation (MATLAB)

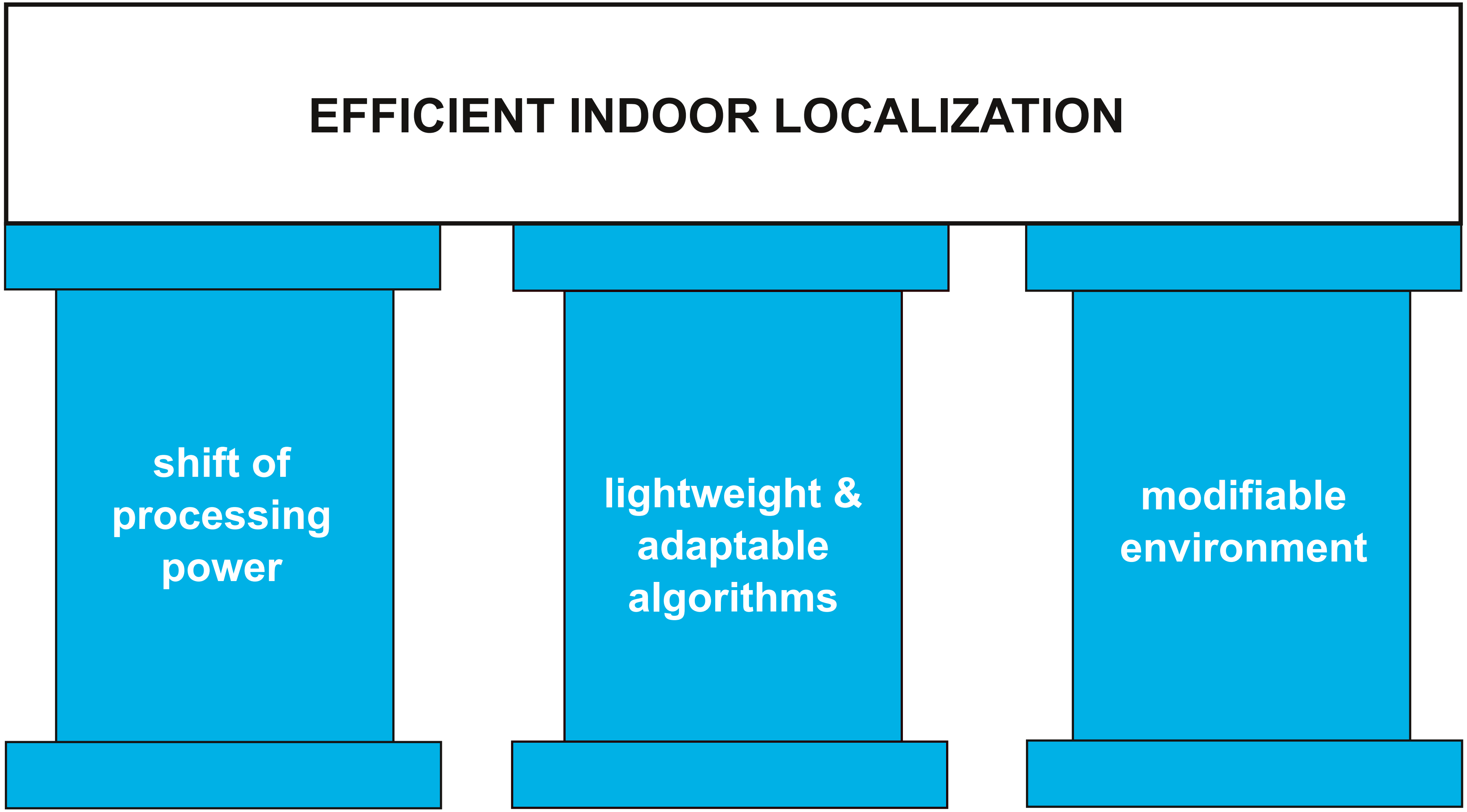
  https://github.com/Pold87/evaluation-thesis

- Localization: SIFT matching, particle filter, texton-based approach (C)

  C: https://github.com/Pold87/paparazzi   Python: https://github.com/Pold87/treXton

PAPARAZZI
The Free Autopilot

CONCLUSION



EFFICIENT INDOOR LOCALIZATION
shift of processing power
lightweight & adaptable algorithms
modifiable environment