

Lab 3: Motion Planning with a 6-DOF Manipulator

CSCI 545

Team Roomba

Brandon Rathburn, Devayani S Krishnan, Lakshya Ahuja, Bilin Pattasseril, Rut Patel

(72 points total)

1 Main Implementation

In this lab assignment, you will implement the RRT algorithm for a 6-DOF robotic manipulator. To perform the assignment, you will need to have installed the AIKIDO infrastructure. We provide for you the file **adarrt.py**, which contains several methods you will fill in. During development, you will run your code in simulation with -

```
$ python adarrt.py --sim
```

The python file contains the following classes and functions:

- AdaRRT: This is the main class. It initializes the start and goal node, the number of iterations, the step_size δ when extending a node in the tree, the desired goal precision ϵ and the joint limits of the robot. It also includes information about the environment, which includes a table, a soda can that we want to grasp, the robot and a set of constraints that check for collisions. This implementation will be very similar to the RRT you built in HW4, with a few modifications discussed below.
- AdaRRT.Node: A Node object should contain a copy of the state, a pointer to the parent node in the tree, and a list of pointers to all its child nodes in the tree. A state in the provided code is a 6D np.array that contains the robot's configuration.
- main: this function specifies the start and goal configurations, sets up the RRT planner and computes a path. It then calls the AIKIDO function compute_joint_space_path, which generates a trajectory for the robot to follow.

Steps to complete the lab:

1. **Implement an RRT algorithm** by filling in the code in the provided file. For starting configuration q_S and goal configuration q_G , and parameters ϵ and δ use:

$$\begin{aligned} q_S &= [-1.5, 3.22, 1.23, -2.19, 1.8, 1.2] \\ q_G &= [-1.72, 4.44, 2.02, -2.04, 2.66, 1.39] \\ \delta &= 0.25 \\ \epsilon &= 1.0 \end{aligned}$$

Make sure you have `roscore` running before starting your RRT!

2. **Visualize the trajectory in rviz.** First, execute your AdaRRT implementation, but don't execute the trajectory. Then, open rviz from the command line using `rosrun rviz rviz`. In the bottom left module, click the "Add" button and navigate to the "By Topic" tab. You should see a `InteractiveMarkers` topic under `/dart_markers`. Add the topic before executing your trajectory generated by AdaRRT.

- (a) Accept the GitHub Classroom invitation
(GitHub Classroom)
- (b) Download the docker image (we will not use the same docker images as in Lab1 and Lab2).

If use **ARM-64** architecture:

- If use Python2:
Download and directly load this docker image:
(Google Drive)
`docker load -i cs545-lab3-melodic-arm64.tar.`
- If use Python3:
Download and directly load this docker image:
(Google Drive)
`docker load -i cs545-lab3-noetic-arm64.tar.`

If use **X86-64** architecture:

- If use Python2:
Download and directly load this docker image:
(Google Drive)
`docker load -i cs545-lab3-melodic-x86-64.tar.`

If build your own Docker image:

- Follow this instruction:
(Google Drive)

- (c) Build the provided workspace (already in the docker image, you can skip this step): (Google Drive)

Unzip it to your home directory. Before running the assignment codes, make sure you have run source /ros_ws/devel/setup.bash in the same terminal as your lab script. Remove build, devel, and log from your ros_ws and rebuild the workspace by running

```
catkin_make_isolated -j4 # Use 4 parallel jobs
```

- (d) Create Docker Container

- (e) Run lab3 code

If use **ARM-64** architecture:

- Terminal 1: Run roscore

Run roscore

```
source /opt/ros/melodic/setup.bash  
roscore
```

- Terminal 2: Run your script

Put your script in '/ros_ws/src/lab3/adarrrt.py'.

Run your script:

```
source ~/ros_ws-devel_isolated/libada/setup.bash  
export ROS_PACKAGE_PATH=$ROS_PACKAGE_PATH:/root/ros_ws/src/libada  
python ~/ros_ws/src/lab3/adarrrt.py --sim
```

- Terminal 3: Run Rviz visualization

```
source /opt/ros/melodic/setup.bash  
source ~/ros_ws-devel_isolated/libada/setup.bash  
export ROS_PACKAGE_PATH=$ROS_PACKAGE_PATH:/root/ros_ws/src/libada  
rosrun rviz rviz
```

If use **X86-64** architecture:

- Terminal 1: Run roscore

Run roscore

```
source ~/.bashrc  
roscore
```

- Terminal 2: Run your script

Put your script in ~/lab3/adarrrt.py.

Run your script:

```
source ~/.bashrc  
python ~/lab3/adarrrt.py --sim
```

- Terminal 3: Run Rviz visualization

```
source ~/.bashrc  
rosrun rviz rviz
```

3. **(40 points)** Use an off-shelf screen capture software (e.g., <https://itsfoss.com/kazam-screen-recorder/>) to **record a video** of the trajectory. Include the video in the root of your GitHub repo as a file named `question-3.mp4`.
4. **(10 points)** The RRT trajectory is typically jerky. Typical planners use shortcuttering algorithms to make the path smoother. **Replace the function** `ada.compute_joint_space_path` with `ada.compute_smooth_joint_space_path`. Capture the new trajectory with two videos – one showing the default isometric view, and another showing the top view. Include the videos in the root of your GitHub repo as files named `question-4-default.mp4` and `question-4-top.mp4`.
5. **(10 points)** The goal precision ϵ of 1.0 in the previous question is too large. In order to avoid collisions, we need to improve the precision. However, this dramatically increases the time to compute a solution. To improve computation, **add a method** `_get_random_sample_near_goal` that generates a sample around the goal within a distance of 0.05 along each axis of the search space. Then, change the `build` method so that it calls `_get_random_sample_near_goal` with probability 0.2 and `_get_random_sample` with probability 0.8. Reduce ϵ to 0.2.

Write down your observations in the PDF file. Also capture the new trajectory with two videos – one showing the default isometric view, and another showing the top view. Include the videos in the root of your GitHub repo as files named `question-5-default.mp4` and `question-5-top.mp4`.

Question 5 Observations: While the distances traveled between the robotic arms are quite similar, the notable difference is the Yaw value, comparing Question 4's Yaw value of 6.24 to Question 5's Yaw value of 0.08. While the end effector in both paths reach the target, the path using the algorithm in question 4 (without `_get_random_sample_near_goal`) appears to be more "awkward". The path in question 5 travels CCW to the target, which seems more "natural" to the human eye, wrapping around the outside of the cylinder. The RRT trajectory in question 4 travels more in the x direction (in the positive and negative direction), which adds to the bulkiness of the path.

6. **(10 points)** Explain why it is not a good idea to call `_get_random_sample_near_goal` with probability 1.0. Also present an example where this could be problematic. Write your answer in the PDF.

Question 6: If we call `_get_random_sample_near_goal` with probability 1.0, it is impossible (there is 0.0 probability) for a sample to be collected outside of this 0.05

distance along each axis of the search space, which itself comes with several issues. When the step size is too small (and/or the configuration space is too large), it is not possible to connect any new nodes to the initial position, rendering it impossible to reach the target destination. The end effector will be stuck in its original location. Even if this is possible given an ideal step size, the number of possible trajectories will be reduced, which would mean that obstacles are more of a hindrance in this scenario. Not only this, but all trajectories will be jerkier than a typical RRT trajectory.

In-person lab: Once you are confident in your simulation results, you are ready to run it on the real robot. This can be done on the lab workstations with -

```
$ python adarrt.py --real
```

Refer to Piazza for more instructions on scheduling time in the lab.

2 Additional Questions

As a very rough guideline, we anticipate that for most teams, the answers to each question below will be approximately one paragraph long (or about 4-5 bullet points). However, your answers may be shorter or longer if you believe it is necessary.

2.1 Resources Consulted

Question: (1 points) Please describe which resources you used while working on the assignment. You do not need to cite anything directly part of the class (e.g., a lecture, the CSCI 545 course staff, or the readings from a particular lecture). Some examples of things that could be applicable to cite here are: (1) did you get help from a classmate *not* part of your lab team; (2) did you use resources like Wikipedia, StackExchange, or Google Bard in any capacity; (3) did you use someone's code (again, for someone *not* part of your lab team)? When you write your answers, explain not only the resources you used but HOW you used them. If you believe your team did not use anything worth citing, *you must still state that in your answer* to get full credit.

Resources Consulted: To better understand and visualize the concept of RRT, this YouTube video (<https://www.youtube.com/watch?v=OXikozpLFGo>) served as a guide to the implementation of the RRT algorithm in step 1. Outside of this, no other resources were consulted.

2.2 Team Contributions

Question: (1 points) Please describe below the contributions for each team member to the overall lab. *Furthermore, state a (rough) percentage contribution for each member.* For example, in a team of 4, did each team member contribute roughly 25% to the overall effort for the project?

Team Contributions: Everyone contributed 20% to the overall effort for the project. Since not everyone was able to make it to the in-person lab due to time constraints and other commitments, those members picked up extra slack where needed, whether it was with completing extra parts of the code or the report.