```
% =========
% ass3_q2.m
% =========
%
% This assignment will introduce you to the idea of first building an
% occupancy grid then using that grid to estimate a robot's motion using a
% particle filter.
%
% There are three questions to complete (5 marks each):
%
%    Question 1: see ass3_q1.m
%    Question 2: code particle filter to localize from known map
%
% Fill in the required sections of this script with your code, run it to
% generate the requested plot/movie, then paste the plots into a short report
% that includes a few comments about what you've observed.  Append your
% version of this script to the report.  Hand in the report as a PDF file
% and the two resulting AVI files from Questions 1 and 2.
%
% requires: basic Matlab, 'gazebo.mat', 'occmap.mat'
%
% T D Barfoot, January 2016
%
clear all;

% set random seed for repeatability
rng(1);

% ==========================
% load the dataset from file
% ==========================
%
%    ground truth poses: t_true x_true y_true theta_true
% odometry measurements: t_odom v_odom omega_odom
%           laser scans: t_laser y_laser
%    laser range limits: r_min_laser r_max_laser
%    laser angle limits: phi_min_laser phi_max_laser
%
load gazebo.mat;

% =================================================
% load the occupancy map from question 1 from file
% =================================================
%  ogres: resolution of occ grid
% ogxmin: minimum x value
% ogxmax: maximum x value
% ogymin: minimum y value
% ogymax: maximum y value
%   ognx: number of cells in x direction
%   ogny: number of cells in y direction
%   oglo: occupancy grid in log-odds format
%    ogp: occupancy grid in probability format
```

```
load occmap.mat;

% =========================================================================
% Question 2: localization from an occupancy grid map using particle filter
% =========================================================================
%
% Write a particle filter localization algorithm to localize from the laser
% rangefinder readings, wheel odometry, and the occupancy grid map you
% built in Question 1.  We will only use two laser scan lines at the
% extreme left and right of the field of view, to demonstrate that the
% algorithm does not need a lot of information to localize fairly well.  To
% make the problem harder, the below lines add noise to the wheel odometry
% and to the laser scans.  You can watch the movie "ass2_q2_soln.mp4" to
% see what the results should look like.  The plot "ass2_q2_soln.png" shows
% the errors in the estimates produced by wheel odometry alone and by the
% particle filter look like as compared to ground truth; we can see that
% the errors are much lower when we use the particle filter.

% interpolate the noise-free ground-truth at the laser timestamps
numodom = size(t_odom,1);
t_interp = linspace(t_true(1),t_true(numodom),numodom);
x_interp = interp1(t_interp,x_true,t_laser);
y_interp = interp1(t_interp,y_true,t_laser);
theta_interp = interp1(t_interp,theta_true,t_laser);
omega_interp = interp1(t_interp,omega_odom,t_laser);

% interpolate the wheel odometry at the laser timestamps and
% add noise to measurements (yes, on purpose to see effect)
v_interp = interp1(t_interp,v_odom,t_laser) + 0.2*randn(size(t_laser,1),1);
omega_interp = interp1(t_interp,omega_odom,t_laser) +
 0.04*randn(size(t_laser,1),1);

% add noise to the laser range measurements (yes, on purpose to see effect)
% and precompute some quantities useful to the laser
y_laser = y_laser + 0.1*randn(size(y_laser));
npoints = size(y_laser,2);
angles = linspace(phi_min_laser, phi_max_laser,npoints);
dx = ogres*cos(angles);
dy = ogres*sin(angles);
y_laser_max = 5;   % don't use laser measurements beyond this distance

% particle filter tuning parameters (yours may be different)
nparticles = 200;       % number of particles
v_noise = 0.2;          % noise on longitudinal speed for propagating particle
u_noise = 0.2;          % noise on lateral speed for propagating particle
omega_noise = 0.04;     % noise on rotational speed for propagating particle
laser_var = 0.5^2;      % variance on laser range distribution
w_gain = 10*sqrt( 2 * pi * laser_var );     % gain on particle weight

% generate an initial cloud of particles
x_particle = x_true(1) + 0.5*randn(nparticles,1);
y_particle = y_true(1) + 0.3*randn(nparticles,1);
theta_particle = theta_true(1) + 0.1*randn(nparticles,1);
```

```
% compute a wheel odometry only estimate for comparison to particle
% filter
x_odom_only = x_true(1);
y_odom_only = y_true(1);
theta_odom_only = theta_true(1);

% error variables for final error plots - set the errors to zero at the start
pf_err(1) = 0;
wo_err(1) = 0;

% set up the plotting/movie recording
vid = VideoWriter('ass2_q2.avi');
open(vid);
figure(2);
clf;
hold on;
pcolor(ogp);
set(plot( (x_particle-ogxmin)/ogres, (y_particle-ogymin)/ogres, 'g.'
 ),'MarkerSize',10,'Color',[0 0.6 0]);
set(plot( (x_odom_only-ogxmin)/ogres, (y_odom_only-ogymin)/ogres, 'r.'
 ),'MarkerSize',20);
x = (x_interp(1)-ogxmin)/ogres;
y = (y_interp(1)-ogymin)/ogres;
th = theta_interp(1);
r = 0.15/ogres;
set(rectangle( 'Position', [x-r y-r 2*r 2*r], 'Curvature', [1
 1]),'LineWidth',2,'FaceColor',[0.35 0.35 0.75]);
set(plot([x x+r*cos(th)]', [y y+r*sin(th)]', 'k-'),'LineWidth',2);
set(plot( (mean(x_particle)-ogxmin)/ogres, (mean(y_particle)-ogymin)/
ogres, 'g.' ),'MarkerSize',20);
colormap(1-gray);
shading('flat');
axis equal;
axis off;
M = getframe;
writeVideo(vid,M);

% loop over laser scans
for i=2:size(t_laser,1)

    % update the wheel-odometry-only algorithm
    dt = t_laser(i) - t_laser(i-1);
    v = v_interp(i);
    omega = omega_interp(i);
    x_odom_only = x_odom_only + dt*v*cos( theta_odom_only );
    y_odom_only = y_odom_only + dt*v*sin( theta_odom_only );
    phi = theta_odom_only + dt*omega;
    while phi > pi
        phi = phi - 2*pi;
    end
    while phi < -pi
        phi = phi + 2*pi;
    end
    theta_odom_only = phi;
```

```
    % loop over the particles
    for n=1:nparticles

        % propagate the particle forward in time using wheel odometry
        % (remember to add some unique noise to each particle so they
        % spread out over time)
        v = v_interp(i) + v_noise*randn(1);
        u = u_noise*randn(1);
        omega = omega_interp(i) + omega_noise*randn(1);
        x_particle(n) = x_particle(n) + dt*(v*cos( theta_particle(n) ) -
u*sin( theta_particle(n) ));
        y_particle(n) = y_particle(n) + dt*(v*sin( theta_particle(n) ) +
u*cos( theta_particle(n) ));
        phi = theta_particle(n) + dt*omega;
        while phi > pi
            phi = phi - 2*pi;
        end
        while phi < -pi
            phi = phi + 2*pi;
        end
        theta_particle(n) = phi;

        % pose of particle in initial frame
        T = [cos(theta_particle(n)) -sin(theta_particle(n)) x_particle(n); ...
             sin(theta_particle(n))  cos(theta_particle(n)) y_particle(n); ...
                    0                      0                  1];

        % compute the weight for each particle using only 2 laser rays
        % (right=beam 1 and left=beam 640)
        w_particle(n) = 1.0;
        for beam=1:2

            % we will only use the first and last laser ray for
            % localization
            if beam==1  % rightmost beam
                j = 1;
            elseif beam==2  % leftmost beam
                j = 640;
            end

            % ------insert your particle filter weight calculation here ------

            if ~isnan(y_laser(i,j)) && y_laser(i,j) < y_laser_max

                row_pos = max(1,round((y_particle(n)-ogymin)/ogres));
                col_pos = max(1,round((x_particle(n)-ogxmin)/ogres));
                threshold = 0.5;
                %get predicted range: y_laser_pred
                y_laser_pred = predict_laser_range(row_pos, col_pos, ...
                    theta_particle(n), angles(j), ogp, ogres, threshold);

                % calculate weight using gaussian pdf function
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```
                w_particle(n) = w_particle(n)*w_gain*normpdf(y_laser(i,
j), ...
                    y_laser_pred, sqrt(laser_var));

            end


            % ------end of your particle filter weight calculation-------
        end

    end

    % resample the particles using Madow systematic resampling
    w_bounds = cumsum(w_particle)/sum(w_particle);
    w_target = rand(1);
    j = 1;
    for n=1:nparticles
       while w_bounds(j) < w_target
           j = mod(j,nparticles) + 1;
       end
       x_particle_new(n) = x_particle(j);
       y_particle_new(n) = y_particle(j);
       theta_particle_new(n) = theta_particle(j);
       w_target = w_target + 1/nparticles;
       if w_target > 1
           w_target = w_target - 1.0;
           j = 1;
       end
    end
    x_particle = x_particle_new;
    y_particle = y_particle_new;
    theta_particle = theta_particle_new;

    % save the translational error for later plotting
    pf_err(i) = sqrt( (mean(x_particle) - x_interp(i))^2 + (mean(y_particle) -
y_interp(i))^2 );
    wo_err(i) = sqrt( (x_odom_only - x_interp(i))^2 + (y_odom_only -
y_interp(i))^2 );

    % plotting
    figure(2);
    clf;
    hold on;
    pcolor(ogp);
    set(plot( (x_particle-ogxmin)/ogres, (y_particle-ogymin)/ogres, 'g.'
),'MarkerSize',10,'Color',[0 0.6 0]);
    set(plot( (x_odom_only-ogxmin)/ogres, (y_odom_only-ogymin)/ogres, 'r.'
),'MarkerSize',20);
    x = (x_interp(i)-ogxmin)/ogres;
    y = (y_interp(i)-ogymin)/ogres;
    th = theta_interp(i);
    if ~isnan(y_laser(i,1)) & y_laser(i,1) <= y_laser_max
       set(plot([x x+y_laser(i,1)/ogres*cos(th+angles(1))]', [y y
+y_laser(i,1)/ogres*sin(th+angles(1))]', 'm-'),'LineWidth',1);
```

```
    end
    if ~isnan(y_laser(i,640)) & y_laser(i,640) <= y_laser_max
       set(plot([x x+y_laser(i,640)/ogres*cos(th+angles(640))]', [y y
+y_laser(i,640)/ogres*sin(th+angles(640))]', 'm-'),'LineWidth',1);
    end
    r = 0.15/ogres;
    set(rectangle( 'Position', [x-r y-r 2*r 2*r], 'Curvature', [1
 1]),'LineWidth',2,'FaceColor',[0.35 0.35 0.75]);
    set(plot([x x+r*cos(th)]', [y y+r*sin(th)]', 'k-'),'LineWidth',2);
    set(plot( (mean(x_particle)-ogxmin)/ogres, (mean(y_particle)-ogymin)/
ogres, 'g.' ),'MarkerSize',20);
    colormap(1-gray);
    shading('flat');
    axis equal;
    axis off;

    % save the video frame
    M = getframe;
    writeVideo(vid,M);

    pause(0.01);

end

close(vid);

% final error plots
figure(3);
clf;
hold on;
plot( t_laser, pf_err, 'g-' );
plot( t_laser, wo_err, 'r-' );
xlabel('t [s]');
ylabel('error [m]');
legend('particle filter', 'odom', 'Location', 'NorthWest');
title('error (estimate-true)');
print -dpng ass2_q2.png

% returns the expected laser measurement given the particle's
% position and map
function y_exp = predict_laser_range(row, col, theta, beam_angle, map, ogres,
 thresh)

    new_angle = atan2(sin(theta+beam_angle), cos(theta+beam_angle));
    incr  = 0;
    r_p = row;
    c_p = col;




    % angle is between -pi/4 and pi/4
    if -pi/4<=new_angle && new_angle<=pi/4
```

```
        c_inc = 1;
        r_inc = tan(new_angle);
        a = cos(new_angle);

    % angle is between -3pi/4 and 3pi/4
    elseif 3*pi/4<=new_angle || new_angle<=-3*pi/4
        c_inc = -1;
        r_inc = -tan(new_angle);
        a = cos(new_angle);

    % angle is between pi/4 and 3pi/4
    elseif pi/4<new_angle && new_angle<3*pi/4
        c_inc = 1/tan(new_angle);
        r_inc = 1;
        a = sin(new_angle);


    % angle is between -pi/4 and -3pi/4
    else
        c_inc = -1/tan(new_angle);
        r_inc = -1;
        a = sin(new_angle);

    end

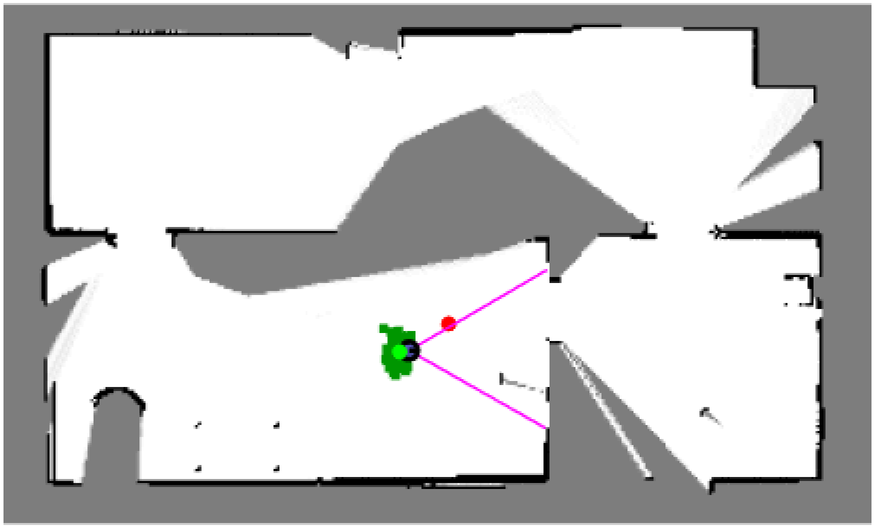


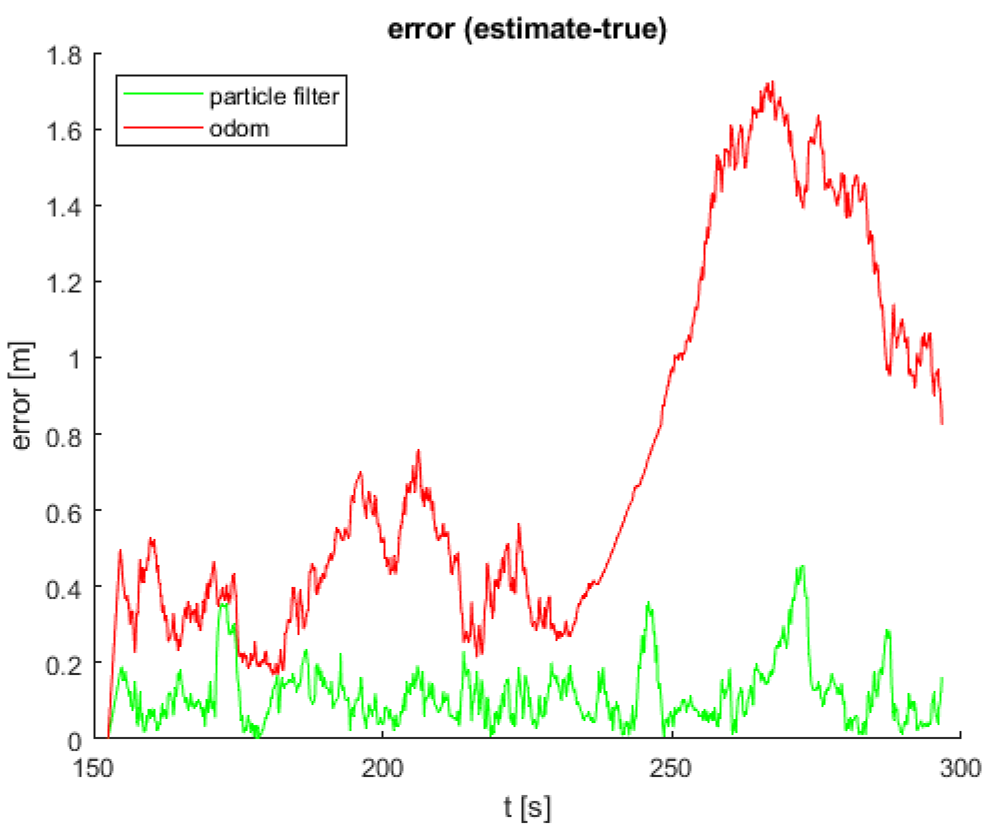
    [row_bound, col_bound] = size(map);

    while r_p > 0 && c_p>0 && r_p<=row_bound && c_p<=col_bound && map(r_p,
 c_p) < thresh
        incr = incr +1;
        r_p = row + round(incr * r_inc);
        c_p = col + round(incr * c_inc);
    end

    y_exp = abs((incr/a)*ogres);


end
```




error (estimate-true)
particle filter
odom
error [m]
t [s]
0
0.2
0.4
0.6
0.8
1
1.2
1.4
1.6
1.8
150
200
250
300

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