CS 188 Robotics Week 1

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Robots

What is a robot

- "A robot is defined as intelligence embodied in an engineered construct, with the ability to process information, sense, plan, and move within or substantially alter its working environment.
- Here intelligence includes a broad class of methods that enable a robot to solve problems or to make contextually appropriate decisions and act upon them.
- Therefore, the following count as robots:
  - Roombas
  - Automatic sliding doors (which may use facial recognition, or just a simple proximity sensor)

Robotics

- Robots must be able to move (physically), or interact with its environment in some way. There are three sectors of robotics:
  - **Kinematics**: the study of motion *without* considering forces or torques
  - **Dynamics**: the study of motion considering the forces and torques that caused it.
  - **Control**: how to execute the desired motion
  - **Perception**: how to understand the world using sensors
  - **Planning**: how to reach a goal

Course Objectives

- Develop a foundational understanding of *kinematics, dynamics, and control* for modeling and managing robotic motion
- Become familiar with *sensors and pereption algorithms* to interpret environmental data for robotic decision-making
- Understand principles of *state estimation*, as well as *task and motion planning*, to enable reliable and efficient robot behaviors.
- Explore basic ideas of *AI in robotics*, including imitation learning and human-robot interactions, for advanced autonomous capabilities.
- Gain *hands-on experience* in simulation tools to design, test, and refine robitic systems in a virtual environment
- Reflect on the *ethical implications* of robotics, fostering responsible development and deployment of robotic technologies

Designing a Robot

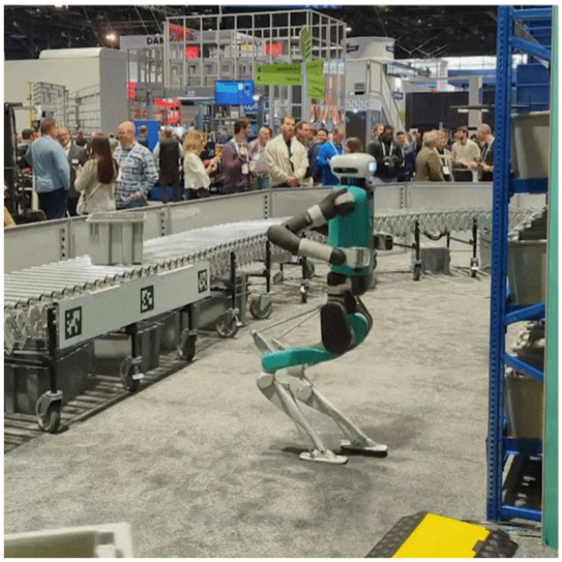
Considerations:

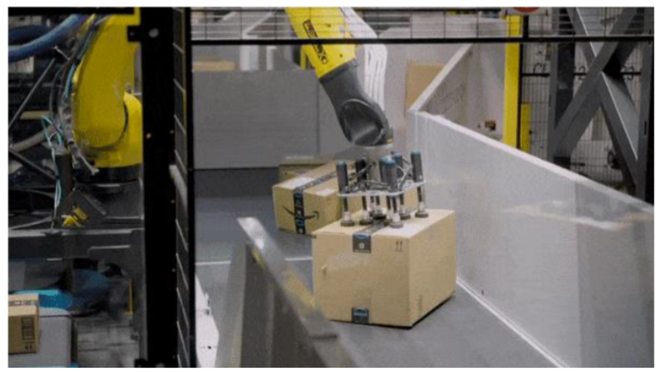
1. Tasks and Operating Environments
    - Define specific tasks the robot will perform.
    - Analyze working environments: indoor/outdoor, structured/unstructured, temperature, terrain, obstacles, etc.
2. Hardware Design
    - Mechanical Structure: Chassis, joints, degrees of freedom
    - Actuators: Motors, servos, pneumatic or hydraulic systems
    - Power System: Battery type, power efficiency, backup options
3. Firmware and Embedded Systems
    - Computing Units: Microcontrollers, onboard processors
    - Sensor integration: Cameras, IMUs, LiDAR, GPS, force sensors
    - Communication Interfaces: Wired/wireless protocols (e.g., I2C, SPI, UART, CAN, Wi-Fi, Bluetooth)
4. Software Architecture
    - Control Algorithms: Motion planning, PID control, pathfinding
    - Autonomy and Intelligence: SLAM, AI/ML models, obstacle avoidance
    - User Interface: Remote control, dashboards, or autonomous modes.

Where are we?

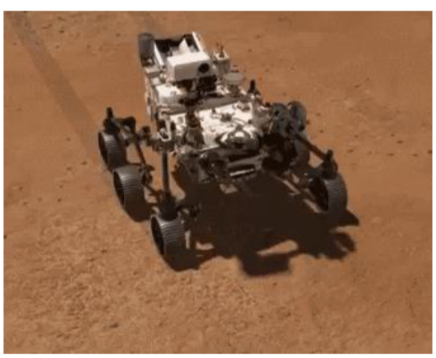
Logistics and Warehouse Robots

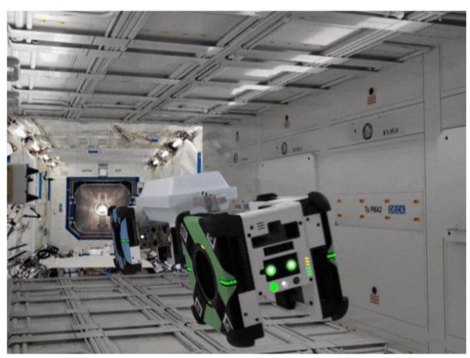
Space Robots



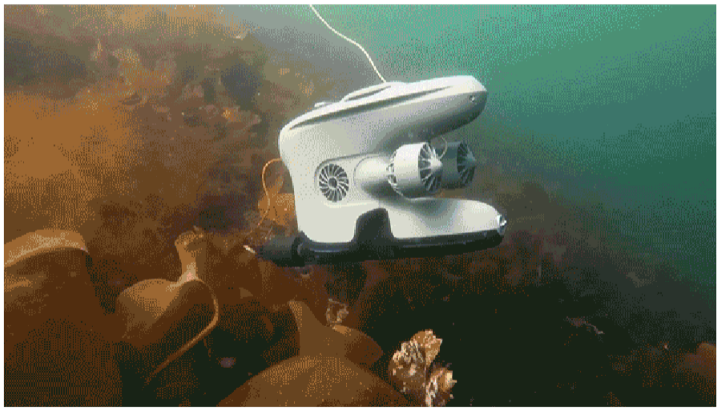


Deepsea Robots





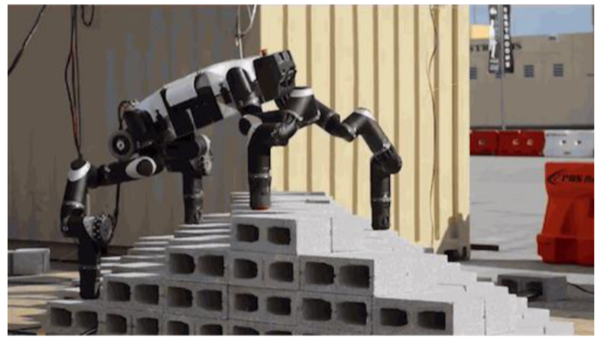
Healthcare and Medical Robots (?)



Agricultural Robots

Disaster Response Robots

Service and Hospitality Robots

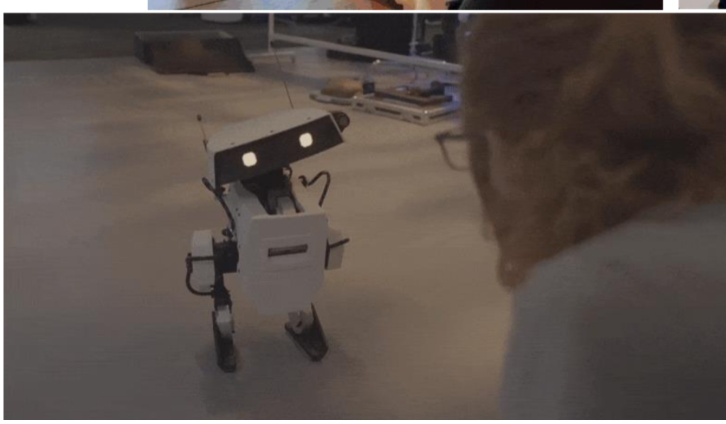
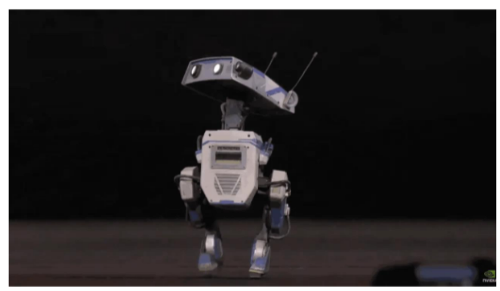


Education, Entertainment, and Companion Robots

Humanoids | Tesla Optimus, Unitree H1, 1x, Figure





[FILL]

[FILL]

Rigid Body in 3D space:

[FILL image] How many DoF does it have?

- $6 = 3$ for position $+ 3$ for orientation

Joints and DoF

[FILL image, full]

How many DoF do you have?

[FILL image] Whole body: 30 DoF (major joints)

Grübler's Formula

$$
\begin{aligned}
\text{def} &= m(N-1) - \sum_{i=1}^{J} c_i \\
&= m(N-1) - \sum_{i=1}^{J} (m - f_i) \\
&= m(N-1-J) + \sum_{i=1}^{J} f_i
\end{aligned}
$$

- The term $m(N-1)$ represents the number of rigid body freedoms
- The term $\sum_{i=1}^{J} c_i$ represents the number of joint constraints.
- We would use $m = 3$ for two-dimensional rigid bodies (planar mechanisms), and $m = 6$ for three-dimensional rigid bodies (spatial mechanisms).

Acrobot (Double Pendulum)

[FILL image]

- You can only move the first joint; the second is completely free moving.
- The tip is called the **end effector**.
- The entire circle that the robot can reach is called the **work space.**

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Motors and Gears

Action and Actuation

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Definition of Effector

- An effector is any device that has an effect on the environment.
- A robot's effectors are used to purposefully <u>create an effect</u> on the environment.
- E.g., legs, wheels, arms, fingers, ...
- *The role of the controller is to get the effectors to produce the desired effect on the environment, based on the robot's task*

Definition of Actuator

- An actuator is the mechanism that enables the effector to execute an action.
- E.g., electric motors, hydraulic or pneumatic cylinders, pumps, ...
- Actuators and effectors are **not** the same thing.

Electric Motors

[FILL image]

- **AC Motor**
  - Hard to control speed directly
  - Cheaper and more durable → common in household appliances, HVAC, pumps, and fans
- **DC Motor**

  FILL

  - **The most common actuator in mobile robotics is the direct current (DC) motor**
  - Advantages: [FILL]
  - Disadvantages: [FILL]

How do DC motors work?

- DC motors consist of permanent magnets with loops of wire inside
- When current is applied, the wire loops generate a **magnetic field**, which reacts against the outside field of the static magnets
- The interaction of the fields produces the movement of the shaft or armature
- A **commutator** switches the direction of the current flow, yielding continuous motion

Types of DC Motors

- Brushed motors (mechanical commutation)
  - Low-voltage, low-torque, cheap
- Brushless motors (electric commutation)
  - High voltage, high-torque, expensive
  - No friction or wear of brushes

[FILL images]

Motor Efficiency

- As any physical system, DC motors are not perfectly efficient

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- Good DC motors can be made to have efficiencies in the 90th percentile
- Cheap DC motors can be as low as 50%

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Speed and Torque

- Motor speed w is proportional to induced voltage V.

$$w = k_v V$$

- Torque is a force that acts in a rotational manner

$$t = r \times F$$

- Motor torque t is proportional to applied current I:

$$t = k_I I$$

- Motors have a maximum speed (no-load speed) and a maximum torque (stall torque)

Speed/Torque Relationship

[FILL image (graph)]

Motor Power

- Output power is the product of speed and torque:

$$P = w \times t$$

- At stall torque and no-load speed, the power is zero!

[FILL]

Power as a function of τ, ω

$$P_{motor}(\omega) = -\frac{\tau_s}{\omega_n}[FILL]P_{motor}(\tau) \qquad = [FILL]$$

[FILL]

Operating Voltage and Speed

- Motors have maximum voltage

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DC motors and Robots

- DC motors have high-speed, low torque
- Typical speed range:
  - 9000 to 12000 RPM
  - 150 to 200 Hz
- Robots require low-speed, high torque.
  - What do we do about this? (We use gears!)

Gearing

- Gears are used to [FILL]

Gear Fundamentals

- The force F at the edge of a gear of radius r is given by:

$$F = \tau / r$$

- The linear speed v at the edge of a gear of radius r is given by:

$$v = \omega r$$

Combining Gears

- Meshing gears have equal linear speeds.

$$v_1 = v_2$$

- Thus the output speed is:

$$v = \omega r, \ \therefore \omega_2 = \frac{r_1}{r_2} \omega_1$$

- And the output torque is:

$$F = \tau / r \ \ \therefore \tau_2 = \frac{r_2}{r_1} \tau_1$$

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Examples:

- Gearing down:

$$r_1 = 1, r_2 = 2$$

  - 2:1 gear ratio doubles the torque and halves speed

- Gearing up:

$$r_1 = 2, r_2 = 1$$

  - 1:2 gear ratio halves torque and doubles speed

Gear Stages

- Usually, it is not possible to achieve a sufficient gear ratio with a single pair of gears
- Gears can be arranged *in stages*
- The tortal gear ratio is the product of gear ratios for each stage
  - E.g., $3:1 \times 3:1 = 9:1$

Types of Gears

[FILL image]

Backlash

- Simple gears suffer from *backlash* (teeth not meshing completely)
- Although sometimes this is needed, it reduces the control you have

[FILL image]

Control of Motors

Controlling Speed: Pulse Width Modulation (PWM)

[FILL image]

Controlling Direction: H-Bridge

[FILL image]

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Servo Motors

- Servo motors are adapted DC motors:
  - Gear reduction

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PWM Position Control

[FILL image]

- Not defined by PWM duty cycle but only **duration** of the pulse!
- Pulse width must be very accurate
  - Noise in width $\Rightarrow$ noise in position
- Pulse rate may be variable
  - Noise in rate $\Rightarrow$ no change