COEX-1

Cooperative Explorer

Aurélien Werenne
Advisor: Prof. B. Boigelot

University of Liège

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Overview

General

Objective

The goal of the robot is to map an unknown environment in a centralized multi-agent setting.

The main features of the robots are:

- Following a black line
- Computing the travelled distance
- Detecting, classifying and handling intersections
- Avoiding obstacles
- Communicating with a central unit

- Arduino Nano
- Reflectance sensor array
- Sharp sensor
- Magnetic encoders
- Pololu micro metal gearmotor
- L298 dual H-bridge
- NiMH Battery 7.2V
- HC-06 Bluetooth module
- ...

Photos (2 per slides, 4-5 slides)

- List of variables used in equations with small explanations

Explain flow test.

Plot.

Conclusion.

Bypass capacitor.

Explain flow test.

Plot.

Conclusion.

The line sensors are fixed vertically well above the given recommendations, such that the robot has place to climb hills. This decision made the line sensor particularly sensitive to ambient light interferences. Thus a shield had to be constructed.

Photo.

Explain sender-receiver distortion.

Plots.

Conclusion.

Voltage divider.

Components

Quadrature encoders (1/2)

$$w_L = 2\pi f_L \qquad \text{with} \qquad f_L = \frac{n_L}{\frac{NG_b}{2}\Delta t}$$

$$v = \frac{v_L + v_R}{2} = \frac{R(w_L + w_R)}{2}$$

Remark why divide by 2 for counting. because only 2 pin interrupts.

Plot.

Conclusion. hysterisis. need for regulation.

Instabilities, fixed by software however + ceramic capacitor.

Use of classical PID controller.

$$o_n \leftarrow K_p e_n + K_d \frac{e_n - e_{n-1}}{\Delta t_{n-1:n}} + K_e \sum_{i=0}^{n} e_i \Delta t_{n-1:n}$$

with the following two precautions called respectively anti-windup and anti-derivative kick:

$$o_n = \begin{cases} max & \text{if } o_n > max \\ min & \text{if } o_n < min \\ o_n & \text{otherwise.} \end{cases} \qquad \text{and} \qquad K_d = \begin{cases} 0 & \text{if } n < T \\ K_d & \text{otherwise.} \end{cases}$$

Control

Speed & direction

$$\begin{cases} \alpha = o_{direction}(e(\frac{v_L - v_R}{2})) \\ \beta = o_{speed}(e(\frac{v_L + v_R}{2})) \end{cases} \Rightarrow \begin{cases} pwm_L = \beta + \alpha \\ pwm_R = \beta - \alpha \end{cases}$$

Recall plot of sensor.

$$e(\frac{v_L - v_R}{2}) = err_{line} \in [-2500; 2500]$$

Explain perturbation plot.

Perturbation plot.

Conclusion. break out angle. Agressive enough such that not seen as intersection.

Reason. Target and progress speed.

$$v_{n+1} \leftarrow v_n + A\,\Delta t_{n:n+1}$$

$$\begin{aligned}
&\Leftrightarrow \int_0^T a(t) = \int_0^T a'(t) \\
&\Leftrightarrow A\,T = \underbrace{d\,B}_{triangles} + \underbrace{(T-2d)B}_{rectangle}
\end{aligned}$$

We introduce the parameter $\psi = \frac{d}{T}$ such that

$$B = \frac{A}{1-\psi}$$

$$v_{n+1} \leftarrow v_n + \int_n^{n+1} a'(t) = v_n + \int_0^{n+1} a'(t) - \int_0^n a'(t)$$

Diagrams.

Reason.

Target and progress speed.

Equations.

Diagrams.

Explain plot.

PID plot.

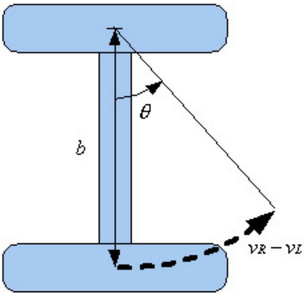
Conclusion. Room for fine-tuning.

Explain forward.

equation

Modelize.

Source of image



Turning θ equation.

PID.

To explore an unknown environment structured as a maze it needs to be able to:

- Compute the distance travelled since the last intersection
- Detect an intersection
- Turn to the desired intersection

First method: Simple equation - explain without mathematics.

Second method: Upperbound of error can be reduced due to relation with distance.

plot relationship

Plot comparison with error bars of two methods on test set.

Conclusion.

Explain we could try to quantify uncertainty and above certain threshold not accept it.

$$MSE = \sum_{i=0}^{N} err_{line}^2$$

One plot

Explain simpler choice is to discretize from second method discretization.

Remard 7.5-12.5 ....

Plot discretization on test set.

Example of resulting big map. Explain annotation

Map.

Explain problem of naive approach.

Solution: majority vote system.

Explain classification.

Figures of 8 types.

Problem with naive approach.

Solution + plot + equation.

Explain plot.

Plot to verify results.

Conclusion.

Advantage.

Diagram.

Link to code.

Pseudocode.