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Robot Mower Mapping and Pathing

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Abstract

The abstract of your report summarises your entire work () in no more than half a page. It should include the context of your work including its main objective, what methods you employed, how you implemented these, what the outcomes were and a final statement as a conclusion. It should not contain acronyms, abbreviations, elements of a literature review (though a statement of related work is permissible if it is crucial to your work) or future work. The abstract should be written when everything else has been written up and the project is finished! is this workng

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1. Introduction

The robot mower is an already existing project developed by previous masters students from the University of East Anglia. Physically, the mower has 2 tracks for movement on the sides of a metal frame, it is controlled by raspberry pi 4 running the Robot Operating System (Macenski et al., 2022). Sensor wise, the robot is equipped with a 4G dongle, lidar and a GPS chip that was upgraded to an RTK chip in this iteration of the project. The existing code base was mostly written in python with very small amounts of C++. Because of this, all of my code will be written in python to slot into existing code without issue.

My contribution to this project this year will be, regarding the overall movement and guidance of the robot. For ease of planning, I have broken this down into 3 sections:

1. Basic map generation
2. complete coverage path planning
3. map generation from an aerial image

These sections are all modular meaning they can be developed, tested and function independently but still easily be integrated together for the final product. The specified use case of the robot will now be to cut golf courses, this is particularly relevant to the aerial map generation section of my work which will likely use a machine learning model and require relevant training data, while the other sections are not concerned with a real world use case as their algorithms will work be able to tweaked for any applicable use case of this robot.

2. Background and Related Work

Another section that is essential and should keep its title as is! Although you could perhaps call it “Literature Review” instead, this is not advisable as at this stage of your project we do not expect an extensive literature review since this was already done in the second formative assignment. The rationale is simply because you will lose valuable pages that could be used better in the next two sections that will cover the preparation and implementation of actual work done. So just provide the context in which your project operates here, and then provide a brief overview of similar work that is directly

relevant to yours. Try to avoid blatant copying and pasting from the formative literature review as it is bound to read awkwardly.

3. System Design

3.1. Map Generation

Map generation is an important part of testing this system, it is important to test on all scenarios that may occur in the real world. For this reason, random or parameter based map generation is very necessary to guarantee success in every environment. As the outputs of this section will mostly be used for testing the path planning algorithm on regions with differing area, number of corners and complexity, no excessive algorithmic complexity is needed. This program should also be able to create n obstacles within the main field, such areas would represent obstructions in the mowers desired path, for example trees or telephone poles in the real world. This means we need a function with 2 parameters:

- K, number of angles in the outer field
- N, number of obstacles within the field, since it would not be sensible to take a parameter for the number of corners for every hole, we can generate them randomly assuming 3-8 corners staying inline with the complexity of the rest of the field without being unreasonably over engineered.

3.1.1. Corners

The number and bydistance between corners could be thought to represnt complexity of a shape. The number of corners in a shape

3.1.2. Obstacles

Obstacles or holes, can be thought to represent real world obstructions for example trees or telephone poles in a real field. Generation of obstacles can be completed using the same function as the outer field generation, simply with different parameters. The algorithm 2 takes 3 parameters, number of points in the shape, an origin point and the range new points. This allows for variable size, positioning and complexity.

3.1.3. Graham Scan

The Graham Scan (?) is an algorithm to find convex hulls, that is from a set of points the outline which contains all inner points. This algorithm does this by sorting the points by their polar angle to the lowest point, since this is always in the hull. There is then further calculations based on the angle between adjacent points to omit inner points from the outline, however for this use case that is not necessary since all points will be vertexes in a field. For this reason, the algorithm used is not strictly a Graham Scan but rather heavily based on the first stage, as shown in 3 Using this algorithm allows for consistent outlining of any set of points with no crossovers or intersections

3.2. Complete Coverage Path Planning

Complete coverage path planning(CCPP) is "the task of determining a path that passes over all points of an area or volume of interest while avoiding obstacles" Zhao and Hwang (2023) For this module, I have used the Fields2Cover library Team (2023), this library is open source. During the course of this project, i contributed to his library, fixing a bug during the build process.

3.2.1. Robot sizing

Robot sizing has 2 important factors, track width - how wide the machine itself is and blade width - how wide the utility object is. For farming equipment the utility object is usually larger than the vehicle, for example a combine harvester's wheels being narrower than blade, however for this project the blade is within the tracks. For this reason the functions will compute slightly differently to its probable intended use case as the tracks are likely to overlap however this should not cause an issue and all outputs should function as needed.

The robot is

3.2.2. Headland Generation

Headlands are the area in which a vehicle turns, think of the rough edges of a crop field. Although this is not strictly needed, the robot could turn

3.2.3. Swath Generation

3.2.4. Route Planning

3.2.5. Path Planning

3.2.6. Cell Decomposition

3.3. Aerial Map Generation

Previously, for the user to plot a custom map or an translate a real world area to the robot, they would have to trace around an image manually. A great increase in usability and user experience would be to automate this labourious and time consuming task. Such a way to do this is with a machine learning model detecting the outlines of the desired area.

3.3.1. Algorithmic Approaches

3.3.2. Machine Learning Approach

3.3.3. Data Set

3.3.4. Training

4. Performance Evaluation

4.1. Map Generation

4.2. Complete Coverage Path Planning

4.3. Aerial Map Generation

5. Conclusion and Future Work

Another essential section that should keep its title as suggested. Briefly discuss your main findings, outcomes, results; what worked and what could have been done differently. Then summarise your work in a concluding statement by comparing your outcomes against the main and sub-objectives and/or MoSCoW requirements (if used) and suggest potential future work that could be done if more time would be available.

References

- Macenski, S., Foote, T., Gerkey, B., Lalancette, C., and Woodall, W. (2022). Robot operating system 2: Design, architecture, and uses in the wild. *Science Robotics*, 7(66):eabm6074.
- Team, F. (2023). Fields2cover: Mission planning for agricultural vehicles. <https://fields2cover.github.io/>.
- Zhao, S. and Hwang, S.-H. (2023). Complete coverage path planning scheme for autonomous navigation ros-based robots. *ICT Express*, 9(3):361–366.

A. Map Generation

Algorithm 1 Point Class Definition

```
1: procedure CLASS POINT
2:    $X \leftarrow -1$                                 ▷ X-coordinate initialized to -1
3:    $Y \leftarrow -1$                                 ▷ Y-coordinate initialized to -1
4:    $angle \leftarrow -10$                             ▷ Angle initialized to -10
5:   procedure CONSTRUCTOR( $x, y$ )
6:      $this.X \leftarrow x$ 
7:      $this.Y \leftarrow y$ 
8:      $this.angle \leftarrow -10$                     ▷ Default angle value
9:   end procedure
10: end procedure
```

Algorithm 2 Generate random points

```
1: function GENPOINTS( $num, P, size$ )
2:    $points \leftarrow []$ 
3:   for  $i \leftarrow 0$  to  $num - 1$  do
4:      $randX \leftarrow \text{random\_integer}(P.X + 1, P.X + size)$ 
5:      $randY \leftarrow \text{random\_integer}(P.Y + 1, P.Y + size)$ 
6:      $points.append(\text{Point}(randX, randY))$ 
7:   end for
8:   return  $points$ 
9: end function
```

Algorithm 3 Sort points by polar angle to origin

```
1: function SORTPOINTS(points, origin)
2:   hull  $\leftarrow$  [origin]
3:   Sort points by Y-coordinate
4:   for i  $\leftarrow$  0 to length(points) – 1 do
5:     points[i].angle  $\leftarrow$  CALCANGLE(origin, points[i])
6:   end for
7:   Sort points by angle
8:   Append points to hull
9:   return hull
10: end function
```

Algorithm 4 Main function

```
1: function MAIN
2:   hull  $\leftarrow$  []
3:   origin  $\leftarrow$  Point(20,20)
4:   field  $\leftarrow$  GENPOINTS(20, origin, 400)
5:   hull.append(SORTPOINTS(field, origin))
6: end function
```

Algorithm 5 Main function with holes in shape

```
1: procedure MAIN
2:   hull  $\leftarrow$  empty list
3:   origin  $\leftarrow$  Point(20,20)
4:   field  $\leftarrow$  GenPoints(20, origin, 400)
5:   add SortPoints(field, origin) to hull
6:   hole1Base  $\leftarrow$  Point(100,100)
7:   hole1Points  $\leftarrow$  GenPoints(5, hole1Base, 50)
8:   add SortPoints(hole1Points, hole1Base) to hull
9:   hole2Base  $\leftarrow$  Point(150,50)
10:  hole2Points  $\leftarrow$  GenPoints(3, hole2Base, 30)
11:  add SortPoints(hole2Points, hole2Base) to hull
12: end procedure
```
