

Shared Autonomy: A PLACEHOLDER TITLE

Trung Kien La¹ and Eric Guiffo Kaigom¹

Abstract—... and highlight the main aspects of the Web Framework.

I. INTRODUCTION

Geometric navigation approaches that are for example LiDAR based, are especially limited outdoors [1]. Self-supervised autonomous navigation systems such as BADGR [2], WayFAST [1] or the successor model WayFASTER [3], are therefore used to estimate the traversability with regard to bumps and navigable objects such as tall grass. Even though these neural networks excel in a static environment, they are constrained in a dynamic and busy environment where people, animals or other objects such as cars are moving. Furthermore, not all parameters can be taken into account in these models. Parameters such as battery state of charge (SoC) or engine temperatures of the robot are equally important to ensure successful and safe navigation. It is therefore common for robots to be additionally monitored and controlled by a human operator. For these reasons, it is advantageous for a person with better situational awareness to take back control for a certain action or period of time. In this respect, shared autonomy describes a robotic system that independently adapts its autonomy level to the given environmental factors [4]. To support this physical robot-human interaction (pHRI), intuitive control and monitoring of critical data is required. We therefore provide the robot operator with a web-based interface that reflects the perception of the robot, visualizes its critical data and offers multiple control options. Security aspects such as login and persistent data storage via a database are also integrated. In addition, a concept for shared autonomy with the Husky UGV mobile robotic platform from Clearpath [5] and WayFASTER are presented.

A. Web Framework, Wiederholung aus MMAR24 Paper?

The web framework is used to control and monitor the Husky, which runs on ROS2 Humble and is platform-independent. Due to the web-based approach, all devices with a browser can access the app.

II. PLACEHOLDER

III. RELATED WORK

- Shared Autonomy - Presentation of BADGR and WayFASTER - Web based UI Apps?

¹The authors are with the Department of Computer Science & Engineering, Frankfurt University of Applied Sciences, 60318 Frankfurt am Main, Germany, e-mails: trung.la@stud.fra-uas.de; kaigom@fb2.fra-uas.de

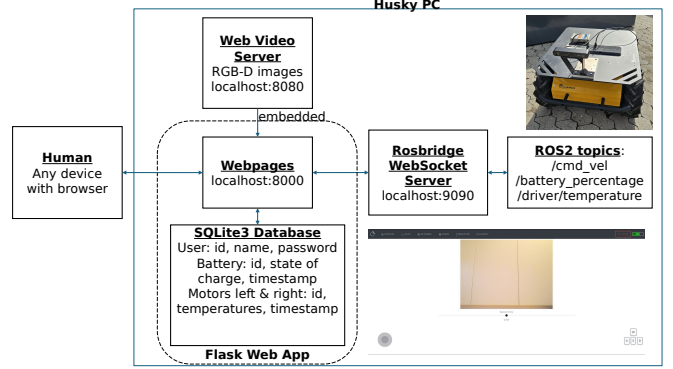


Fig. 1. Backend architecture of the web app with a Screenshot of the frontend

IV. METHODOLOGY AND CONCEPT

We propose a shared autonomy approach of the guidance of a robot such as the Husky UGV from Clearpath. The idea is to let the robot take over initial control through a self-supervised navigation system such as WayFASTER. The kino-dynamic model of a skid-steered Robot, such as the Husky, is given below: [3]

$$x_{k+1} = \begin{bmatrix} p_{x_k} \\ p_{y_k} \\ \theta_k \end{bmatrix} + \begin{bmatrix} \mu(p_{x_k}, p_{y_k}) \cdot \cos(\theta_k) & 0 \\ \mu(p_{x_k}, p_{y_k}) \cdot \sin(\theta_k) & 0 \\ 0 & v(p_{x_k}, p_{y_k}) \end{bmatrix} \begin{bmatrix} v_k \\ \omega_k \end{bmatrix}$$

where x_k is the state vector, p_x and p_y are the coordinates and θ_k is the orientation (heading angle) of the robot. The $\cos(\theta_k)$ and $\sin(\theta_k)$ functions describe the movement in x- and y-Axis depending on the orientation. $\mu(p_x, p_y)$ and $v(p_x, p_y)$ are outputs (traversability coefficients) of the WayFASTER model TravNet and have a value between 1 and 0 respectively. They indicate how well the robot can move across the terrain and are associated with the control inputs v_k and ω_k , which are the linear and angular velocities. In ROS terms these are what a Twist Message contains.

We plan to integrate the transversability coefficients into our web framework. Since these coefficients have a value of 1 for good transversability and 0 for poor transversability, a threshold can be specified. A value of 0 (for both coefficients) would mean that the robot stops. To ensure a more seamless transition from autonomous control to human control, falling below the defined threshold will result in a warning in the web app. This is intended to indicate the human operator to take control within the app. The app is programmed in such a way that human input always has top priority. Specifically, this can be achieved with Husky by

sending control commands (`geometry_msgs/Twist_Message`) in different topics with different priorities [source].

We suggest that you use a text box to insert a graphic (which is ideally a 300 dpi TIFF or EPS file, with all fonts embedded) because, in an document, this method is somewhat more stable than directly inserting a picture.

Fig. 2. Inductance of oscillation winding on amorphous magnetic core versus DC bias magnetic field

V. CONCLUSIONS

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- [5] <https://clearpathrobotics.com/husky-unmanned-ground-vehicle-robot/>