CSE 490R:
Mobile Robots

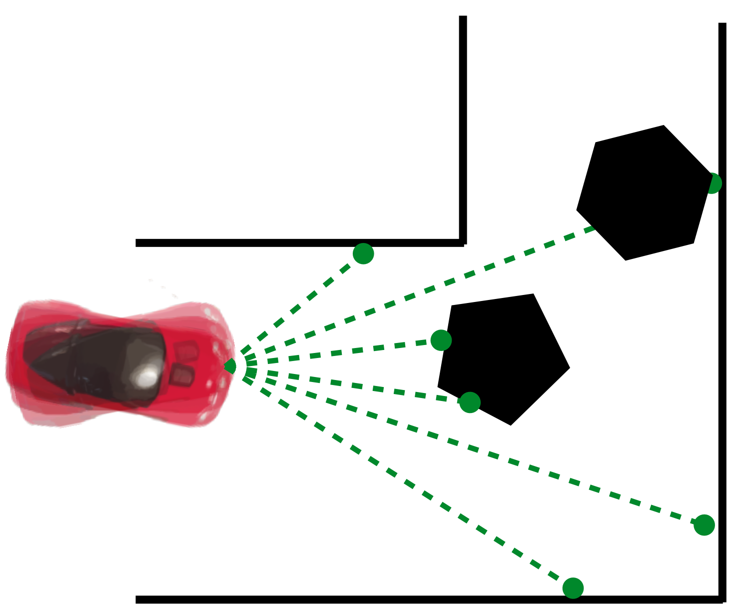
Sanjiban Choudhury

TAs: Matthew Rockett, Gilwoo Lee, Matt Schmittle

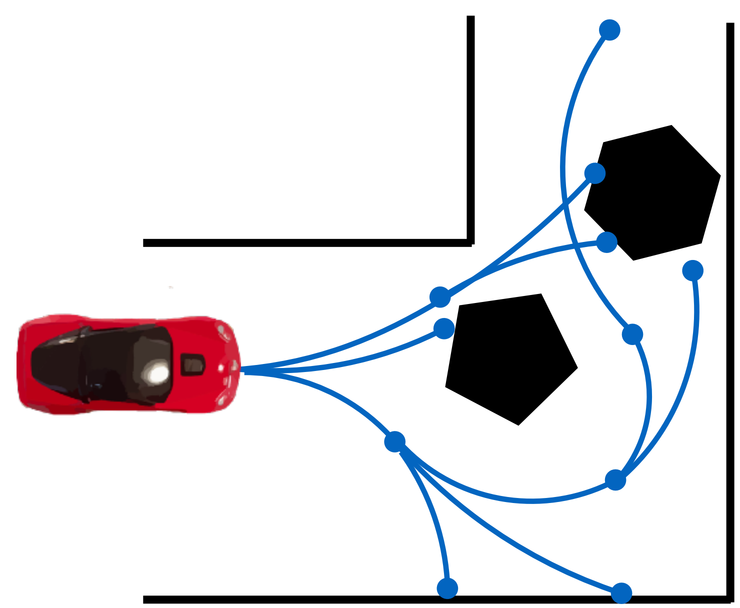
Logistics

- Submit knowledge survey ASAP
- Form a 3 person team by today, Wednesday 4/3 (send a private note to instructors in Piazza)
- Assignment 0 is released and due on 4/12.
    - Familiarize yourself with ROS
- Come to recitation on Thursday, get your robot and start working on Assignment 0.

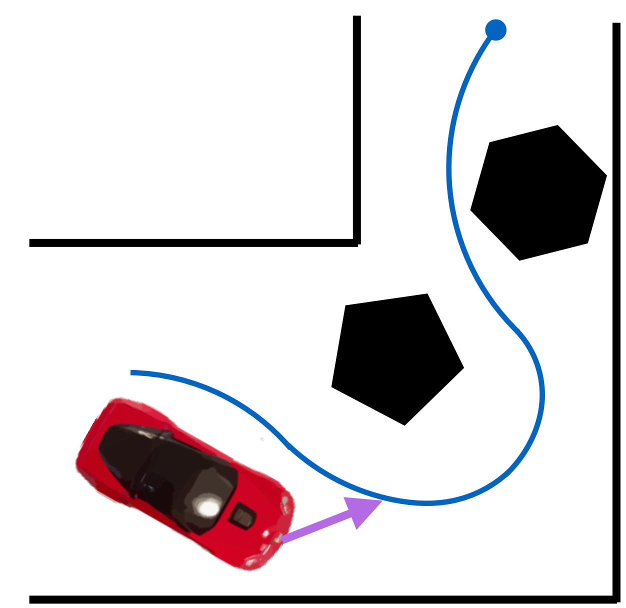
Estimate state



Plan a sequence of motions



Control robot to follow plan



Anatomy of a self-driving car

Sanjiban Choudhury

BOSS: CMU’s winning entry to DARPA challenge

(2007)


CAT
19

Tartan Racing: A Multi-Modal Approach to the DARPA Urban Challenge

April 13, 2007

Chris Urmson, Joshua Anhalt, Drew Bagnell, Christopher Baker, Robert Bittner, John Dolan, Dave Duggins, Dave Ferguson, Tugrul Galatali, Chris Geyer, Michele Gittleman, Sam Harbaugh, Martial Hebert, Tom Howard, Alonzo Kelly, David Kohanbash, Maxim Likhachev, Nick Miller, Kevin Peterson, Raj Rajkumar, Paul Rybski, Bryan Salesky, Sebastian Scherer, Young Woo-Seo, Reid Simmons, Sanjiv Singh, Jarrod Snider, Anthony Stentz, William "Red" Whittaker, and Jason Ziglar

Carnegie Mellon University

Hong Bae, Bakhtiar Litkouhi, Jim Nickolaou, Varsha Sadekar, and Shuqing Zeng

General Motors

Joshua Struble and Michael Taylor

Caterpillar

Michael Darms

Continental AG

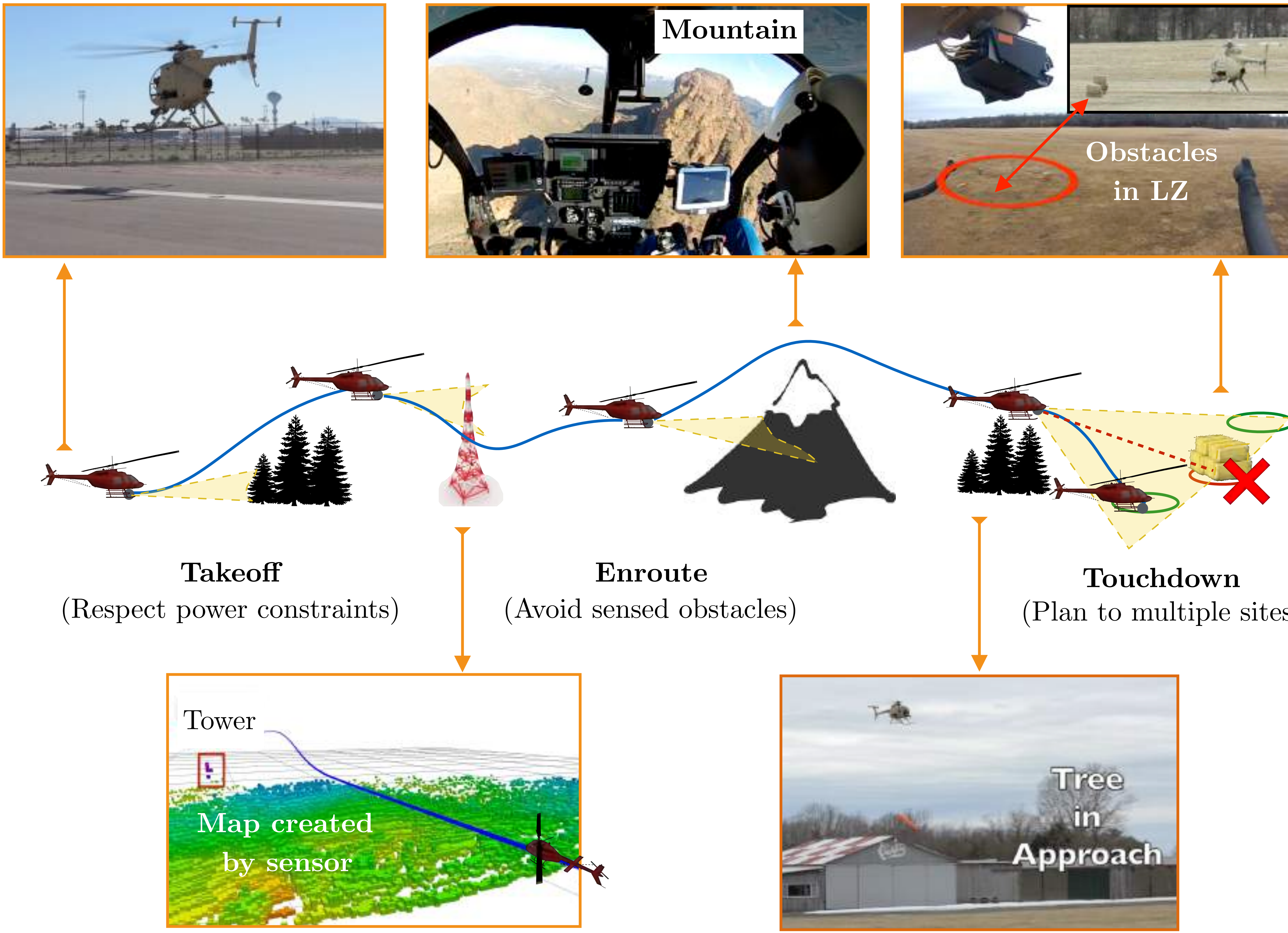
http://repository.cmu.edu/cgi/viewcontent.cgi?article=1967&context=robotics

Anatomy of a ~~self-driving car~~ self-flying helicopter

Sanjiban Choudhury

Autonomous full-scale helicopter

Mission: Take-off to landing



Mountain
Obstacles
in LZ
Takeoff
(Respect power constraints)
Enroute
(Avoid sensed obstacles)
Touchdown
(Plan to multiple sites)
Tower
Map created
by sensor
Tree
in
Approach

Today's objective

1. Learn how to architect a mobile robotic system

2. Step through a set of fundamental lessons
that shape robot system / algorithm design

Task: A contract the robot has to satisfy

Given:

Start (lattitude, longitude), Goal (lattitude, longitude)

List of no-fly-zones (unsafe air space)

Coarse terrain map of continental USA

Sensors - GPS, Laser, etc

Objective:

Minimize time it takes to complete mission

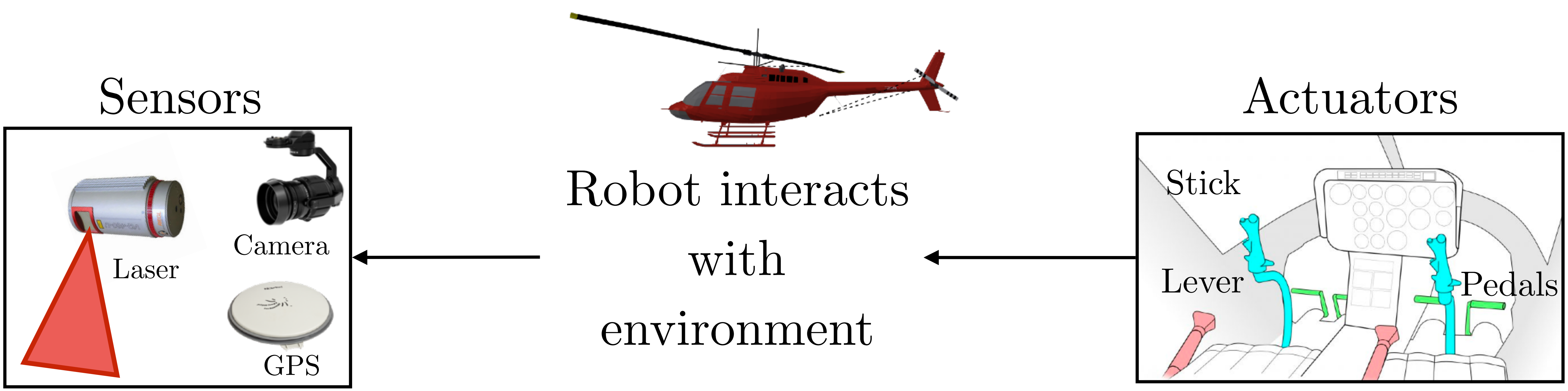
Constraint:

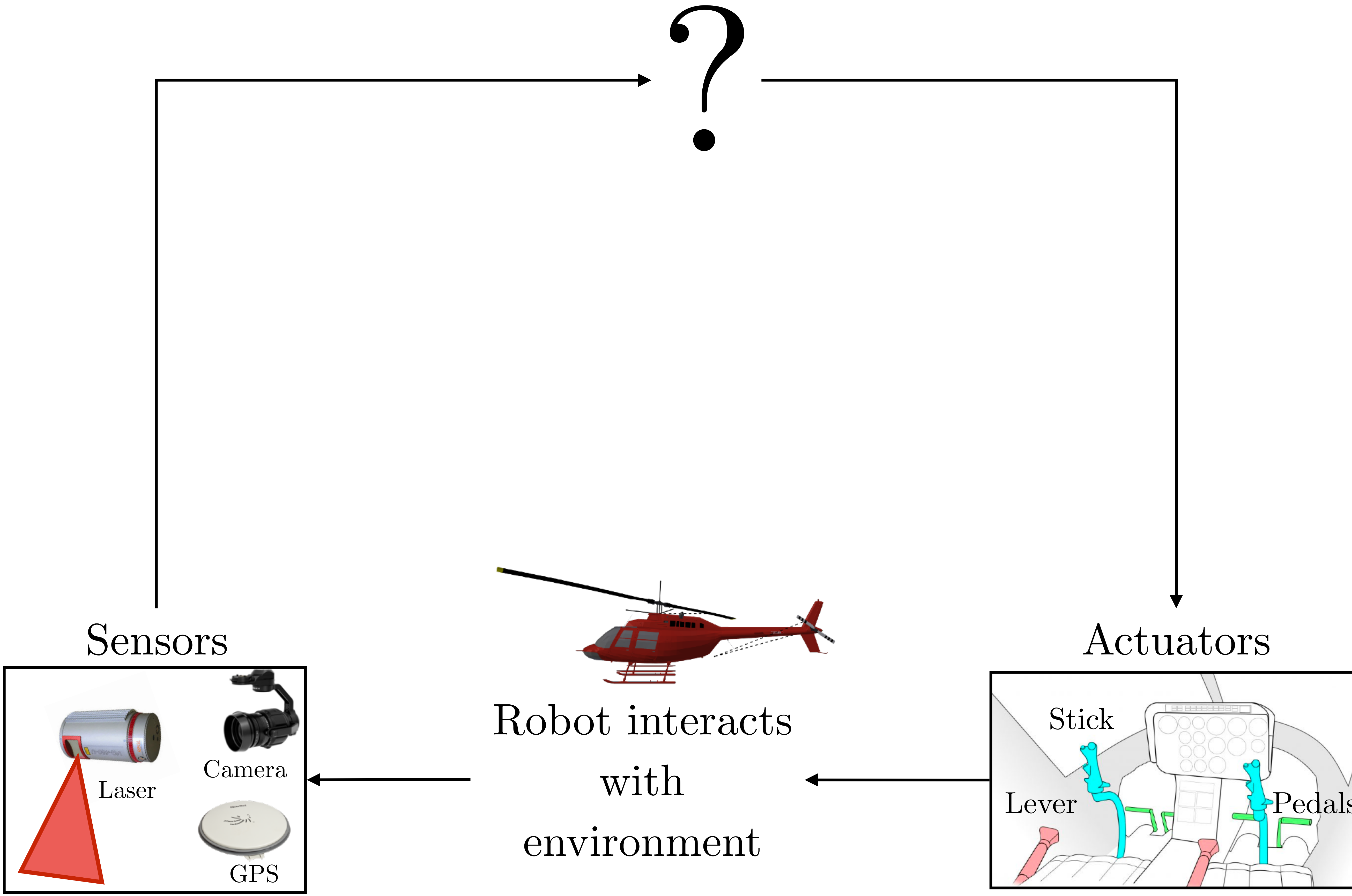
Don't come close to obstacles / don't enter no-fly-zones

Don't exceed limits of the vehicle (flying upside down)

How do we tractably solve the task?

Begin with a blank slate


Sensors
Laser
Camera
GPS
Robot interacts
with
environment
Actuators
Stick
Lever
Pedals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Lesson 0: Look at one piece at a time

Q1: Assume we know everything about the world.

What commands should we send to the actuator?

Q2: How do we use raw sensor data to update what we know about the world?

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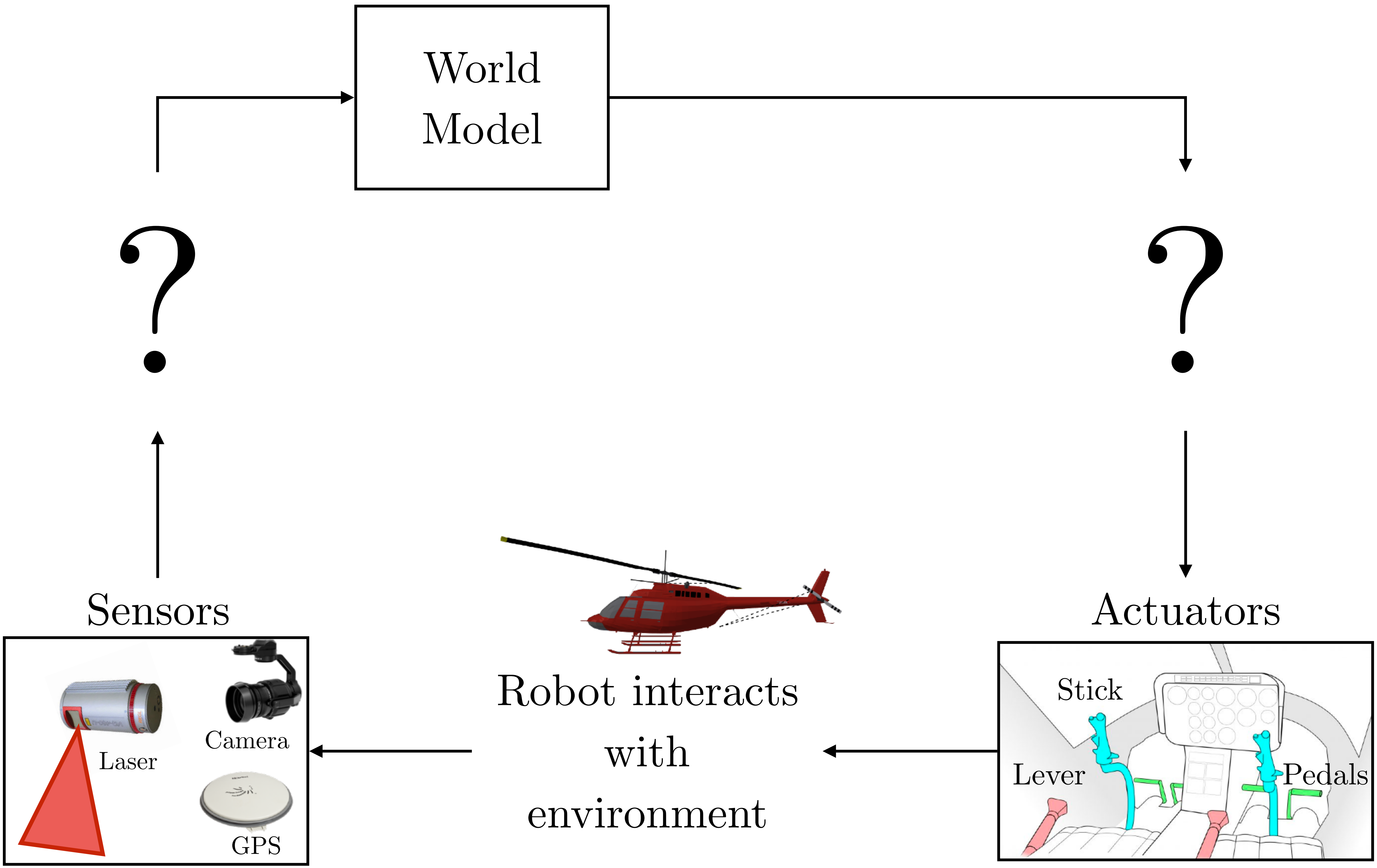
World Model
?
?
Sensors
Actuators
Laser
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Robot interacts with environment
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Pedals

What is the world model?

List of everything we need to know to accomplish the task

- Where is the robot in the world? What is it's state?

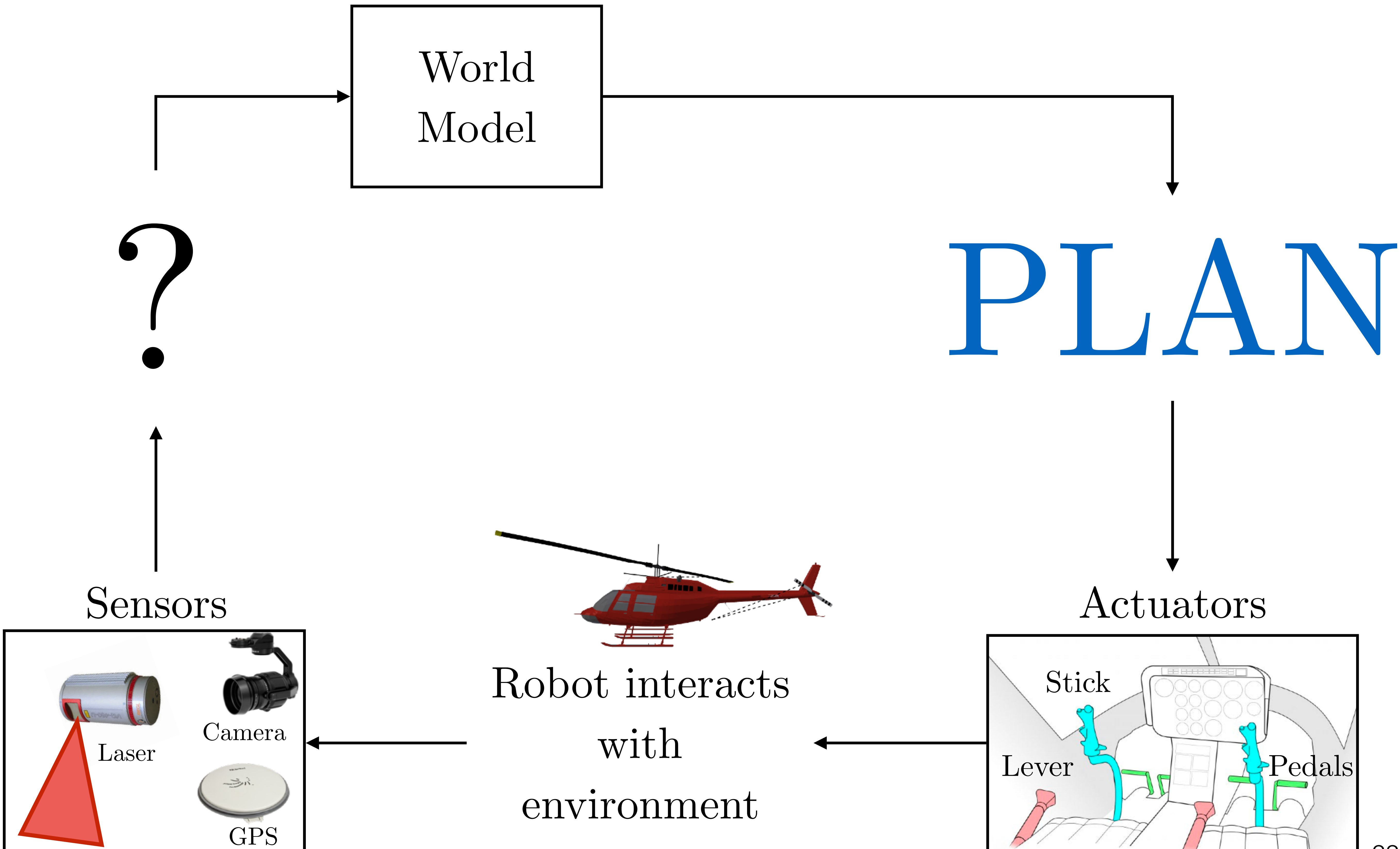
- What are the obstacles in the world?

- What type are the obstacles (radio towers, trees)?

- What are the no-fly-zones?

- Are there other aircrafts?

- What is the wind, temperature, etc?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What is planning?

Planning is an optimization problem where ...

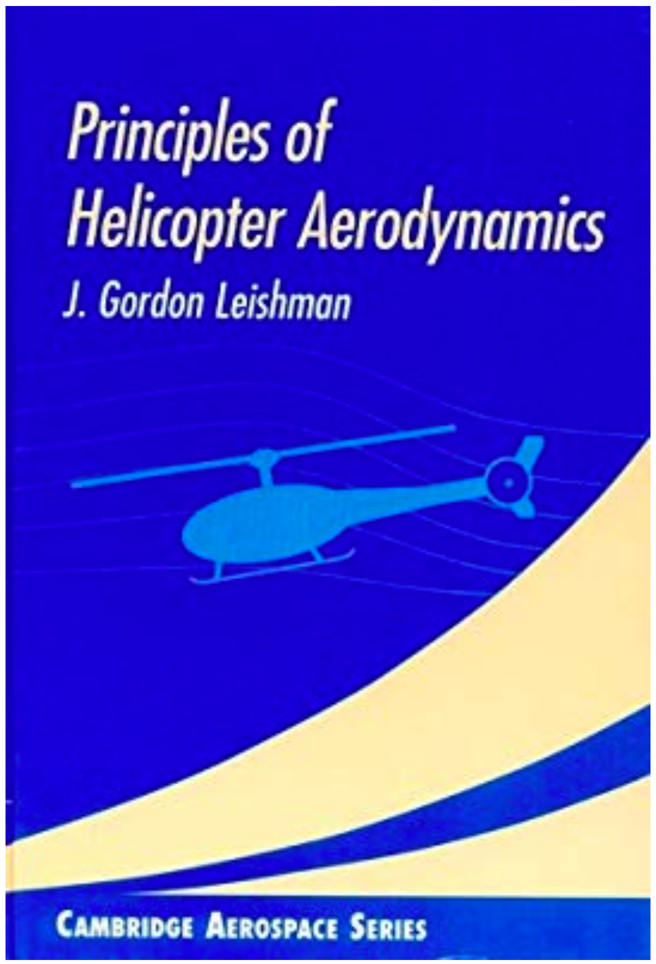
Searching over a sequence of actions

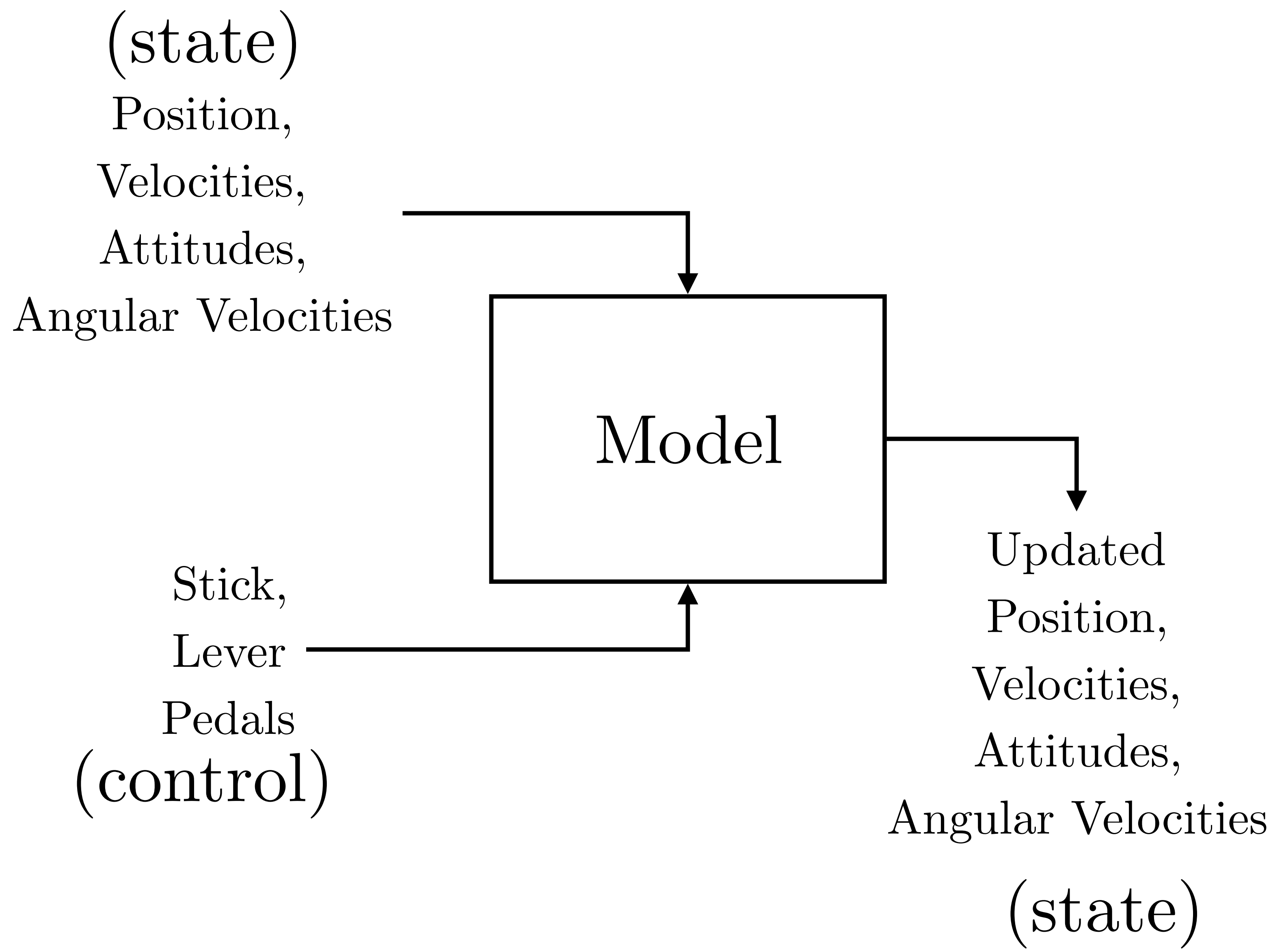
Using a model of your robot to predict where it will go

Minimize time to reach the goal

Don't violate constraints (e.g. crash)

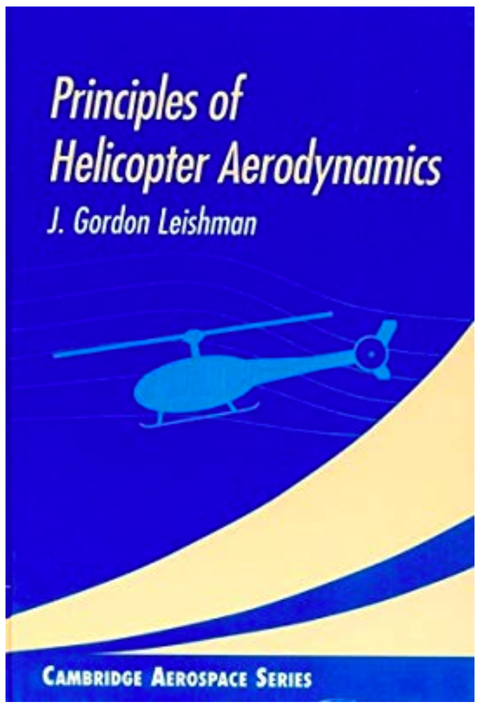
How do we get a model of the helicopter?





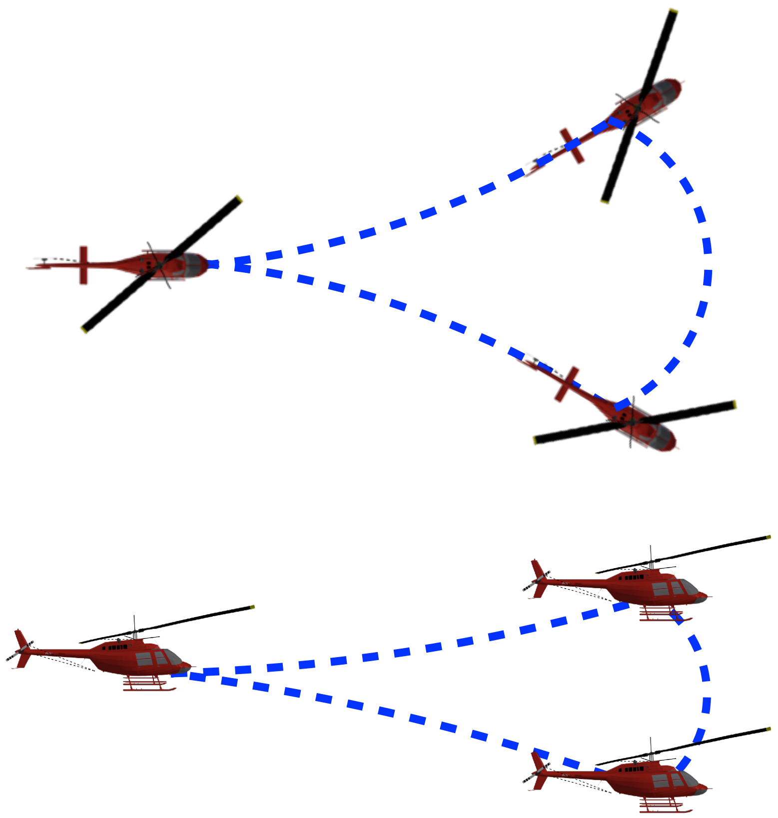
Problem: Model is very complicated! Intractable to plan with it.

Lesson 1: Plan with simple models



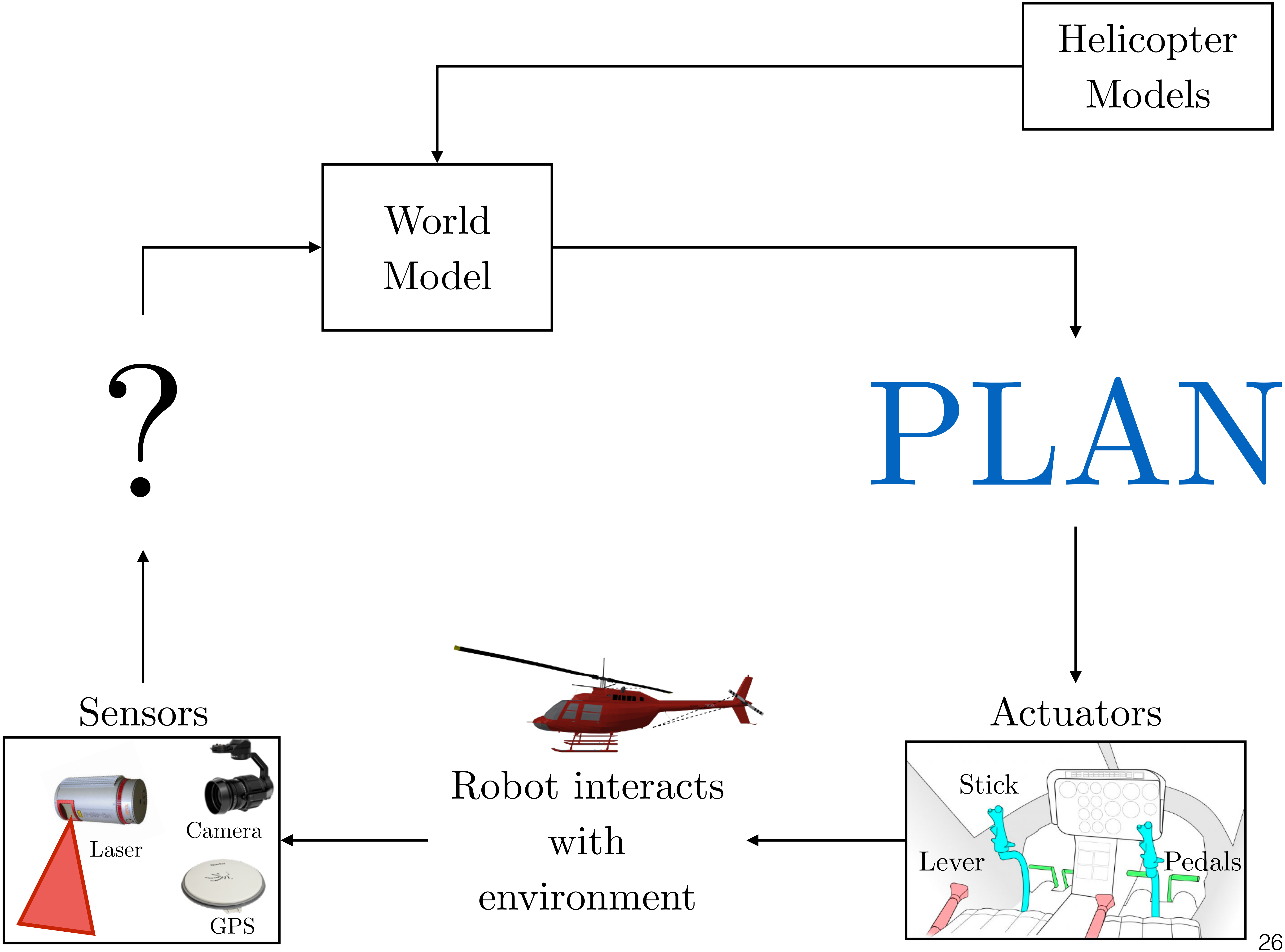
Complex aerodynamical model

Use domain knowledge to simplify model



Flying unicycle at high speeds!

Different models at different flight regimes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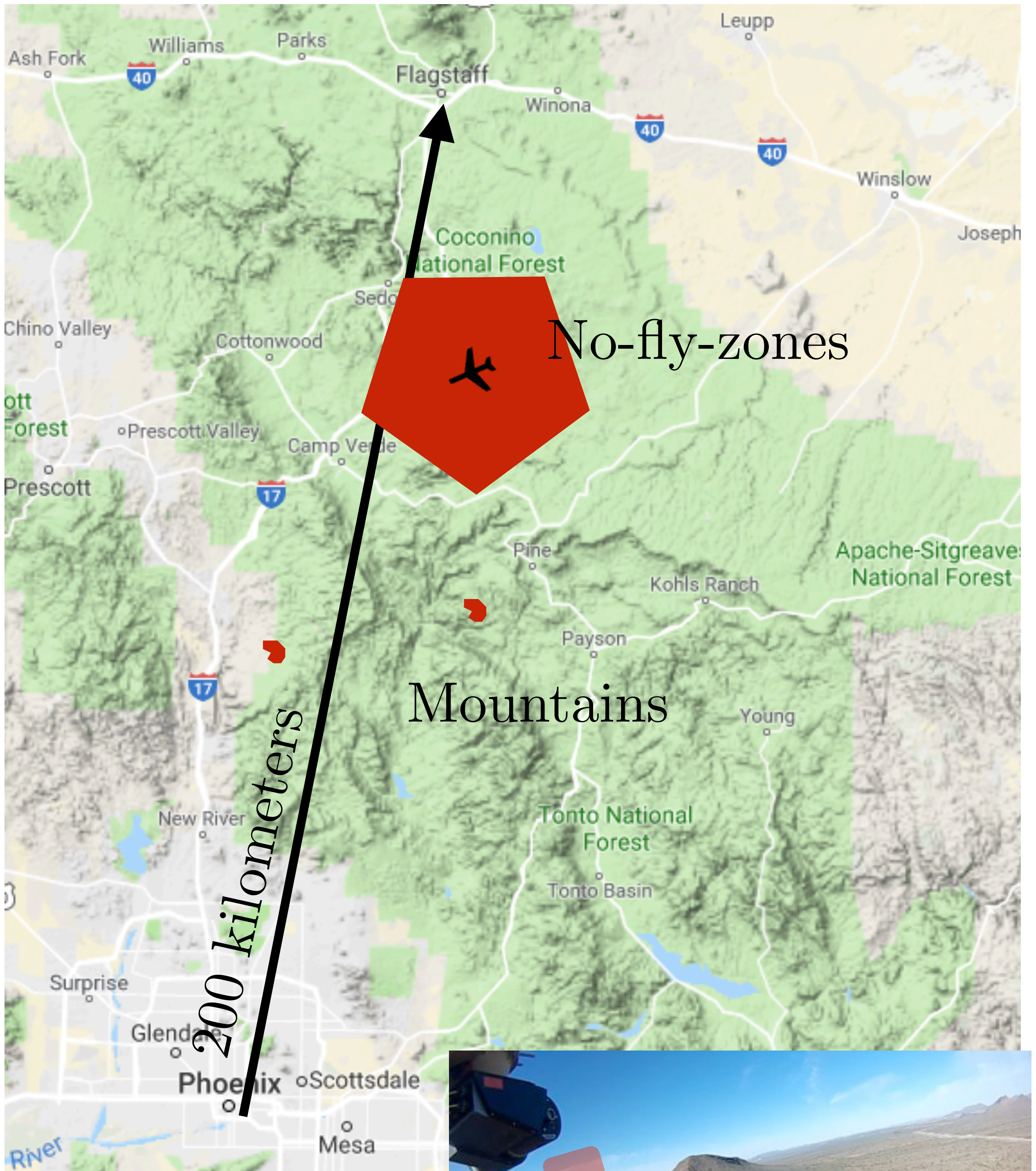
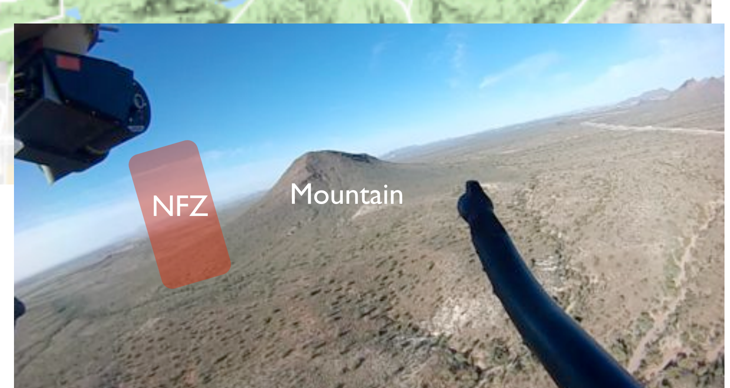
What resolution should we plan?





Example mission:

Fly from Phoenix to Flagstaff as fast as possible (200 km)

Avoid mountains, no-fly-zones, radio towers, wires, bad weather

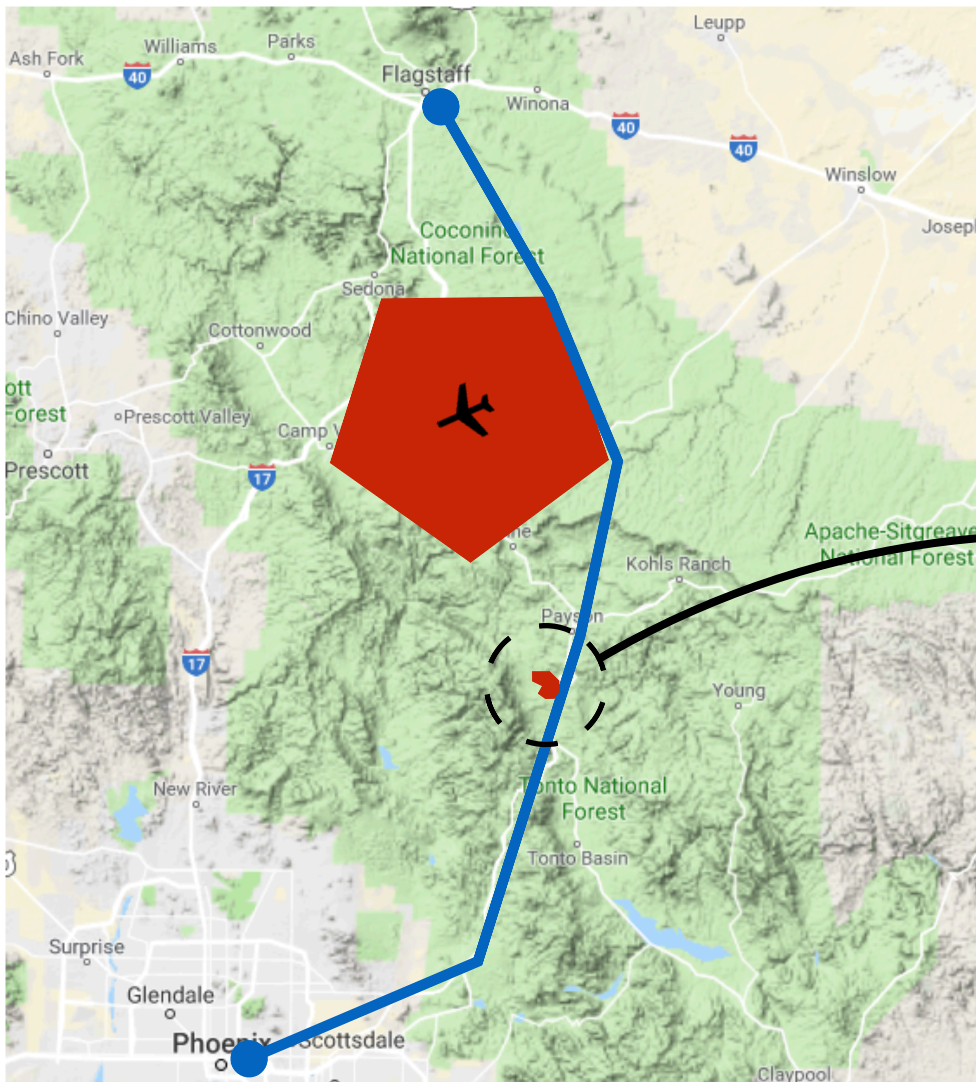
Pass through narrow gaps

Problem:

Take forever to plan at high resolution ALL the way to goal

Lesson 2: Plan at multiple resolutions

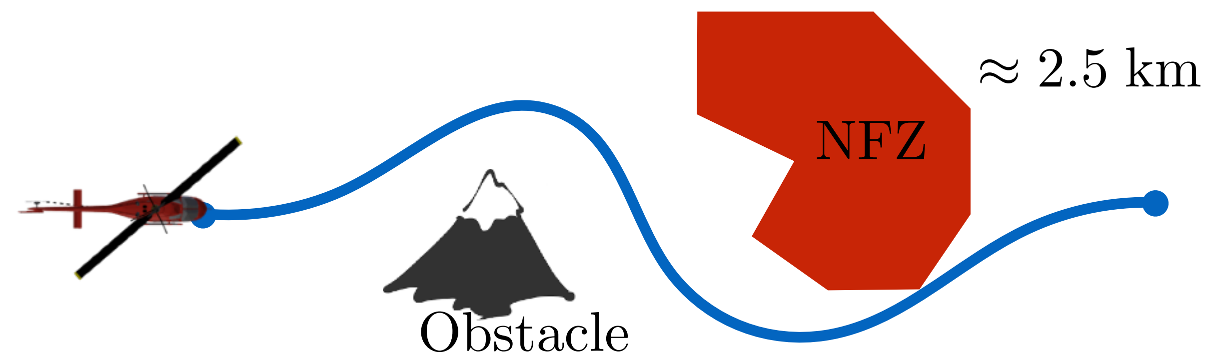
Global planner



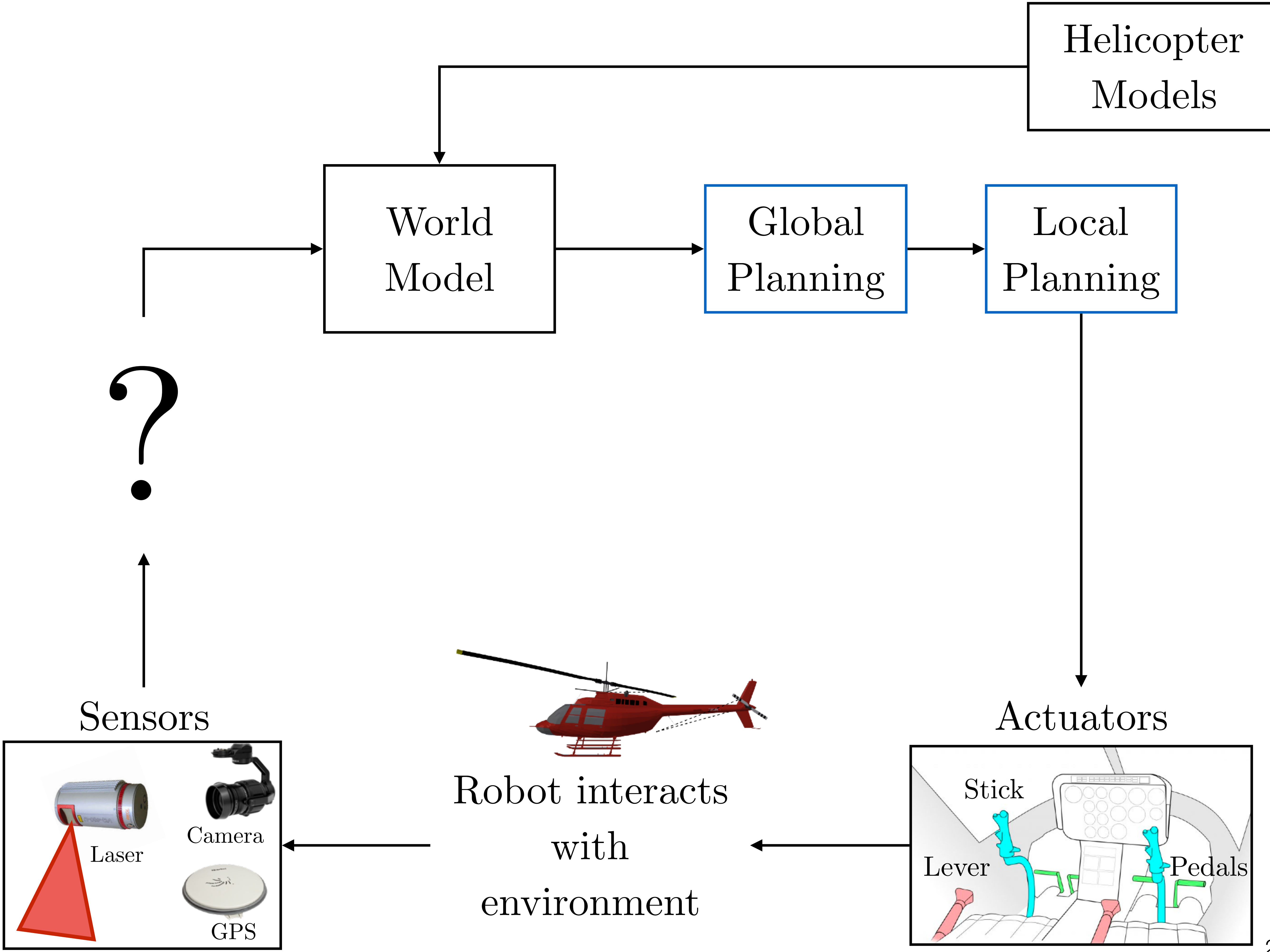
Plan at coarse (1km) resolution,
compute entire route from start to goal
avoid large obstacles, no-fly-zones etc

(only consider factors that
significantly affect mission time)

Local planner



Plan at high (10 m) resolution,
follow the global route,
avoid all obstacles, produce smooth
dynamically feasible paths



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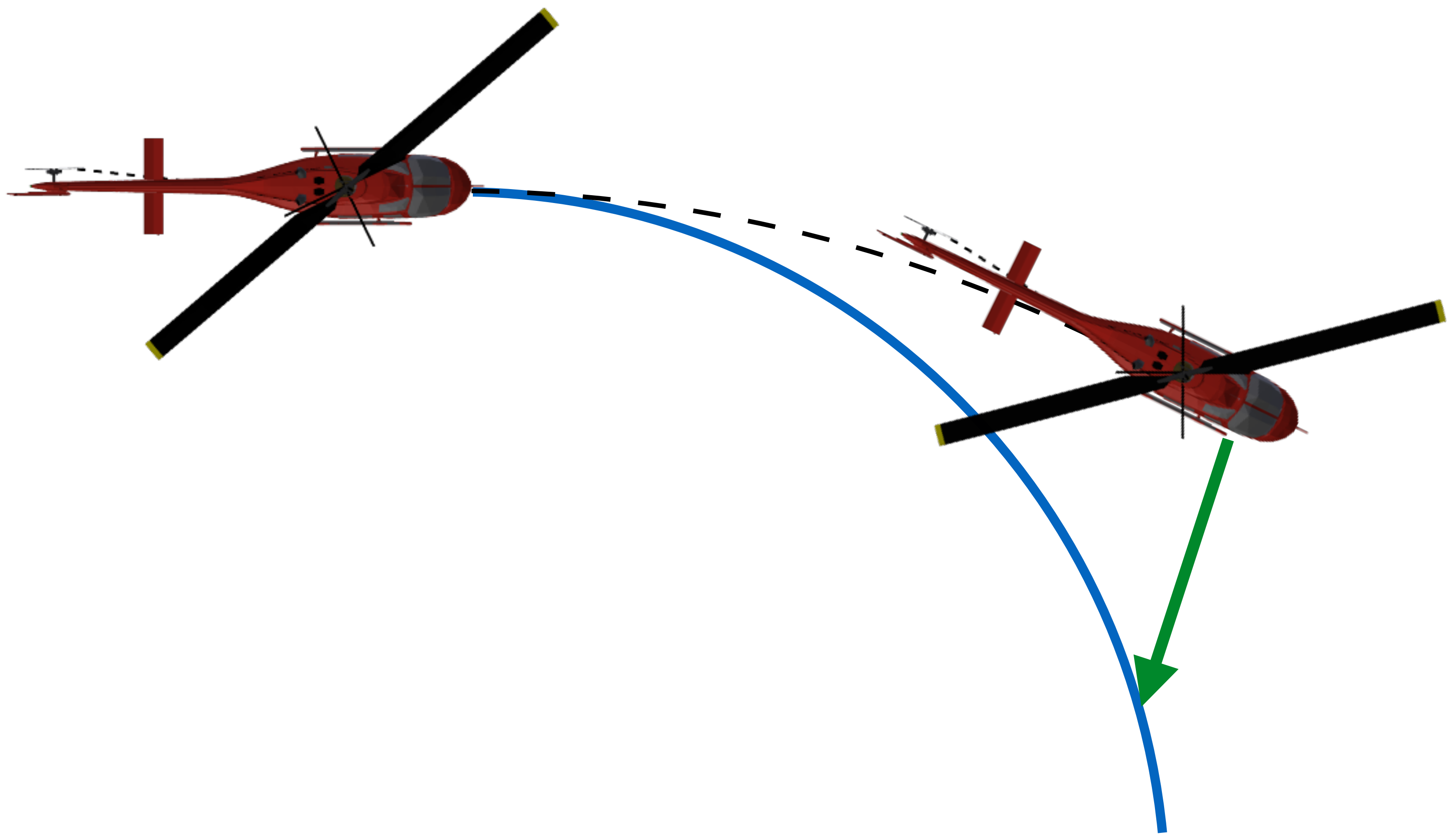
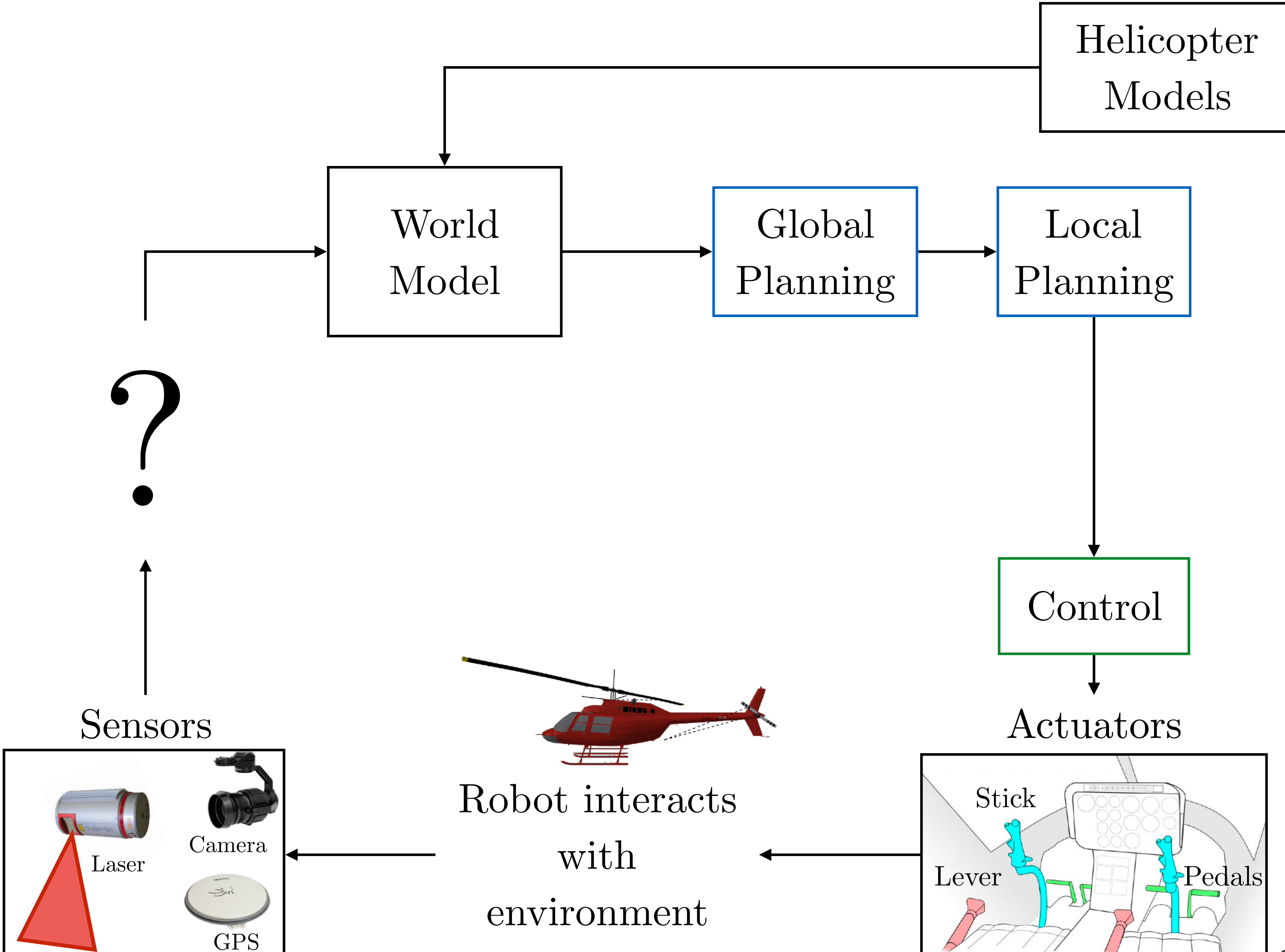
Lesson 3: Open loop planning is not enough



Robot will go "off" the plan for many reasons
(disturbance, model errors, actuation errors, ...)

A controller immediately corrects for any tracking error
and gets the robot back on the path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Look at one piece at a time

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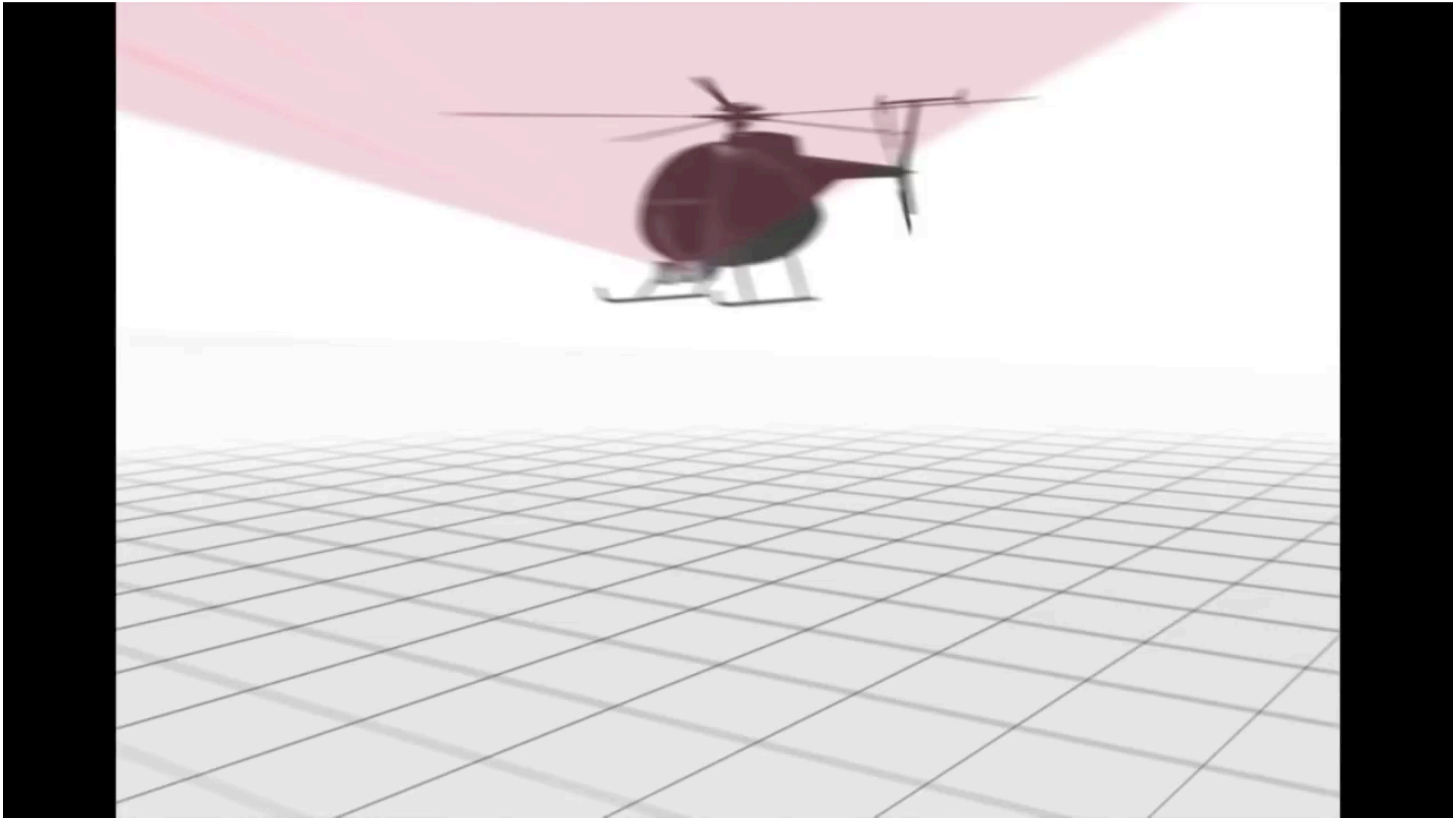
What is the world model?

List of everything we need to know to accomplish the task

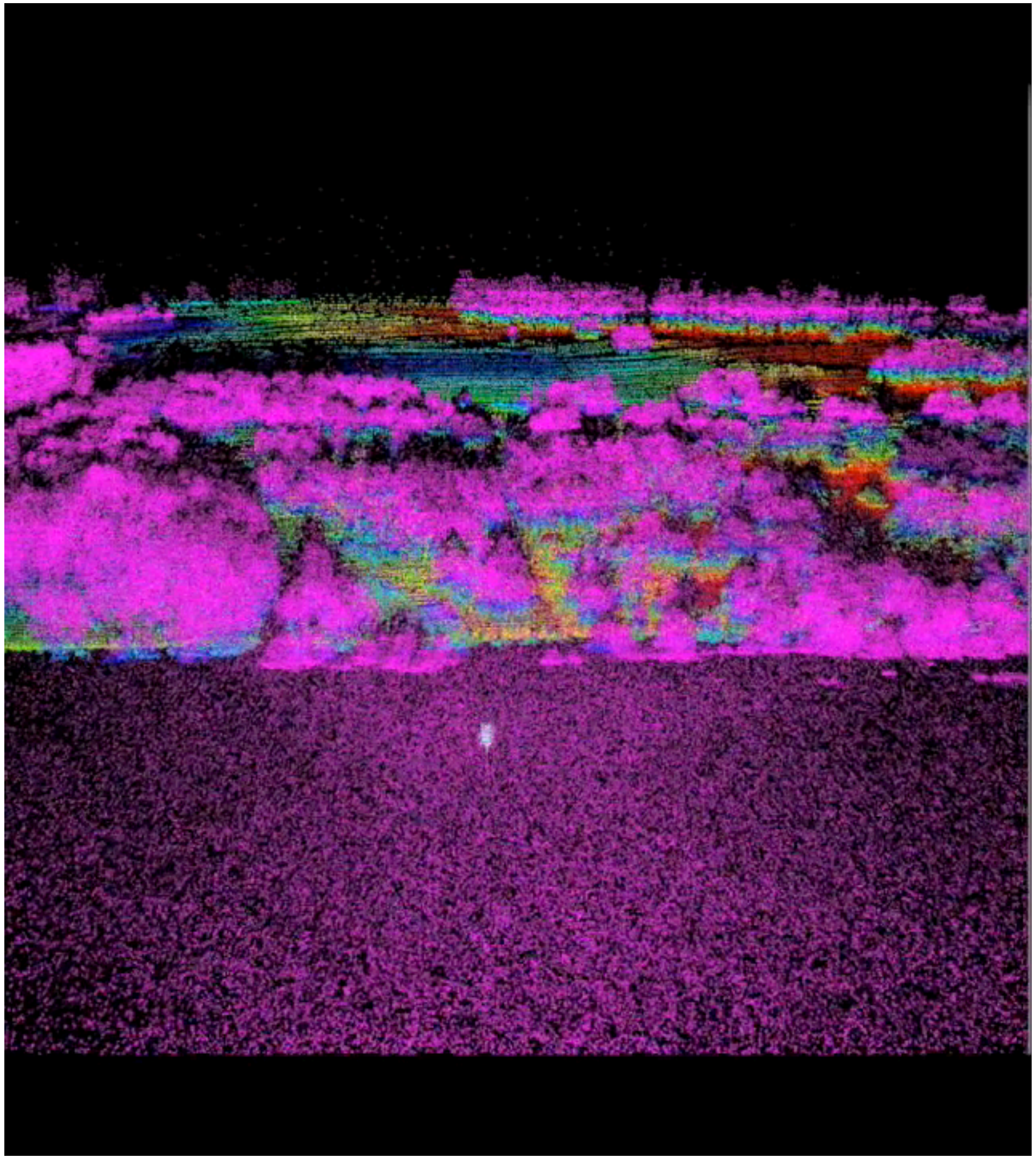
- Where is the robot in the world? What is it's state?	GPS
- What are the obstacles in the world?	Laser
- What type are the obstacles (radio towers, trees)?	Camera
- What are the no-fly-zones?	Radio
- Are there other aircrafts?	Radio
- What is the wind, temperature, etc?	Pitot tube, barometer, etc

Can we simply “fuse” laser readings to map the world?



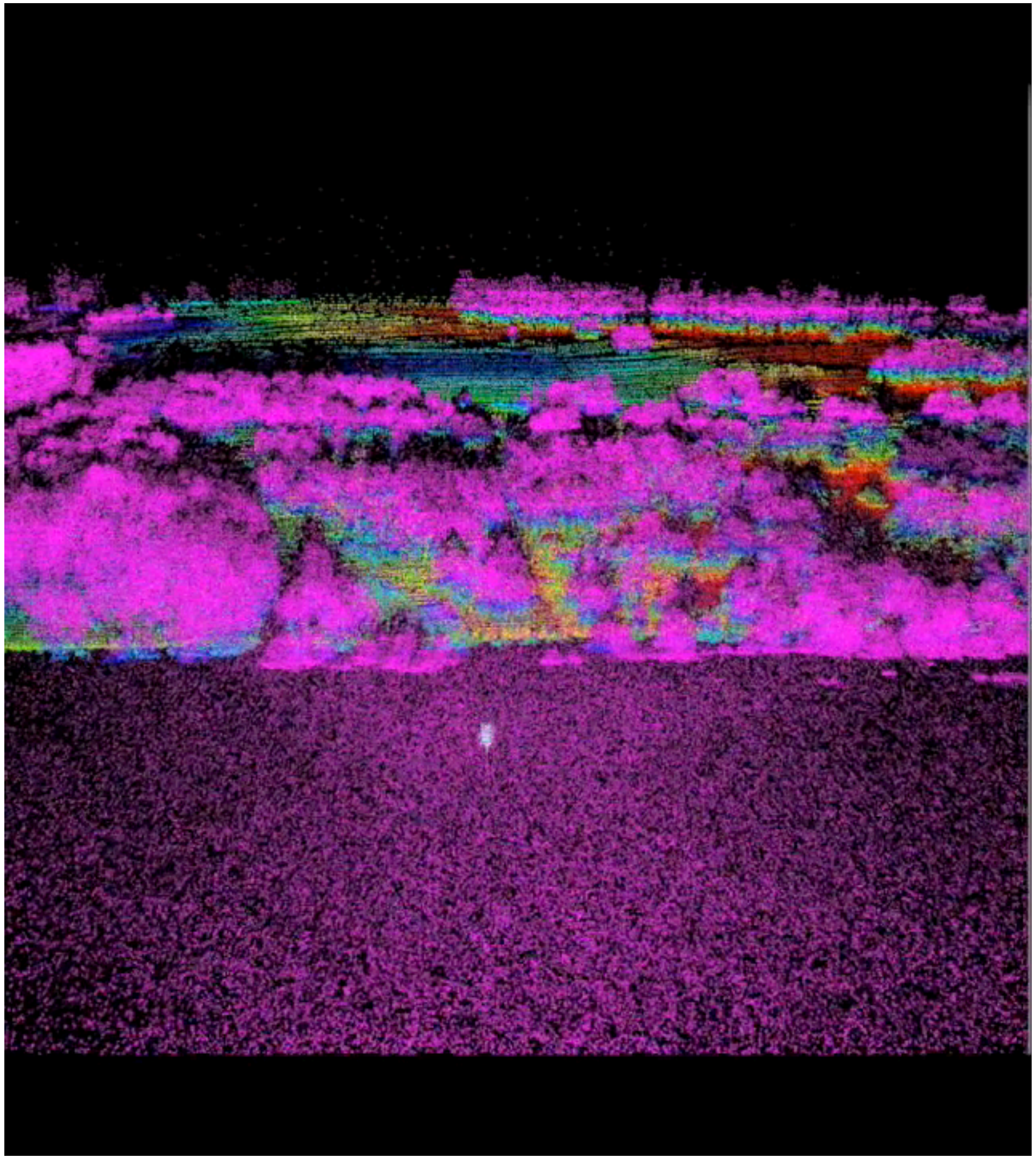
(courtesy Chamberlain et al.)

Lesson 4: Use probabilistic models of the sensor

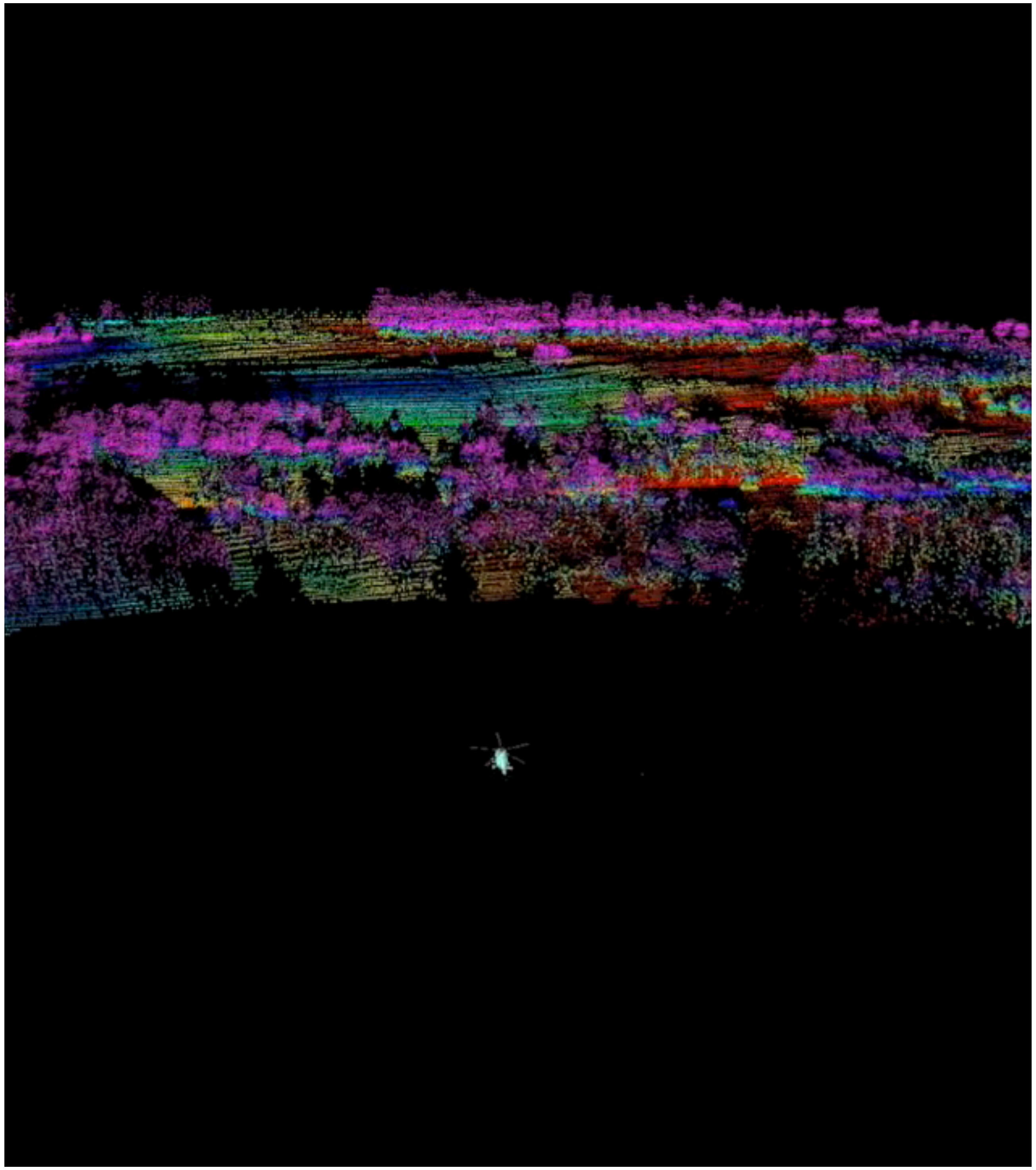


Flying in a snow storm

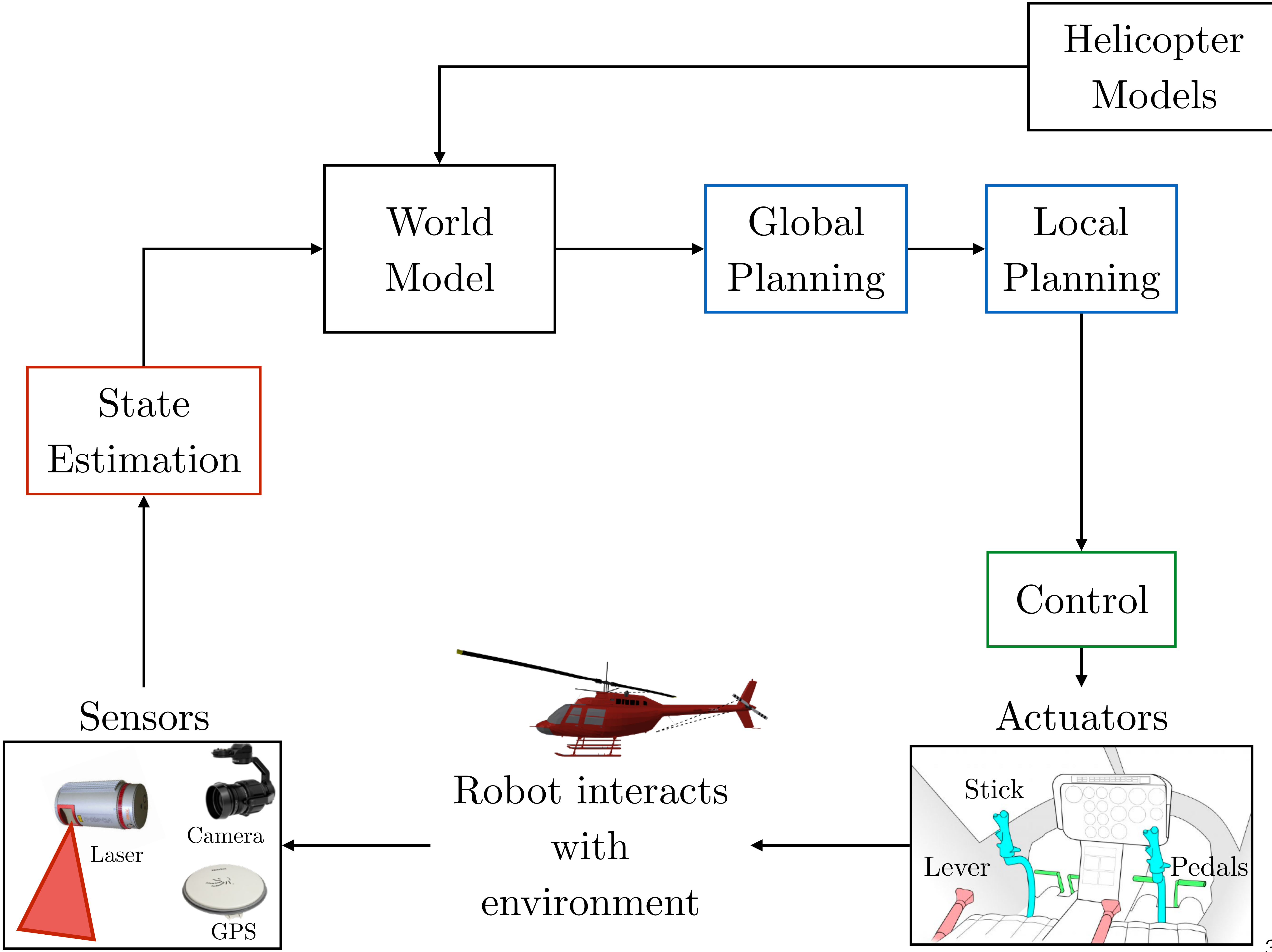
Lesson 4: Use probabilistic models of the sensor



Laser reflected by snow!



Correctly fused laser data using probabilistic models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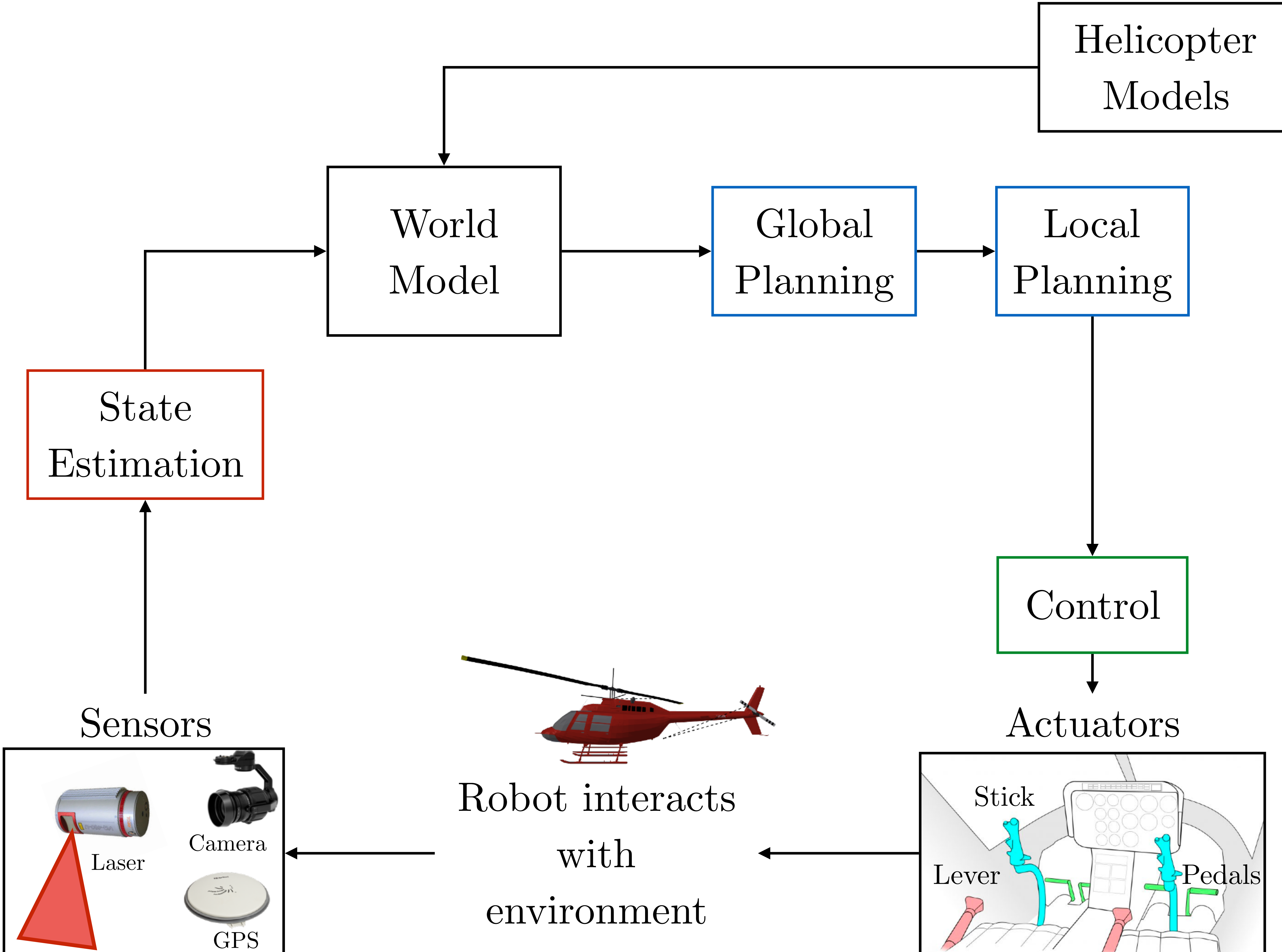
What is state estimation?

Given raw sensor data, use probabilistic models to estimate world model

$$P(\text{world model}|\text{data})$$



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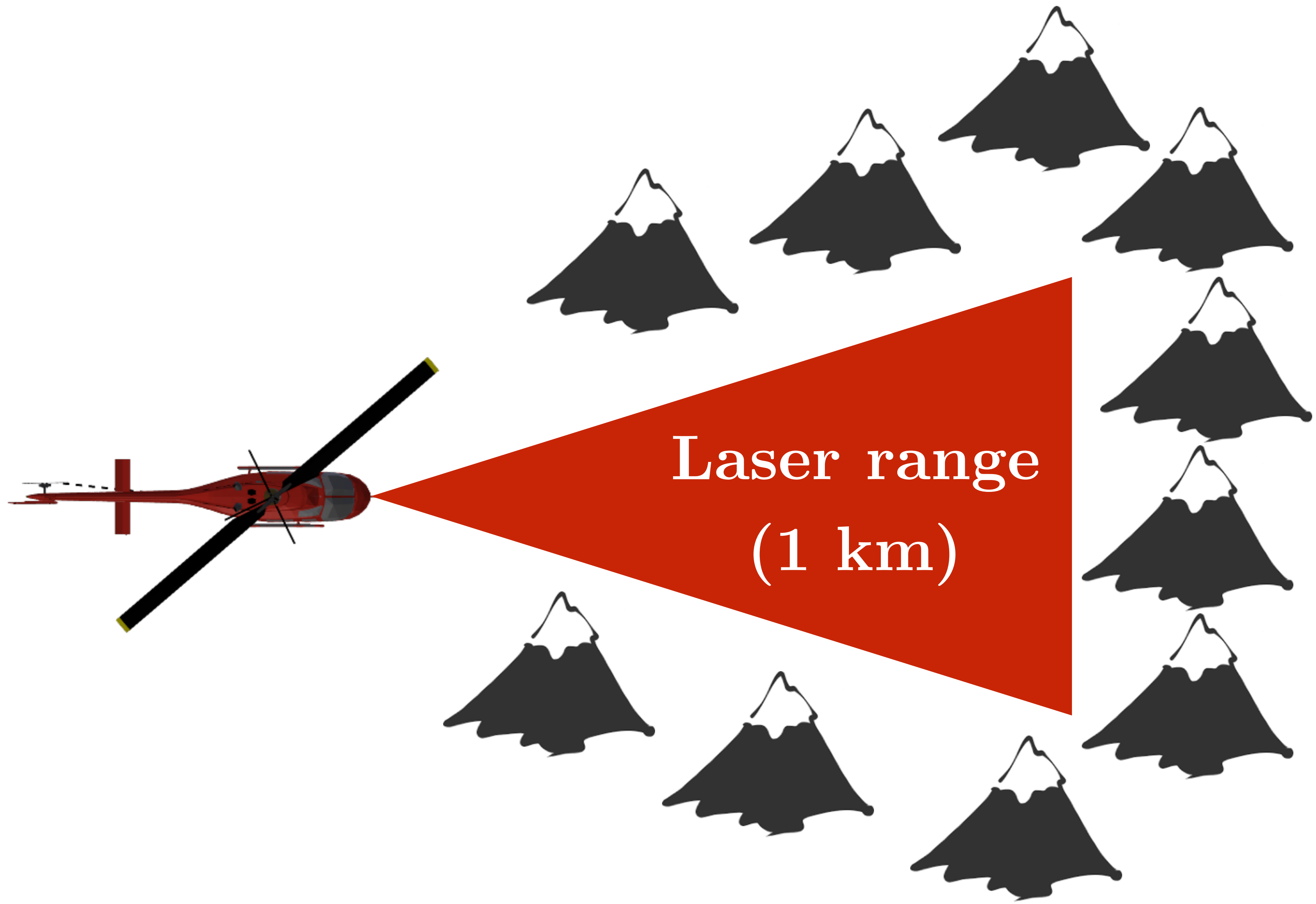
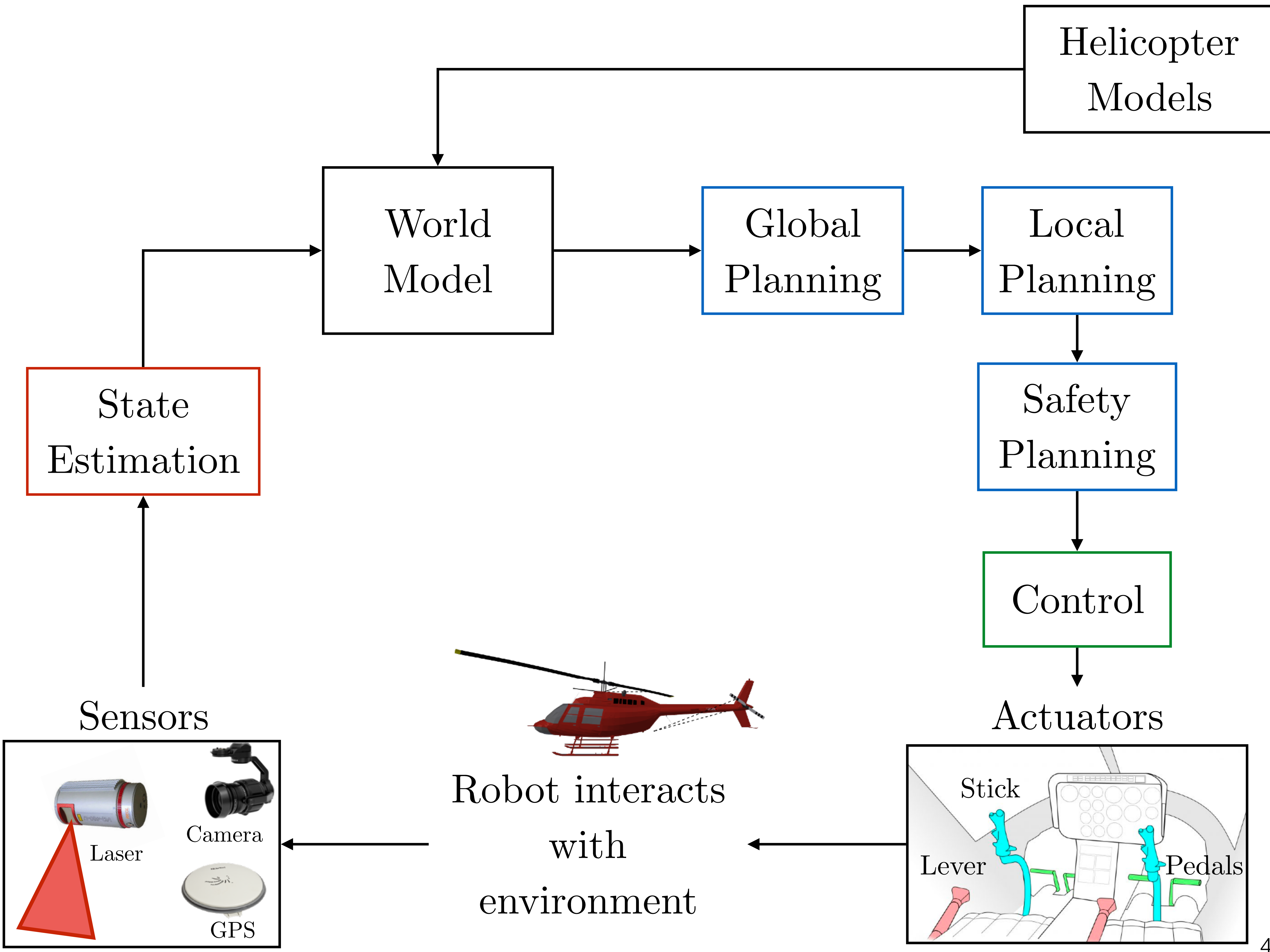
Lesson 5: Guarantee safety



What prevents the system from flying at high speeds to a dead end?

Safety planner that guarantees the robot can stay safe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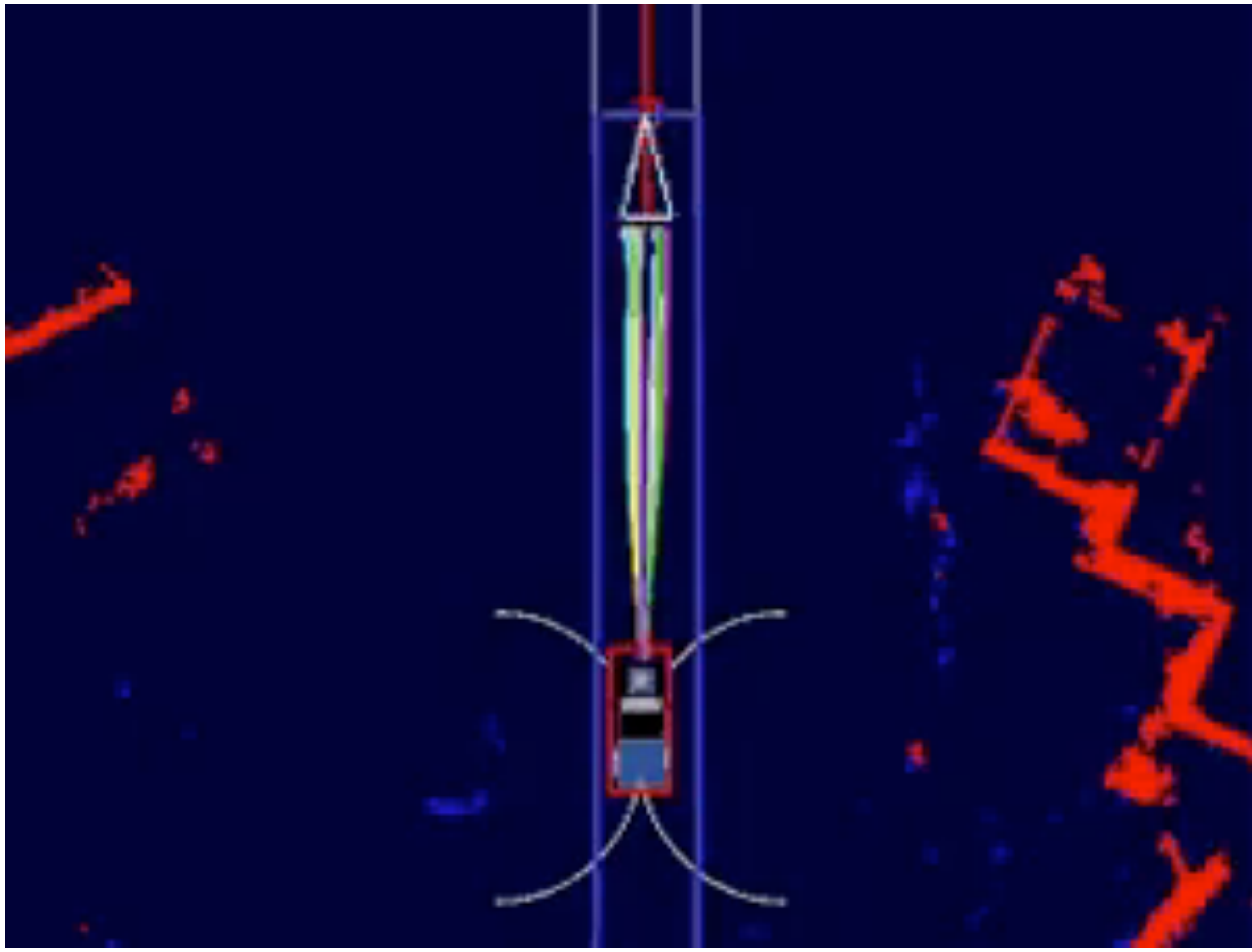
Today's objective

1. Learn how to architect a mobile robotic system

2. Step through a set of fundamental lessons
that shape robot system / algorithm design

BOSS: CMU's entry to urban challenge

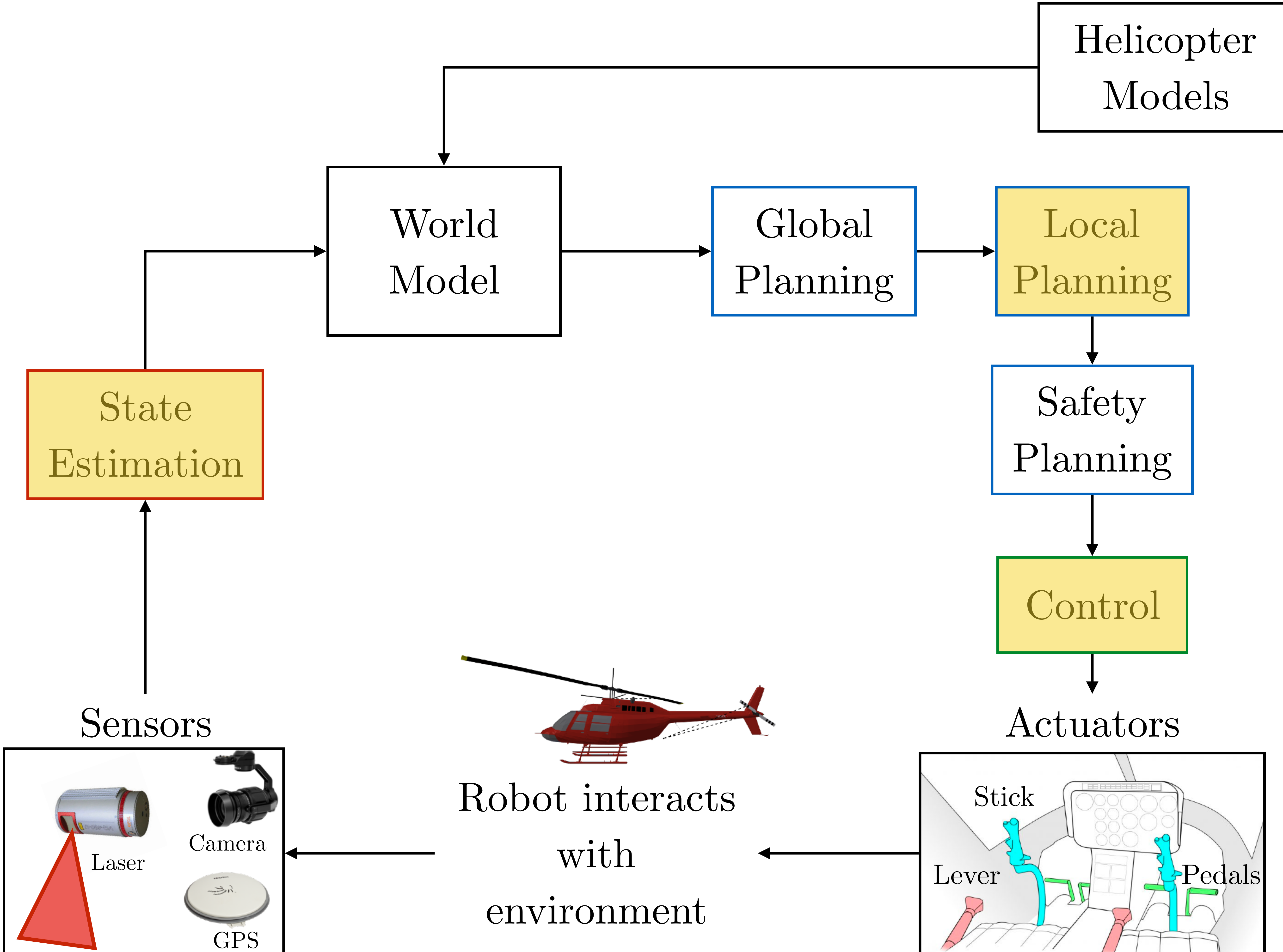
BOSS in action!



1. World Model ✓
2. Car Model ✓
3. State Estimation ✓
4. Global Planner ✓
5. Local Planner ✓
6. Safety Planner ✓
7. Control ✓

Additional challenges: Predict human drivers

Looking ahead...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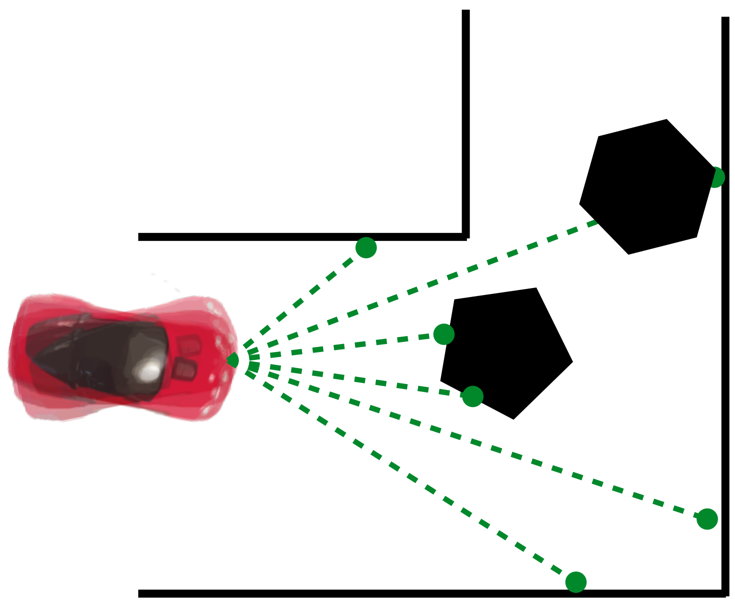
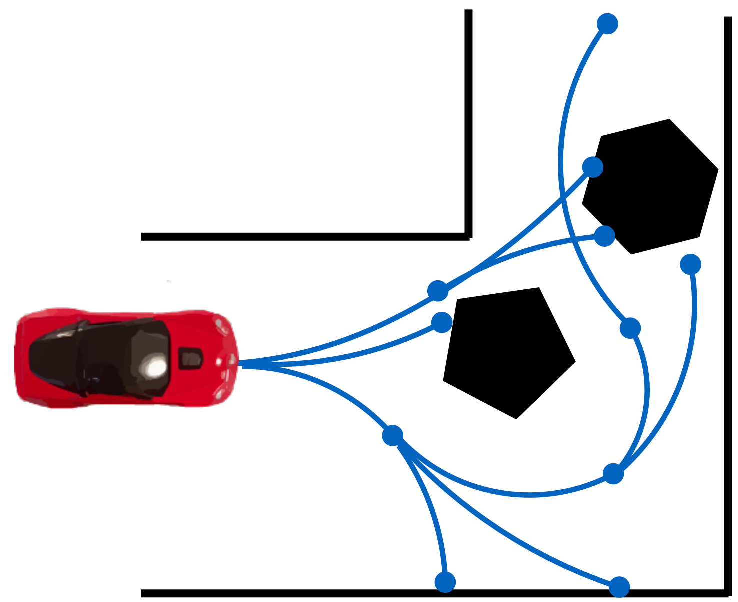
Estimate state



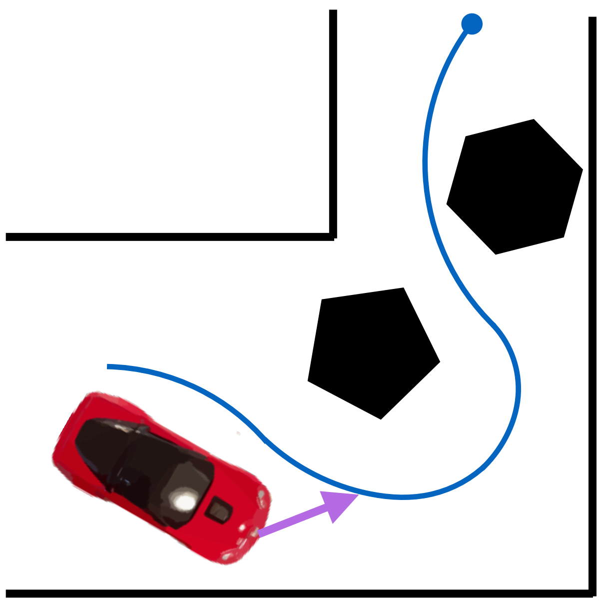
Weeks 2-4

Plan a sequence of motions



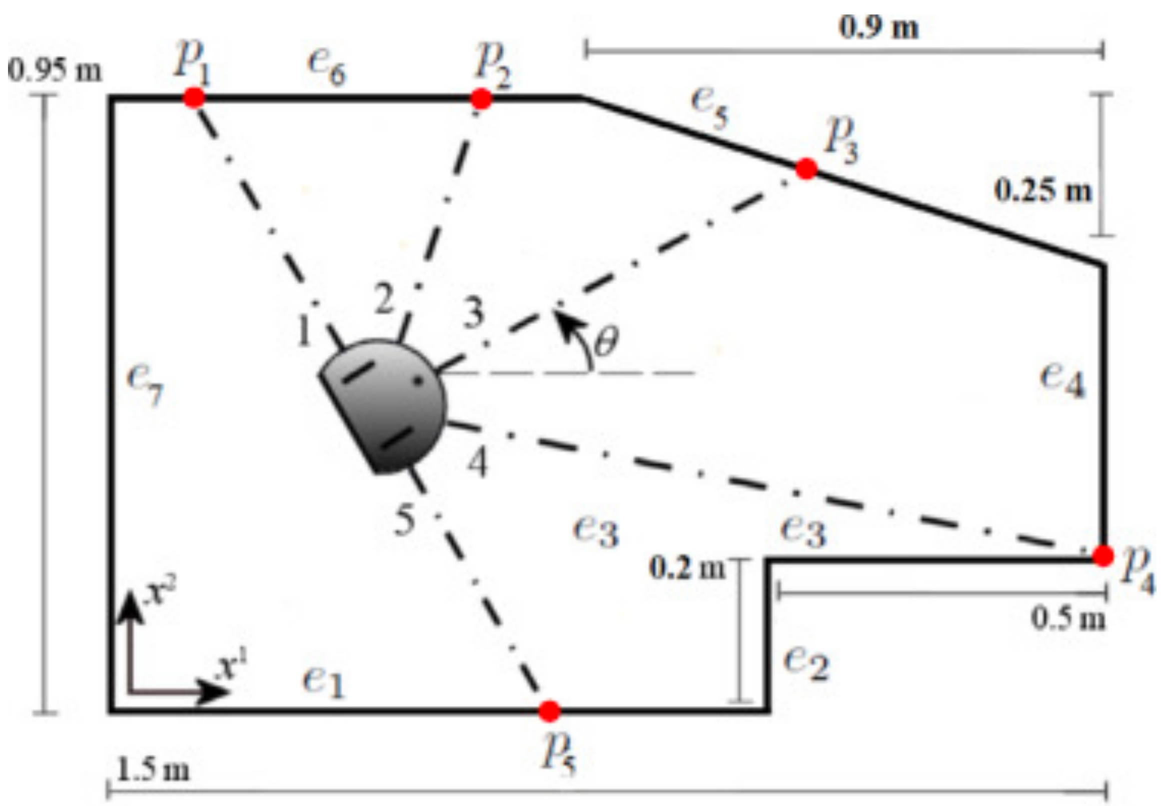
Weeks 7-8

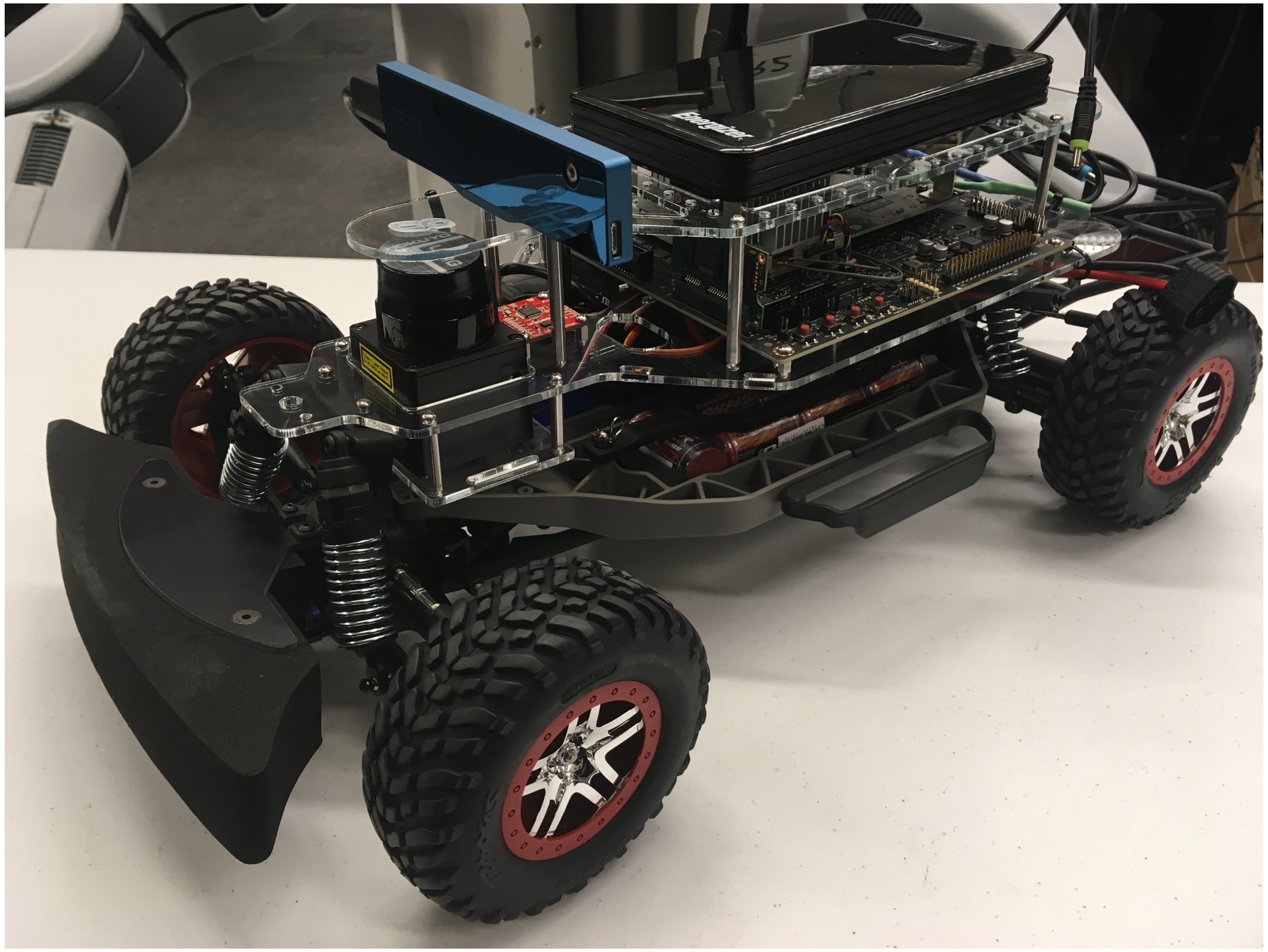
Control robot to follow plan



Weeks 5-6

Challenge for indoor robots: Localization





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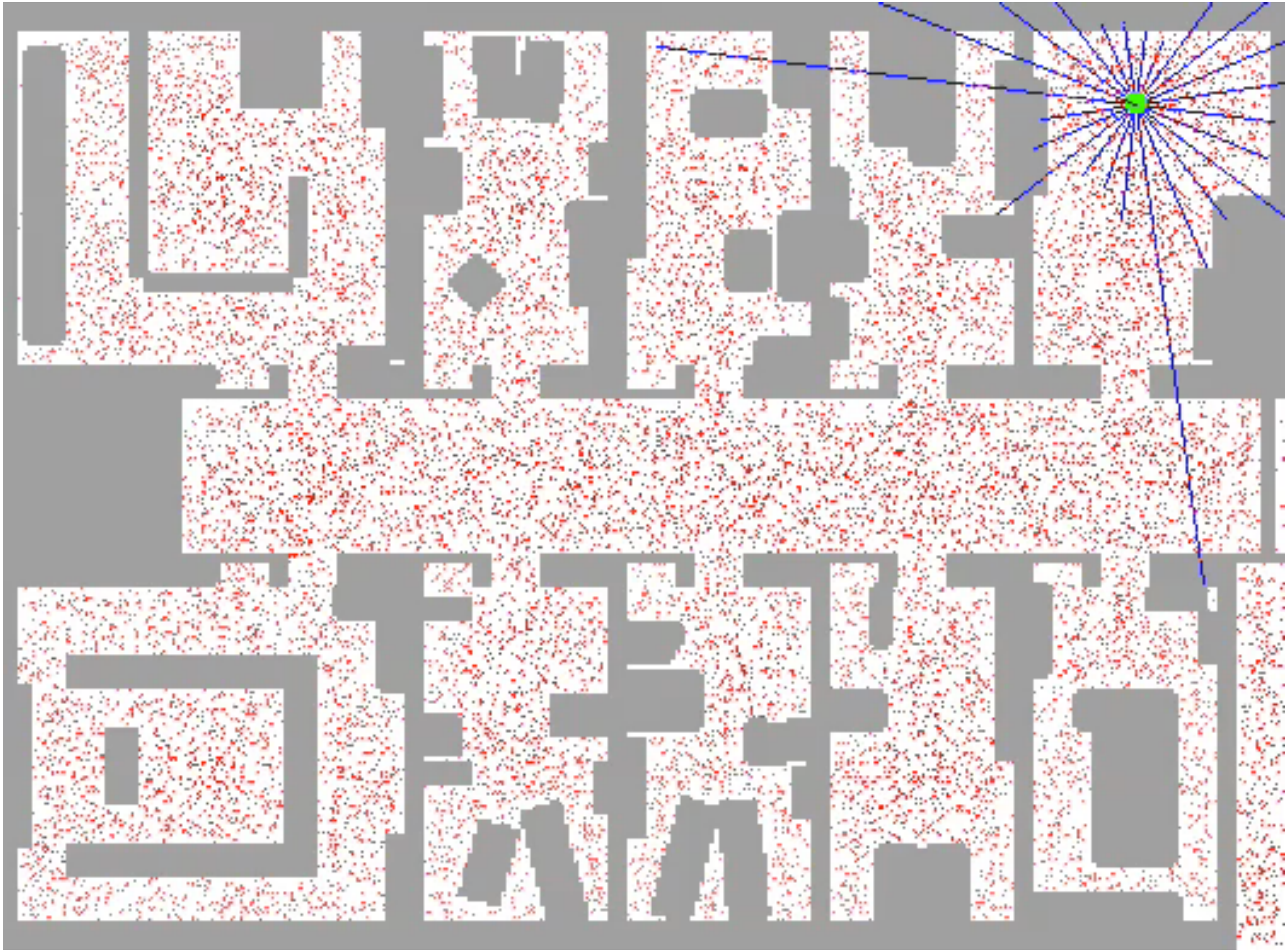

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