



DARWIN-OP DRIVES

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Outline

- ① Conception
 - Why have a humanoid drive?
- ② Simulation
 - Interface challenges
 - Algorithm prototyping
- ③ Realization
 - The Robot and the Roomba

Concept

- Humans have developed countless tools to extend our capabilities. With the ability to use these same tools, humanoid robots can become our most versatile invention yet.



Autonomous vehicles

- ◎ Why do we drive?
 - Go further, faster
 - Traverse the roughest terrains
 - Carry more stuff

- ◎ Why Autonomy?
 - Safety
 - Eliminate *human* error
 - Convenience
 - Drop-off, pick-up, chauffeur
 - Optimization
 - Traffic, time, gas



Current Efforts

- ◎ DARPA Grand / Urban Challenge
- ◎ Google's driverless car, etc.
 - One car outfitted with many sensors
 - Tested and tuned
 - Car type chosen for specific application

Why have a humanoid drive?

◉ Adaptability

- **Form** - our world was built for us
 - Able to use our tools in our environment
- **Multi-use** - drive to a destination and perform a task
- **Learning** - adapt to different cars
- **Hardware** - changes to vehicle not necessary



Our Solution...



DARwin-OP Humanoid Application Challenge ICRA 2012



***Brittany Killen, Sun Chunyang,
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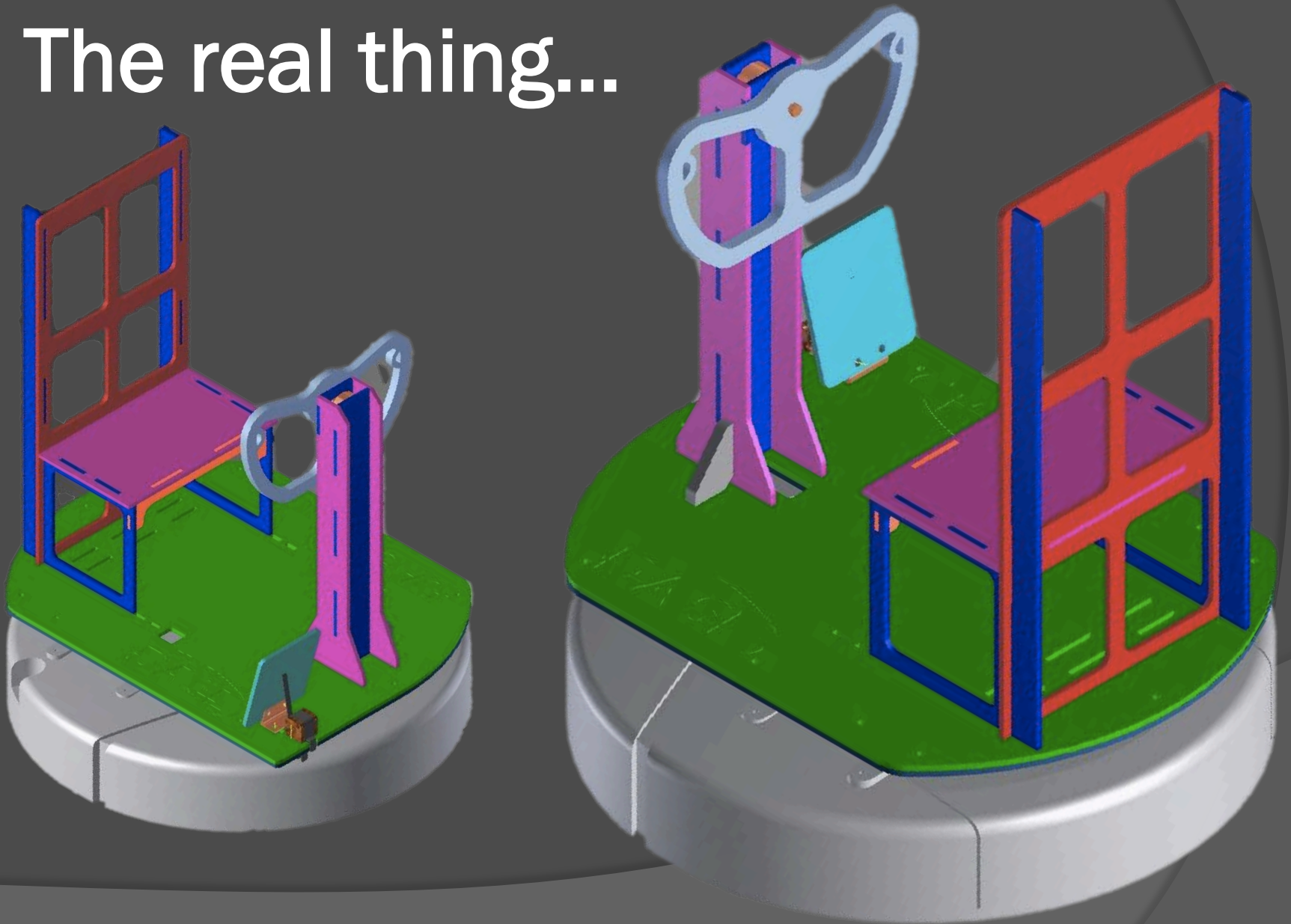
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The real thing...

- ◎ DARwin-OP remains unmodified
 - Vision Processing
 - Steering controller outputs arm movement
 - Foot puts the pedal to the metal

- ◎ iRobot Create (vehicle)
 - Differential Drive with Atmel
 - Digital I/O
 - A/D
 - Laser-cut acrylic steering wheel, seat & pedal
 - Potentiometer controls angular velocity
 - Gas pedal controls forward velocity (1/0)

The real thing...



The real thing...

◎ DARwIn's Arms

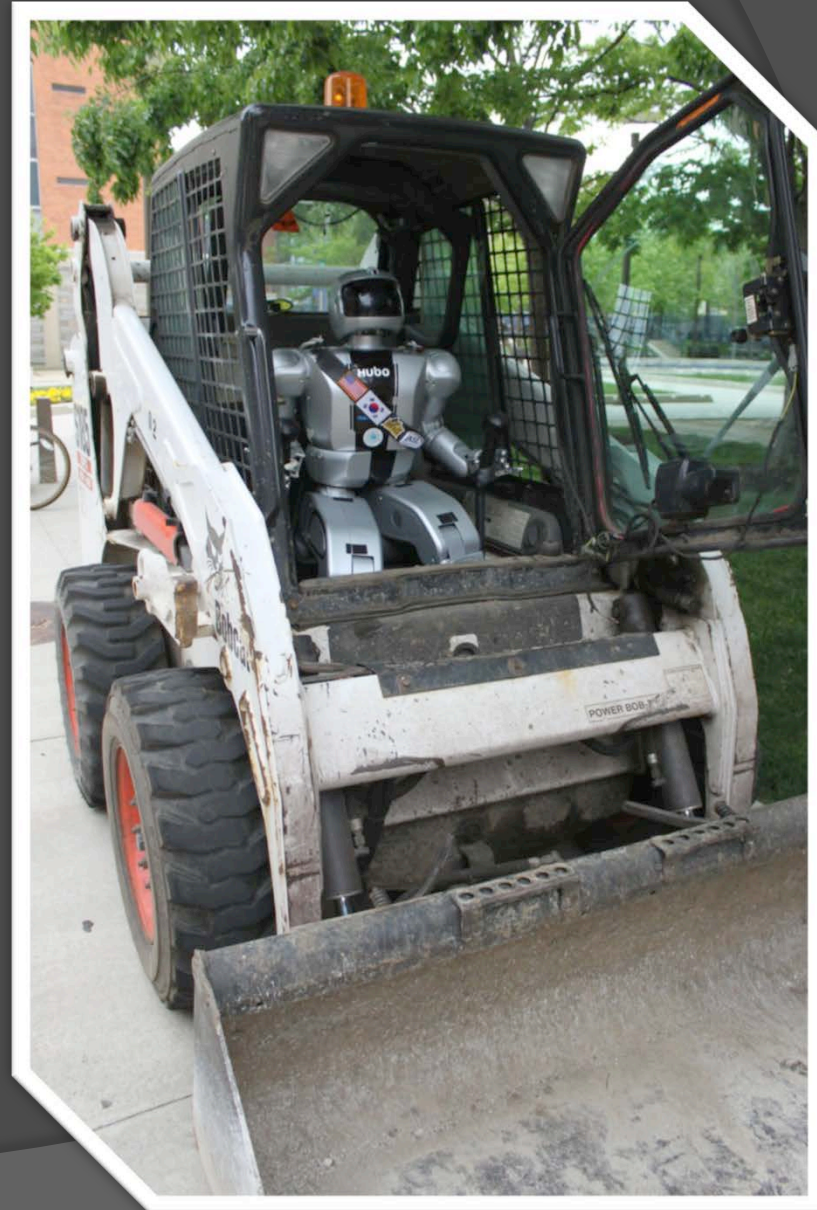
- IK for movement in the steering plane
- PD control
- Elastic constraint to steering wheel

◎ DARwIn's Eyes

- Road and Blob following
- Image processing
 - HSV segmentation
 - Erode and dilate
 - Image projection

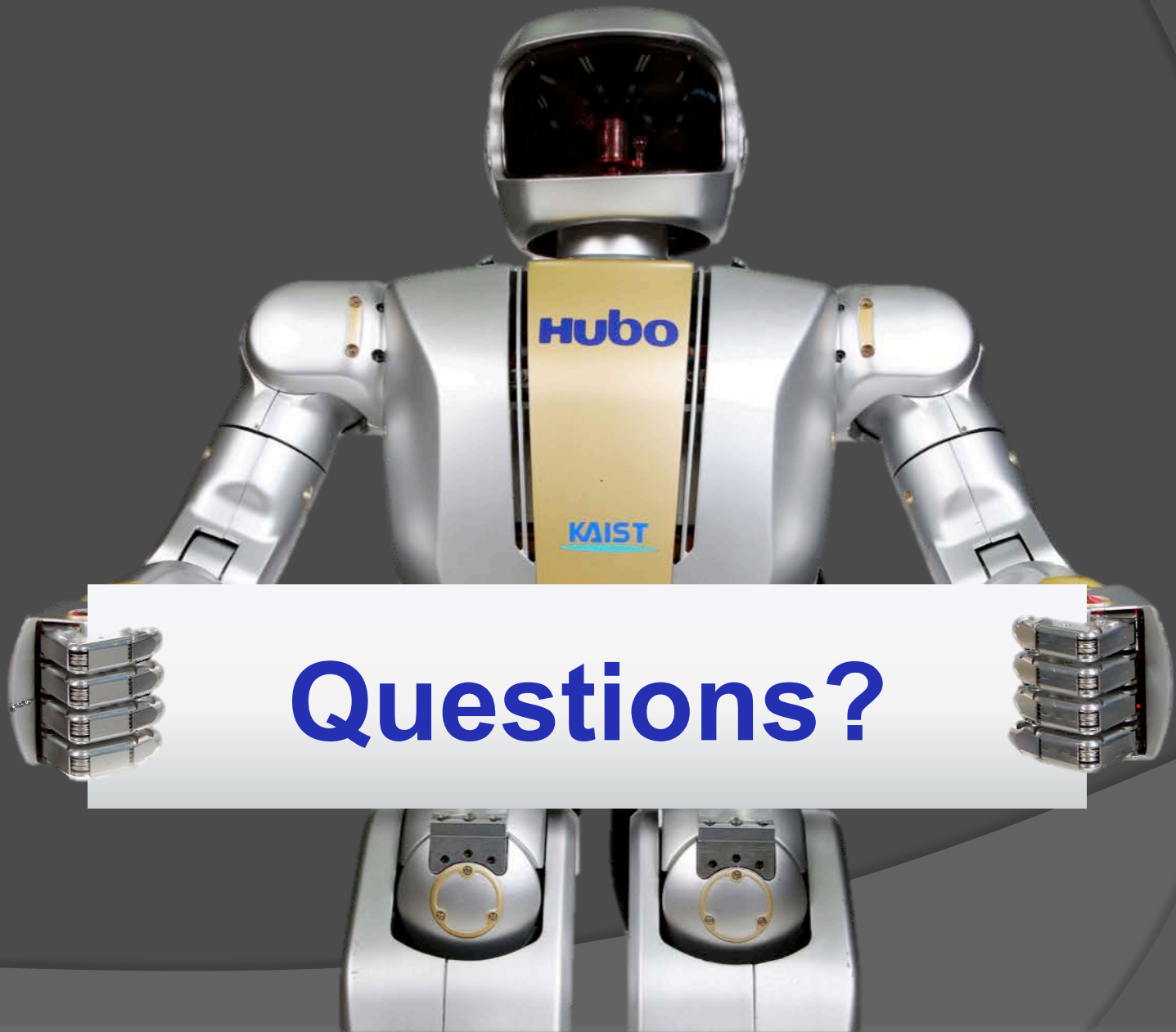
What's next?

- DARPA Research Challenge
- Sensory Augmentation (e.g. Blind)

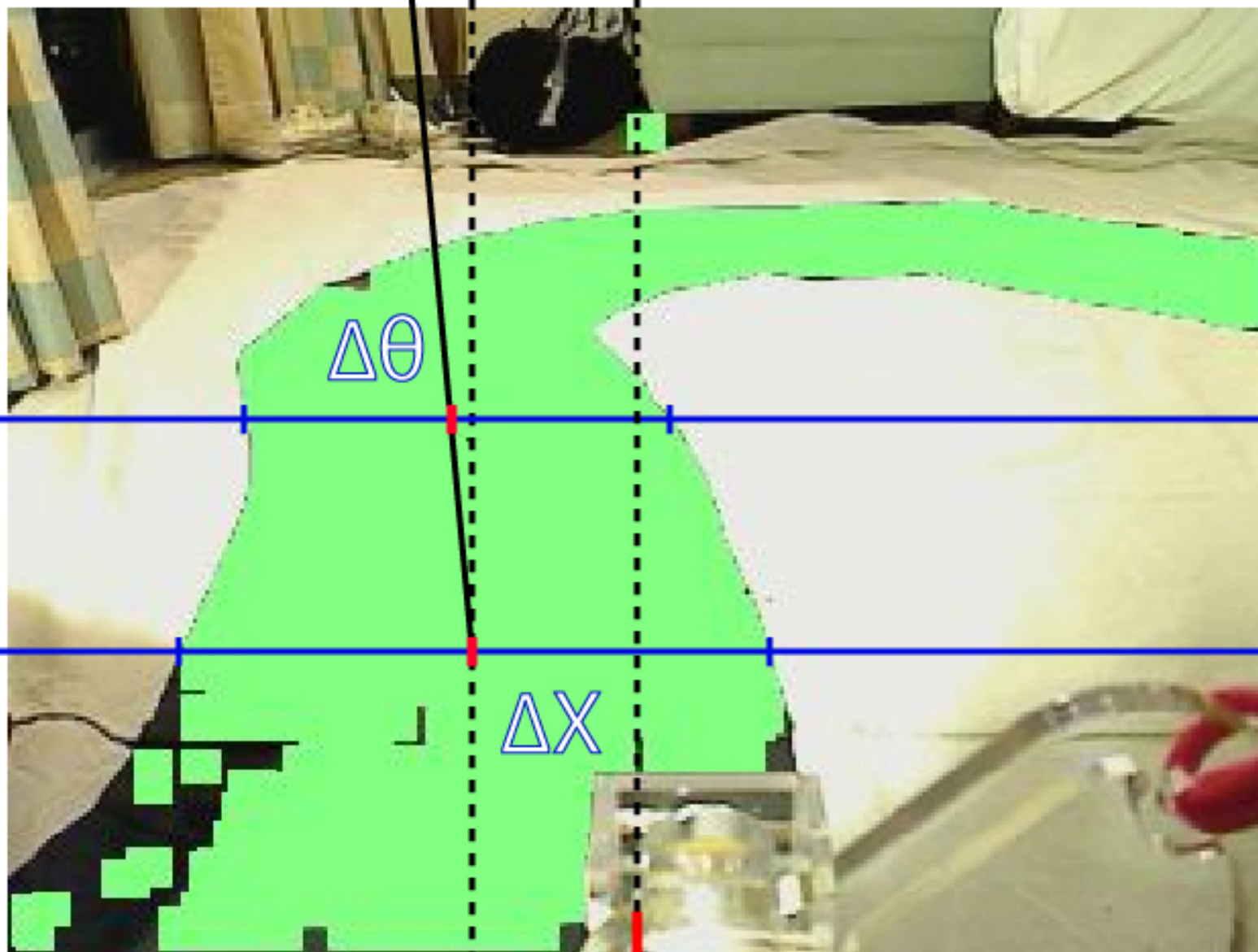




Thanks!



Questions?



Inspiration

