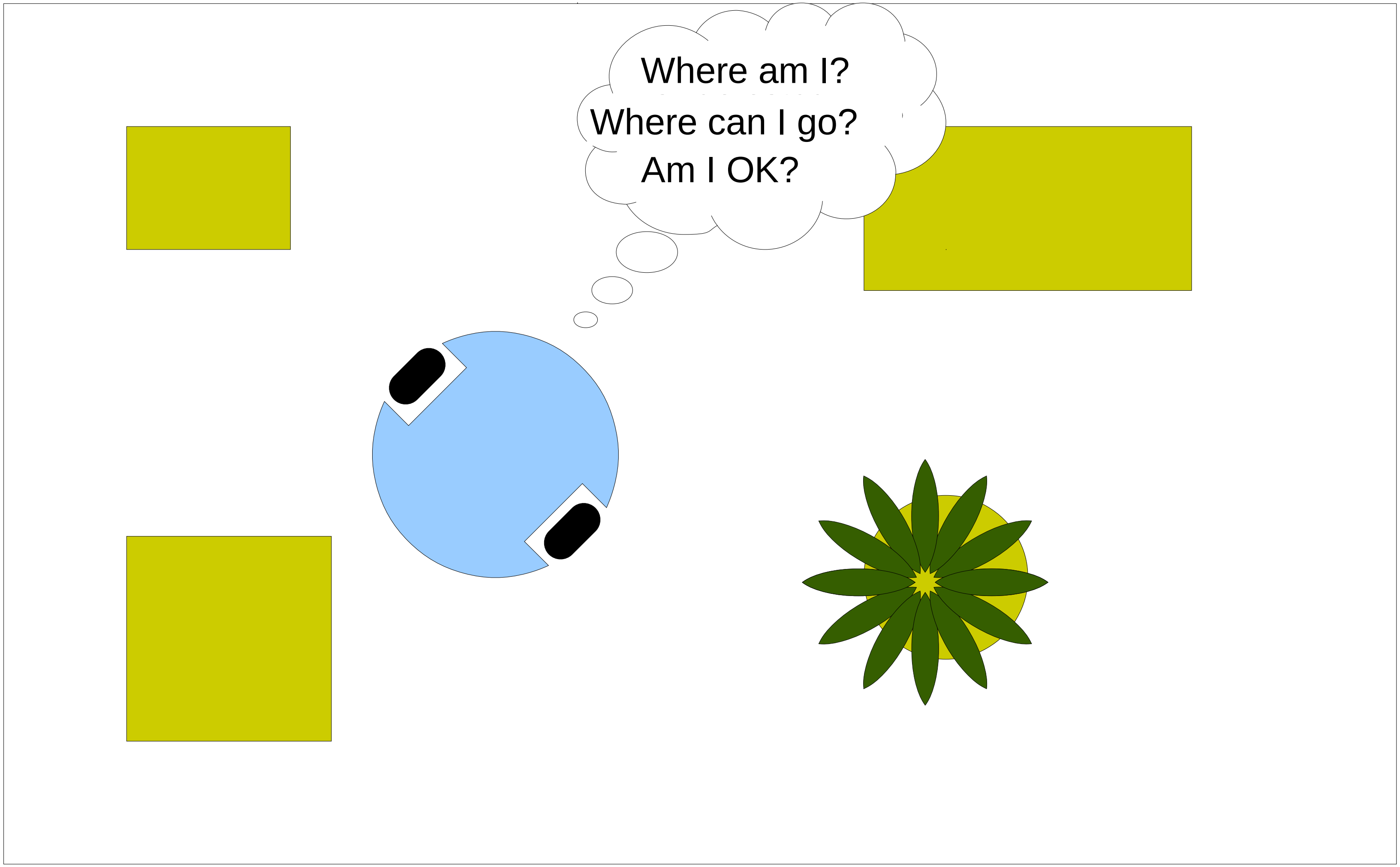
sensors

Robótica Móvel e Inteligente / Mobile and Inteligent Robotics
Mestrado Integrado em Engenharia de Computadores e Telemática

Academic year 2021/22

Departamento de Electrónica, Telecomunicações e Informática
Universidade de Aveiro

existencial problems in a robot's life

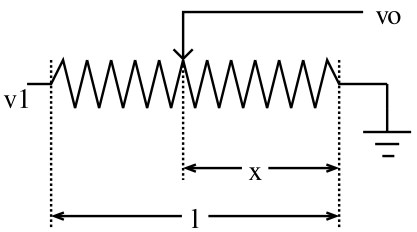


sensorial information

- Self perception (“How am I doing?”)
  - Posture
  - Batteries, ...
- Location (“Where am I?”)
  - Position
  - Orientation
- Environment perception (“Where can I go to?”)
  - obstacles
  - maps: constructing and location
  - targets (application level)

position::potentiometer

- Simplest way to measure position

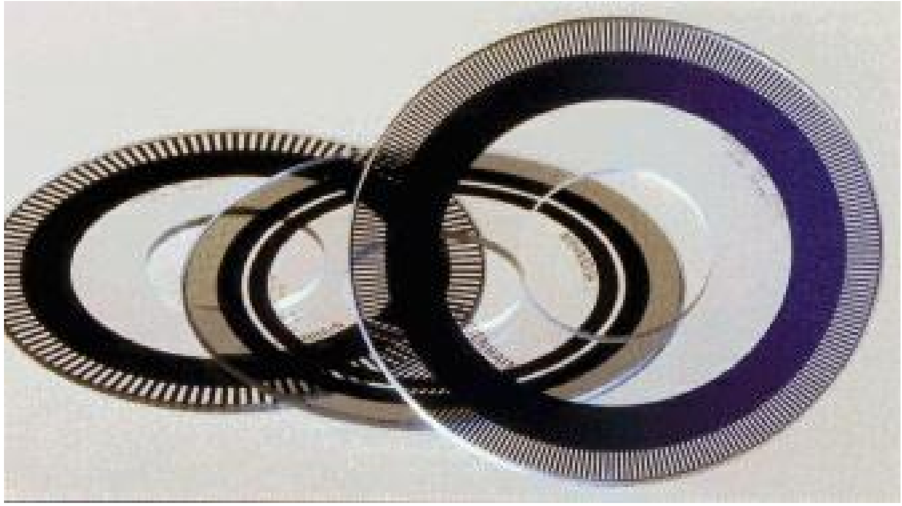


$$x = l\frac{v_o}{v_i}$$

http://alliancesensors.com/lp-22-series-linear-potentiometer

https://www.vexrobotics.com/276-2216.html

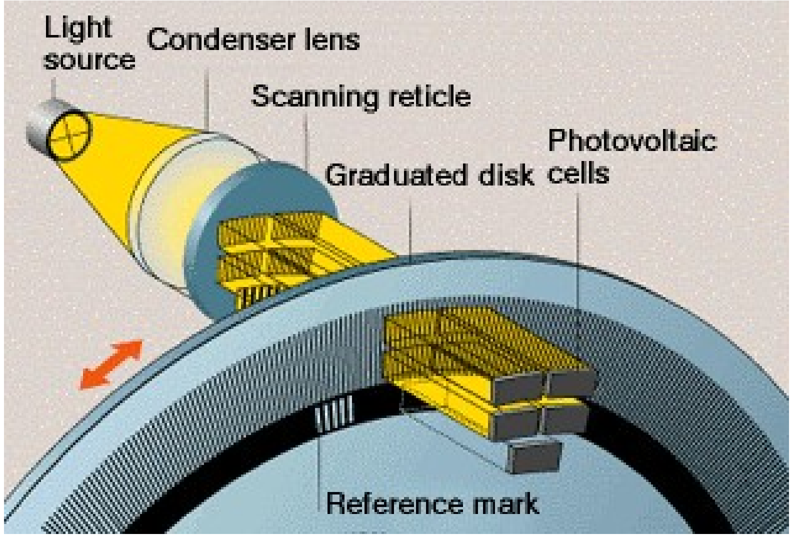
optical encoder

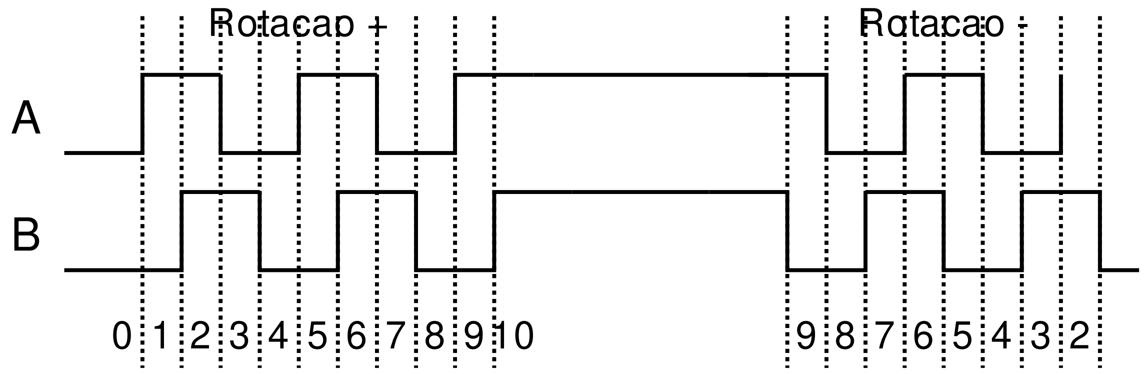


- Pulses generated by the interference of two patterns of stripes
- # of pulses proportional to displacement
- encoder characterized by ppr (pulses per revolution)

optical encoder

- Interference generates a varying signal with displacement
- This signal is converted to digital

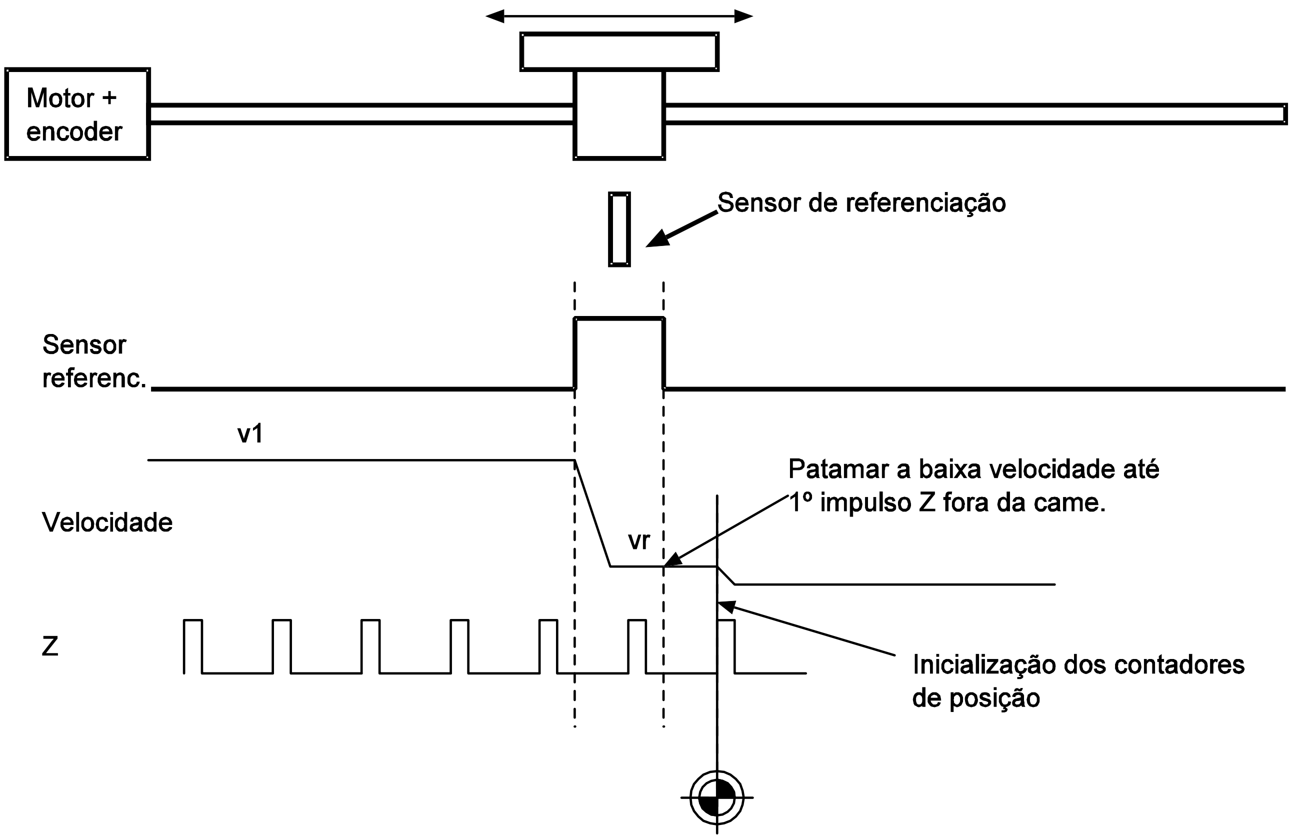




- Quadrature allows:
  - to detect the direction of movement
  - multiply encoder resolution by 4
    - 1 impulse = 4 counts

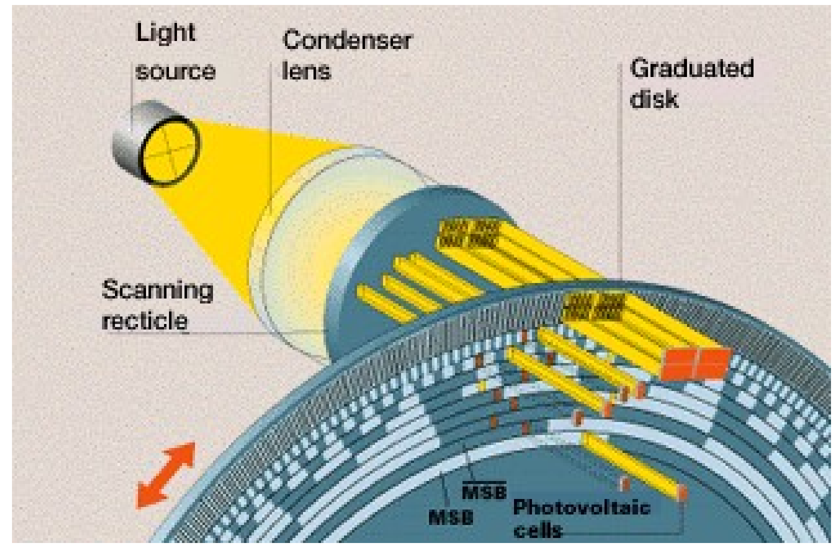
referencing

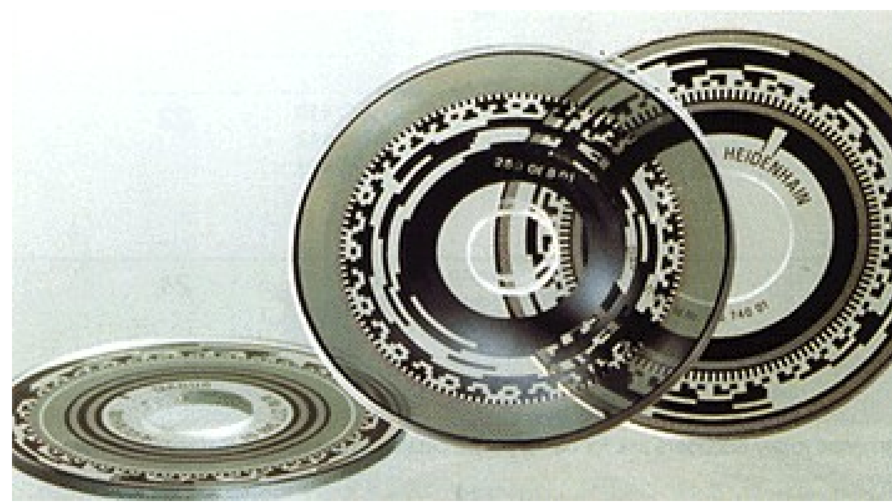
- Incremental encoders detect *displacement*, not *position*
- required detection of a reference point (origin, zero, …)



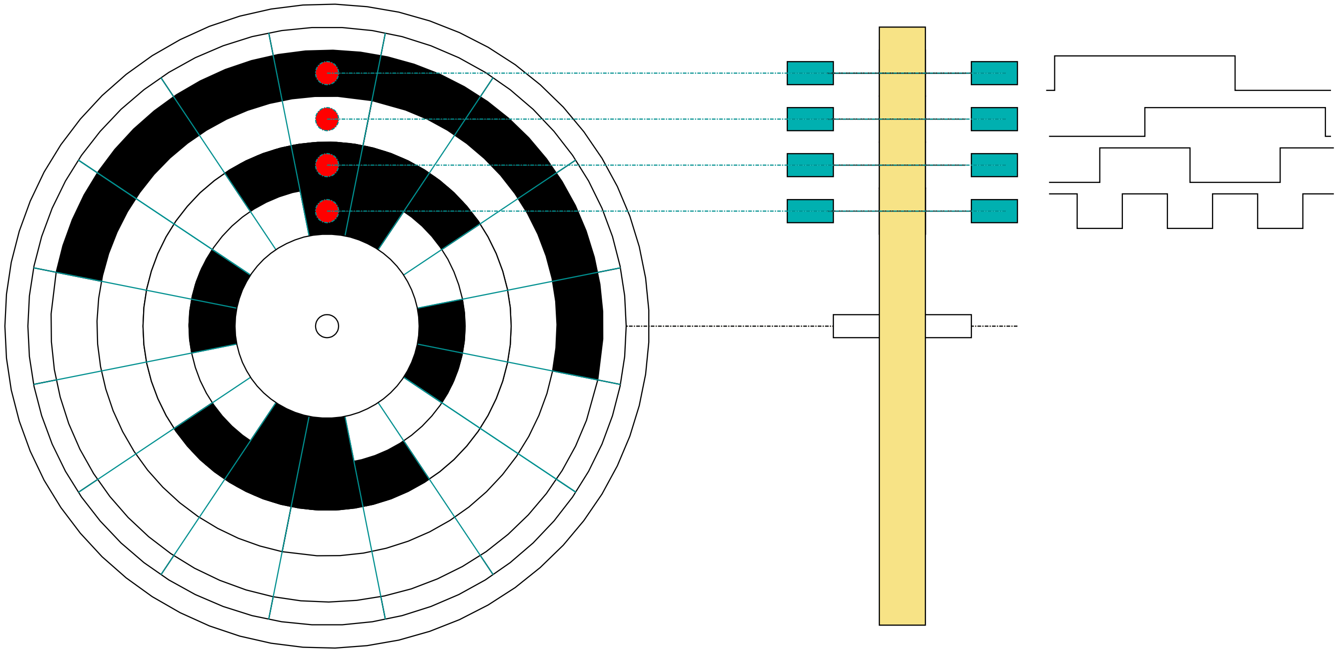
absolute encoder

- optical disk with Gray code
- output is shaft position (angle) in binary code



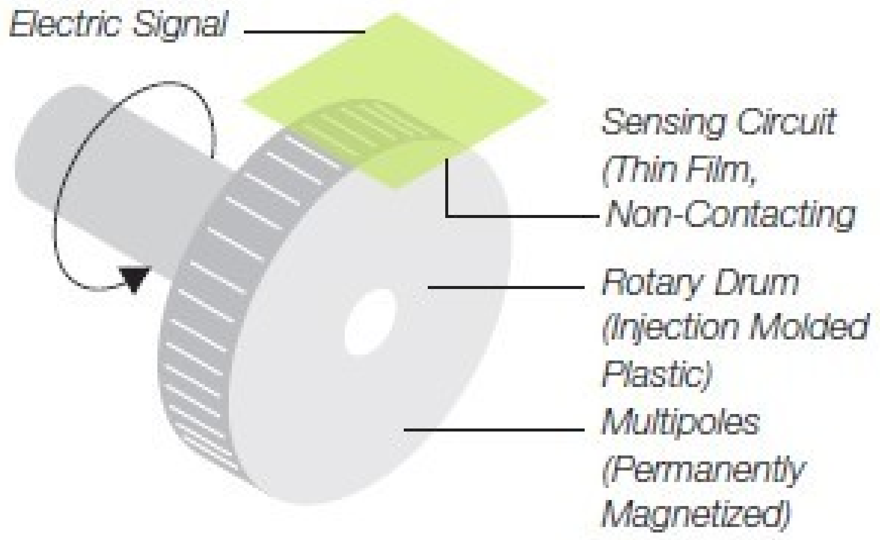


absolute encoder



magnetic encoder

- principle similar to optical incremental encoder
- small permanent magnets in the shaft drum
- sensing circuit detects passing magnets and measures rotation
- Pro: unaffected by dust, moisture, and extreme temperatures, and shock.

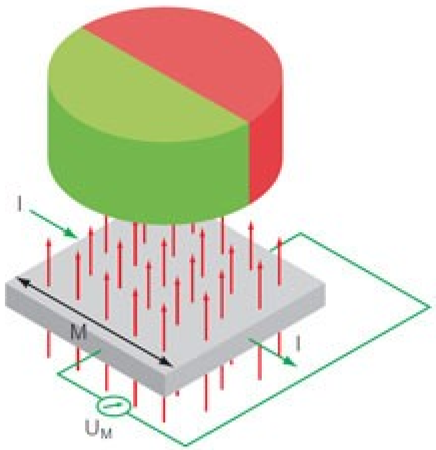


- bicycle computers work in a similar fashion

https://www.bicycle-guider.com/cycling-advice/best-bike-computers-buyers-guide/

hall effect encoder

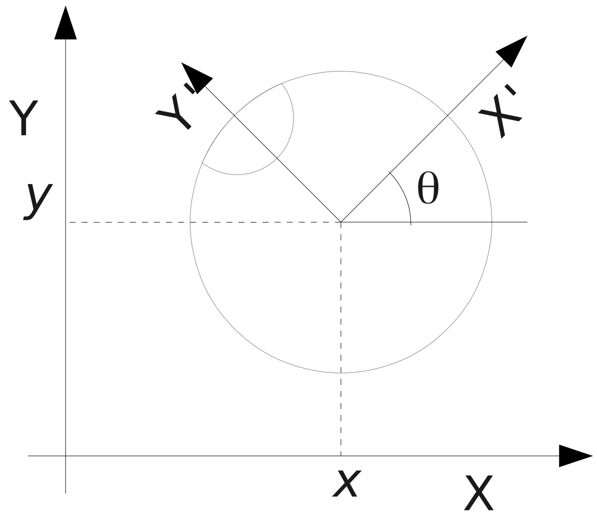
- Based on **Hall effect**
  - production of a voltage difference (the Hall voltage) across an electrical conductor, transverse to an electric current in the conductor and to an applied magnetic field perpendicular to the current
- A permanent magnet is attached to the shaft
- Orientation of magnetic field is detected by an array sensor



https://www.dynapar.com/Technology/Encoder_Basics/Magnetic_Encoder/

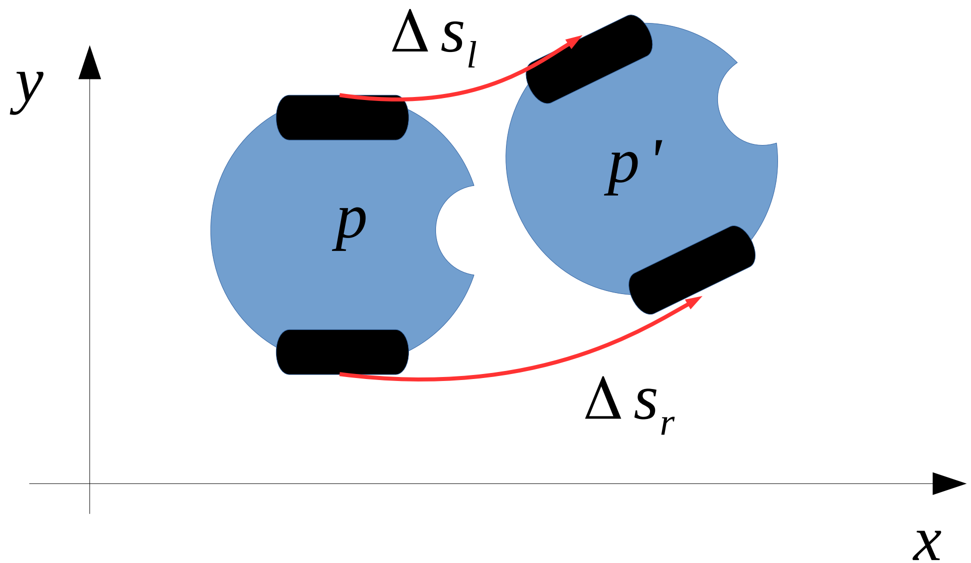
Position

- Odometry
  - def.: use of data from motion sensors to estimate change in position over time
  - relative position
  - Sources of error:
    - limited resolution (encoder)
    - model inaccuracies:
      - systematic → accumulates (error in slope)
        - error in wheel diameter
    - slippage
      - random, can reach significant values
  - Errors accumulate → unbounded !!

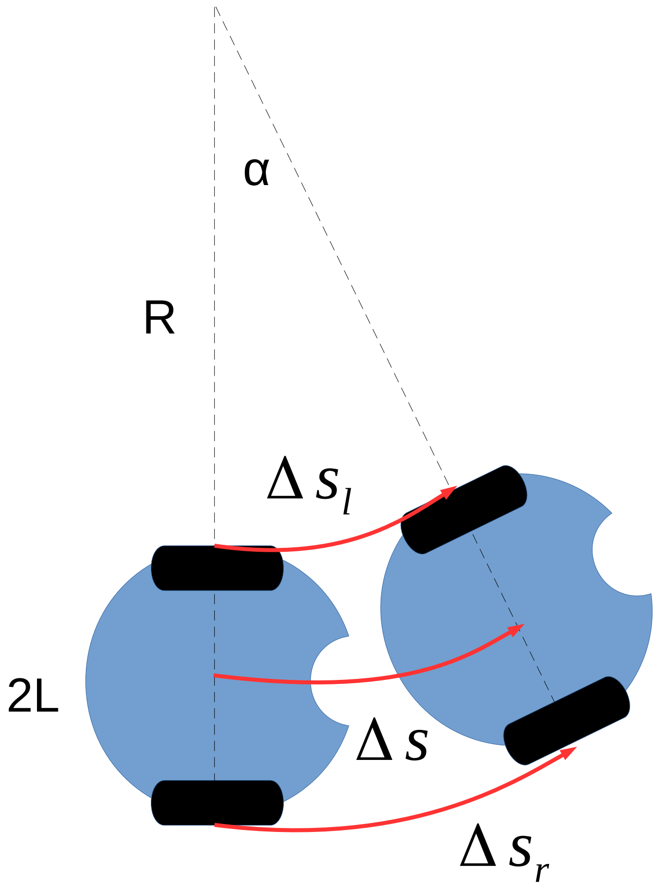


Robot location in the plane
Pose

$$p = \begin{bmatrix} x \\ y \\ \Theta \end{bmatrix}$$



$$\Delta s_l = R\alpha$$
$$\Delta s_r = (R + 2L)\alpha$$
$$\Delta s = (R + L)\alpha$$
$$\Delta s = \frac{\Delta s_l + \Delta s_r}{2}$$

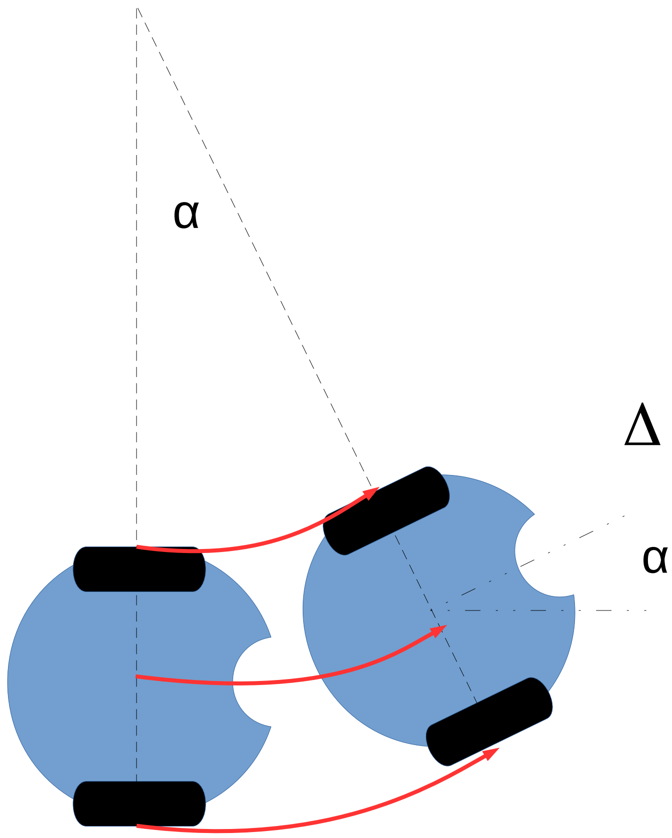


$$\Delta s_l = R\alpha$$

$$\Delta s_r = (R+2L)\alpha$$

$$\frac{\Delta s_l}{R} = \frac{\Delta s_r}{R+2L}$$

$$R = \frac{2L\Delta s_l}{\Delta s_r - \Delta s_l}$$



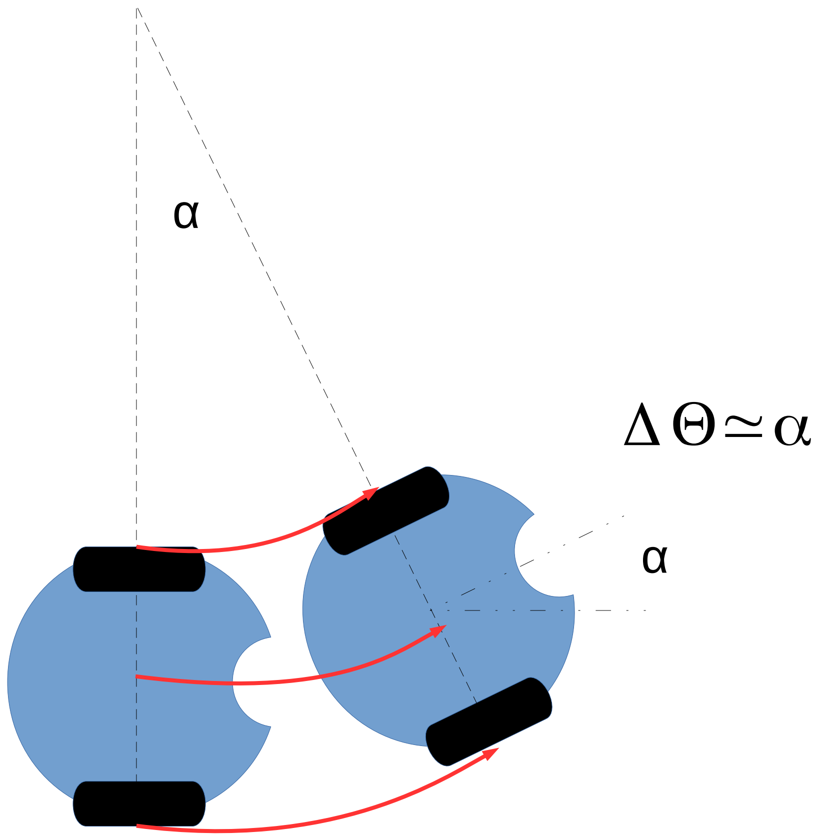
$$\Delta\Theta \simeq \alpha$$

$$\Delta S_l = R\alpha$$

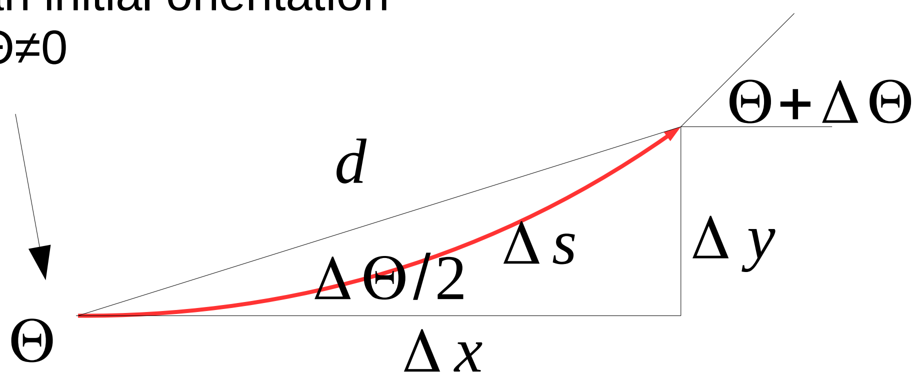
$$R = \frac{2L\Delta S_l}{\Delta S_r - \Delta S_l}$$

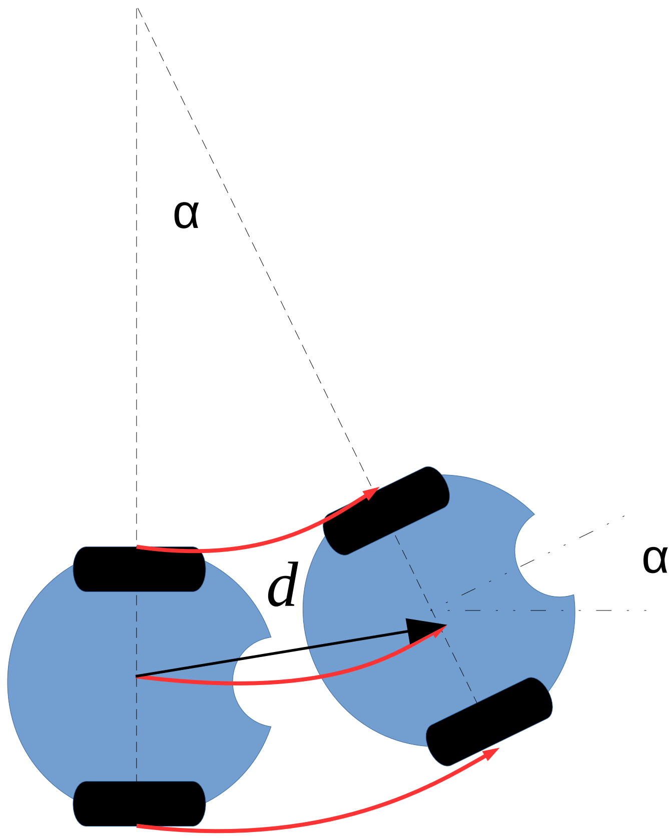
$$\begin{aligned}\alpha &= \Delta S_l / R\\ &= \frac{\Delta S_r - \Delta S_l}{2L}\end{aligned}$$

$$\Delta\Theta \simeq \frac{\Delta S_r - \Delta S_l}{2L}$$



Robot may have
an initial orientation
Θ≠0





Projection of *d* on the *x* and *y* axis

$$\Delta x = \Delta d \cos(\Theta + \Delta\Theta/2)$$
$$\Delta y = \Delta d \sin(\Theta + \Delta\Theta/2)$$

If Δs very small:

$$\Delta x = \Delta s \cos(\Theta + \Delta\Theta/2)$$
$$\Delta y = \Delta s \sin(\Theta + \Delta\Theta/2)$$

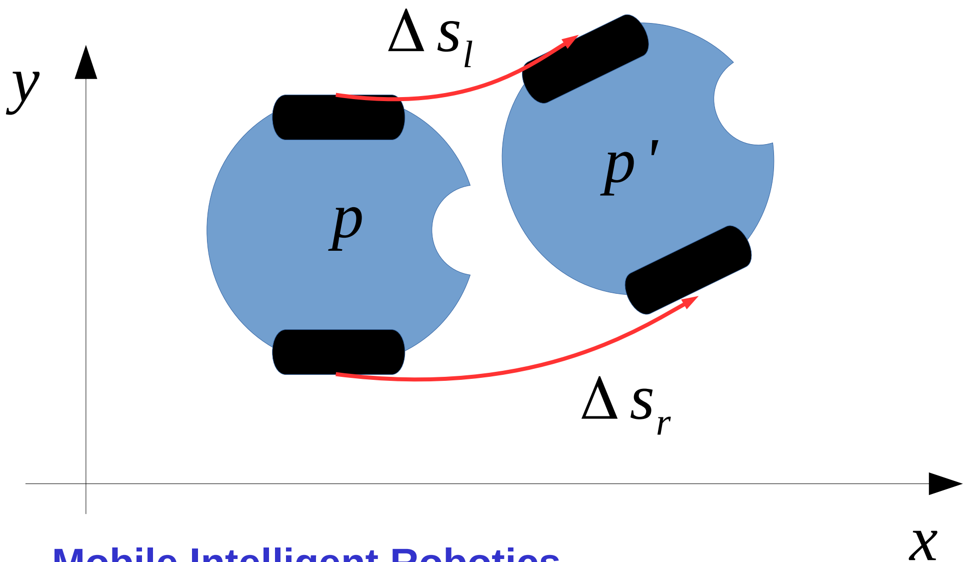
Initial pose:

$$p = \begin{bmatrix} x \\ y \\ \Theta \end{bmatrix}$$

$$\Delta x = \Delta s \cos(\Theta + \Delta\Theta/2)$$
$$\Delta y = \Delta s \sin(\Theta + \Delta\Theta/2)$$
$$\Delta\Theta \simeq \frac{\Delta s_r - \Delta s_l}{2L}$$
$$\Delta s = \frac{\Delta s_l + \Delta s_r}{2}$$

Final pose (after displacement)

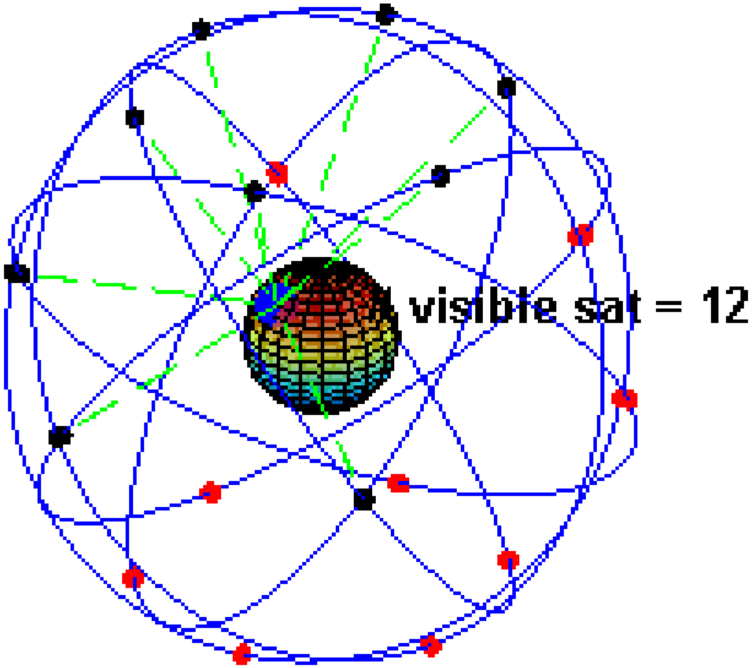
$$p' = \begin{bmatrix} x \\ y \\ \Theta \end{bmatrix} + \begin{bmatrix} \frac{\Delta s_l + \Delta s_r}{2} \cos(\Theta + \Delta\Theta/2) \\ \frac{\Delta s_l + \Delta s_r}{2} \sin(\Theta + \Delta\Theta/2) \\ \frac{\Delta s_r - \Delta s_l}{2L} \end{bmatrix}$$



position

GPS

- Absolute positioning (error in the order of m)
- Relative positioning (error in the order of cm for short time intervals)
- Requires line of sight to a minimum number of satellites → outdoor use
- Start time



error sources in GPS

Ionospheric effects	± 5 meters
Shifts in the satellite orbits	± 2.5 meter
Clock errors of the satellites' clocks	± 2 meter
Multipath effect	± 1 meter
Tropospheric effects	± 0.5 meter
Calculation and rounding errors	± 1 meter

http://www.kowoma.de/en/gps/errors.htm

mobile phone location

- Based on mobile phone location services
  - e.g.: multilateration with cell tower signals

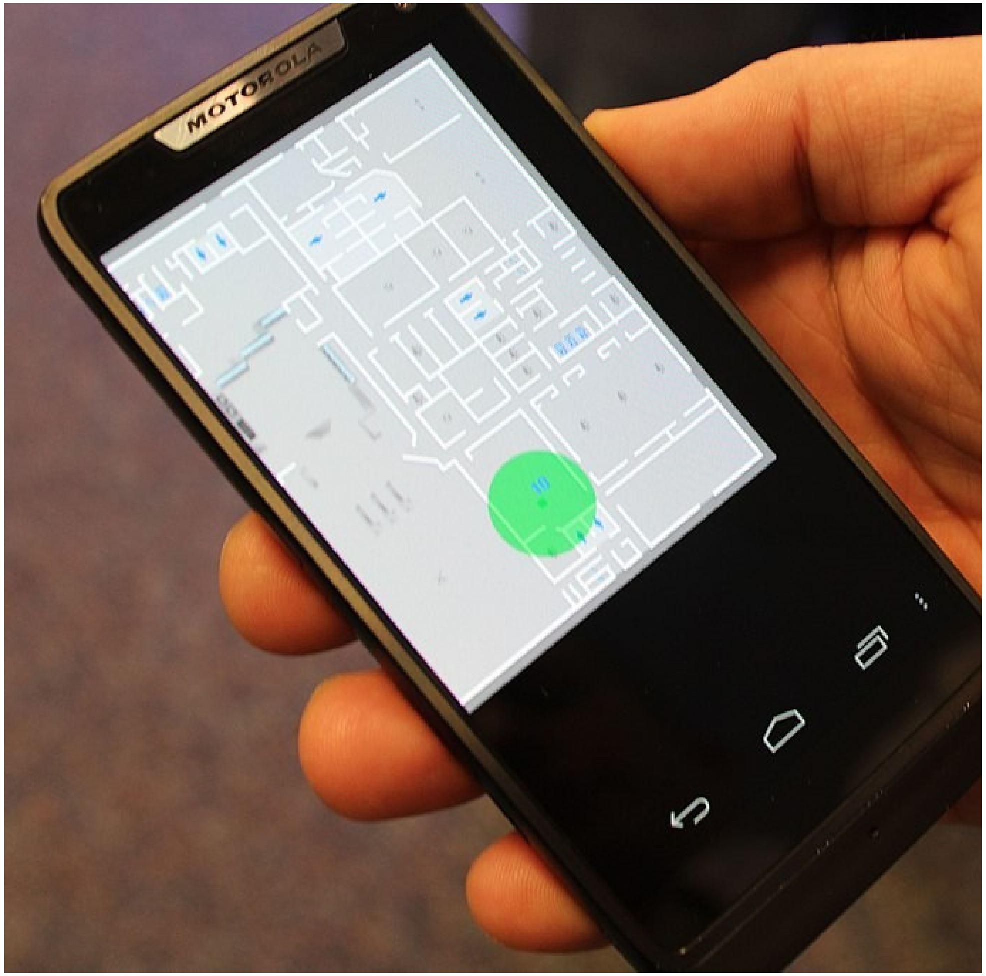
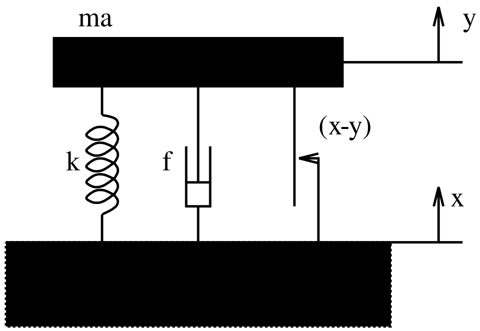


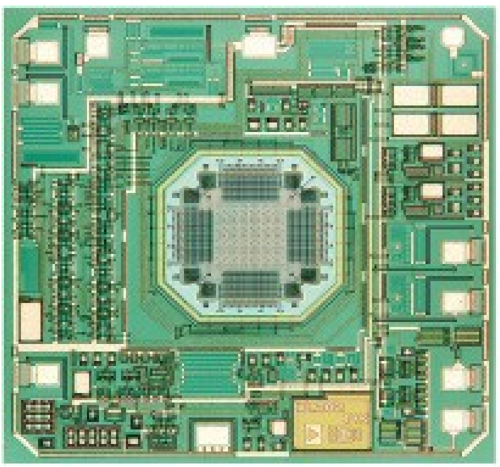
Photo by Intel Free Press - Indoor location services on mobile phone, CC BY-SA 2.0, https://commons.wikimedia.org/w/index.php?curid=71130241

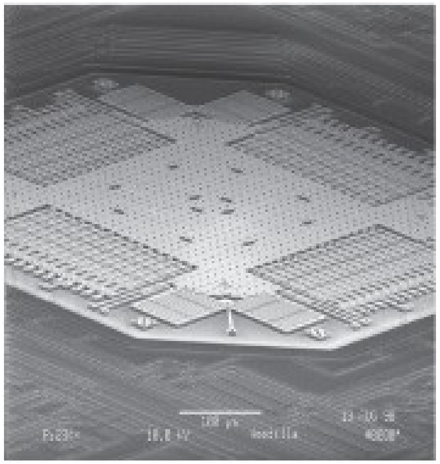
accelerometers



$$k(x-y)+f(\dot{x}-\dot{y})-m_a\ddot{y}=0$$

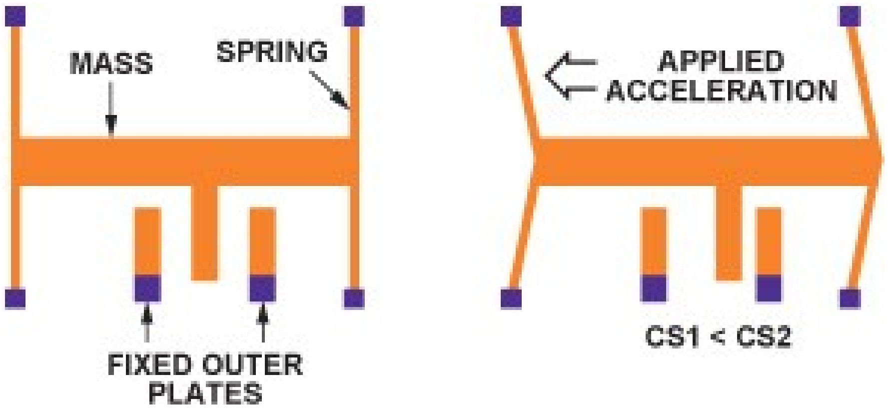
- inertial mass principle
- Ex.: ADXL... from Analog Devices
- MEMS: Micro-electromechanical Systems

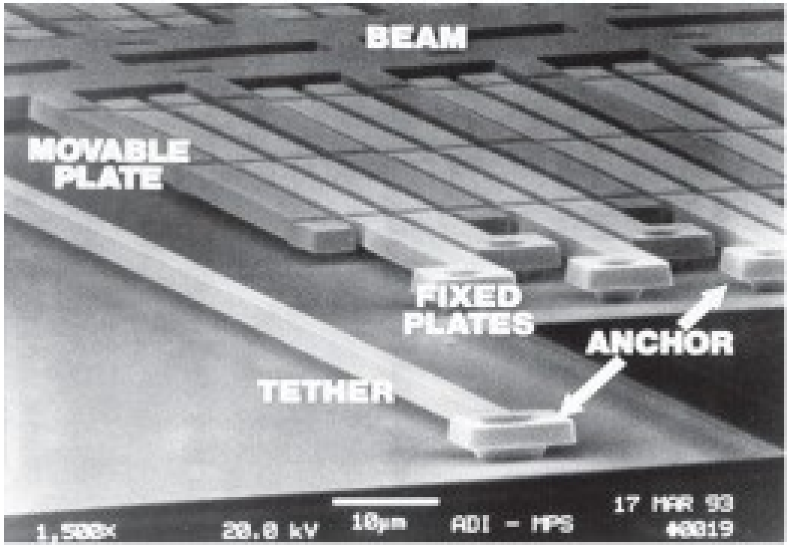




accelerometers

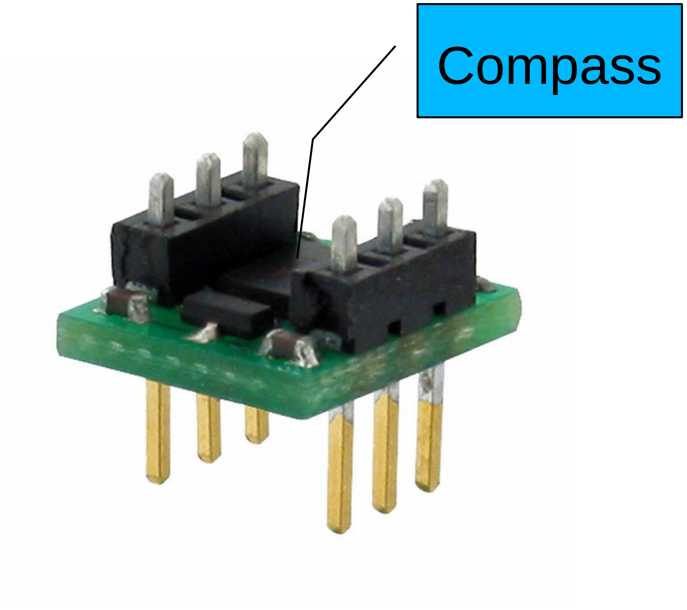
- Detection by changes on:
  - capacity
  - resistance

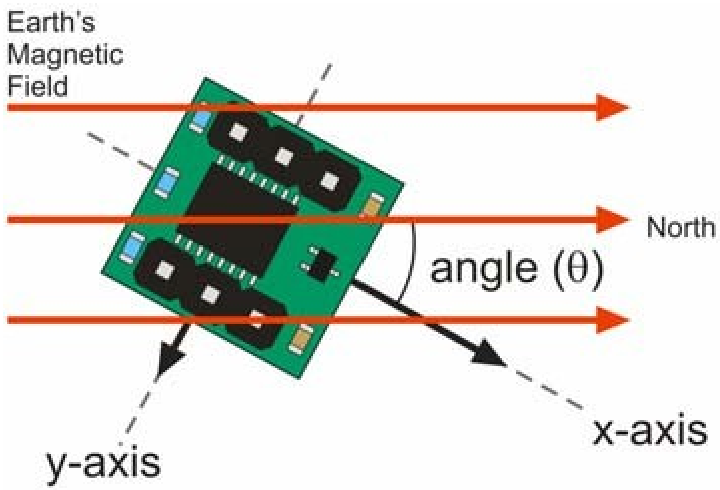




compass

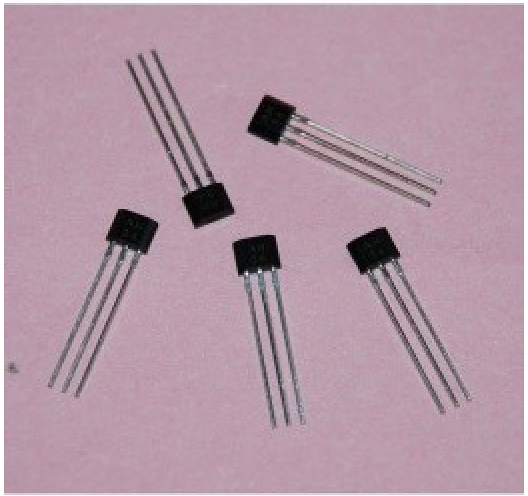
- Ex.: HM55B (Hitachi)
  - Magnetic field detection in 2 axes, x e y
  - Trigonometry is used to compute angle with magnetic N





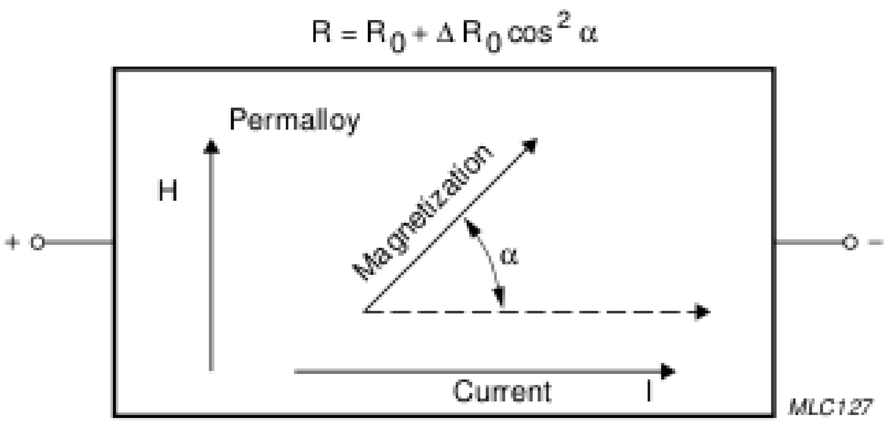
working principle

- **Hall effect**
  - voltage as a function of magnetic field



working principle

- magnetoresistive effect
  - resistivity of certain materials is influenced by magnetic field.
  - Example of magnetoresistive material: Permalloy (20% Fe, 80% Ni)



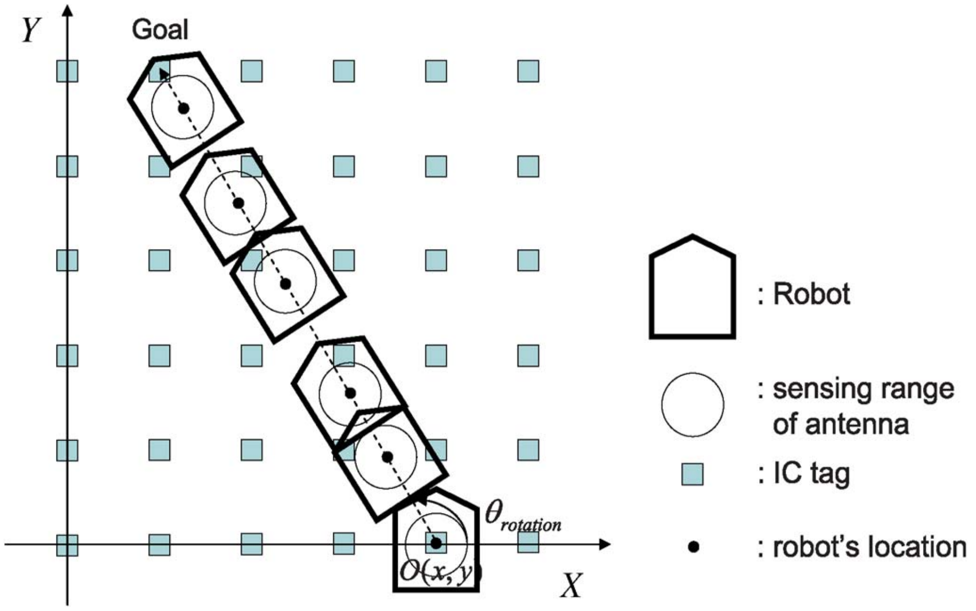
Philips Semiconductors, *Magnetic field sensors*, 1998 [KMZ51 datasheet]

Gyroscopes

- Based on inertia principle
  - rotating disk
- Electronic devices based on mechanical oscillation
  - Foucault pendulum

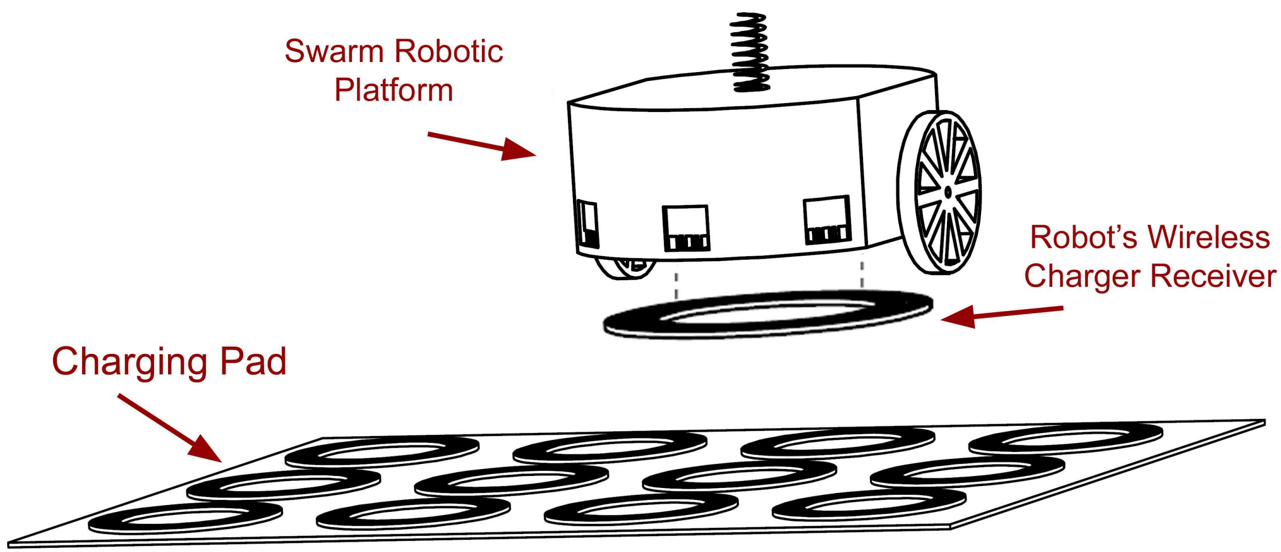
RFID location

- set of RFID tags installed in the floor
  - identifying the tag allows knowledge of position.



[1] Sunhong Park e Shuji Hashimoto, «Autonomous Mobile Robot Navigation Using Passive RFID in Indoor Environment», IEEE Transactions on Industrial Electronics, vol. 56, n. 7, Jul 2009.

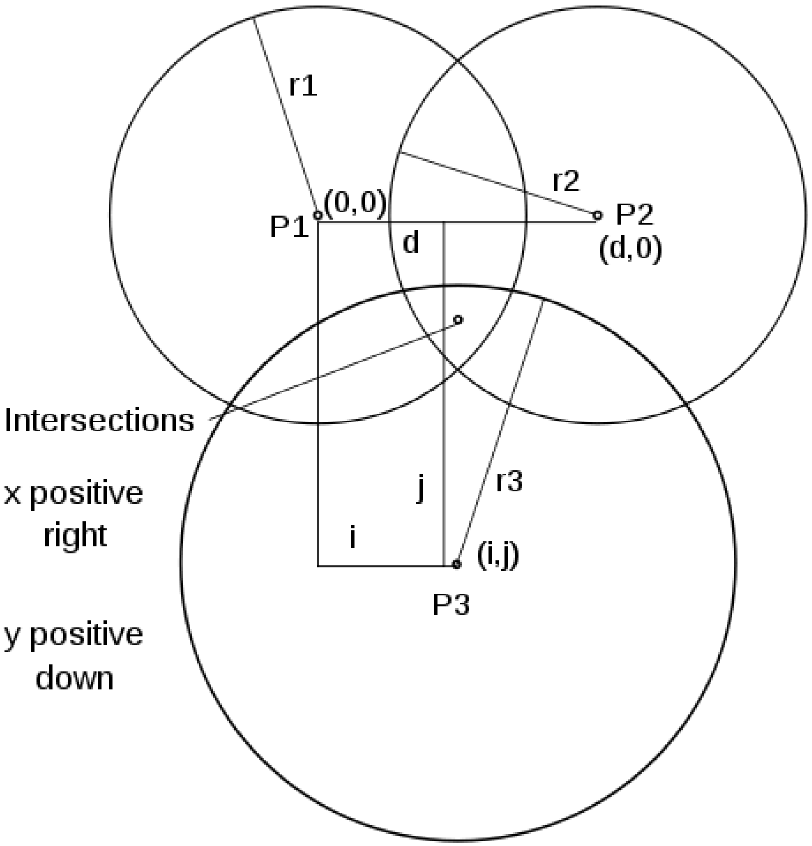
Charging and location



Coils in the floor can work for both:
- Charging (Dynamic Wireless Charging)
- Location

trilateration

- computing position by measuring distance to 3 reference points
- TOF: ultra-sounds
- RSSI: radio signal
  - D. Hahnel, W. Burgard, D. Fox, K. Fishkin, e M. Philipose, «Mapping and localization with RFID technology», 2004, pp. 1015-1020 Vol.1.



$$
\begin{aligned}
d_1^2 &= (x-x_1)^2+(y-y_1)^2\\
&= x^2-2xx_1+x_1^2+y^2-2yy_1+y_1^2\\
d_2^2 &= x^2-2xx_2+x_2^2+y^2-2yy_2+y_2^2\\
&\dots\\
d_n^2 &= x^2-2xx_n+x_n^2+y^2-2yy_n+y_n^2
\end{aligned}
$$

Subtracting the first equation from equations 2 to n:

$$
\begin{aligned}
d_2^2-d_1^2 &= 2x(x_1-x_2)+x_2^2-x_1^2+2y(y_1-y_2)+y_2^2-y_1^2\\
d_3^2-d_1^2 &= 2x(x_1-x_3)+x_3^2-x_1^2+2y(y_1-y_3)+y_3^2-y_1^2\\
&\dots\\
d_n^2-d_1^2 &= 2x(x_1-x_n)+x_n^2-x_1^2+2y(y_1-y_n)+y_n^2-y_1^2
\end{aligned}
$$

$$2(x_1-x_2)x+2(y_1-y_2)y=d_2^2-d_1^2+x_1^2-x_2^2+y_1^2-y_2^2$$
$$2(x_1-x_3)x+2(y_1-y_3)y=d_3^2-d_1^2+x_1^2-x_3^2+y_1^2-y_3^2$$
$$\ldots$$
$$2(x_1-x_n)x+2(y_1-y_n)y=d_n^2-d_1^2+x_1^2-x_n^2+y_1^2-y_n^2$$

$$\begin{bmatrix} 2(x_1-x_2) & 2(y_1-y_2) \\ 2(x_1-x_3) & 2(y_1-y_3) \\ \ldots & \ldots \\ 2(x_1-x_n) & 2(y_1-y_n) \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix} = \begin{bmatrix} d_2^2-d_1^2+x_1^2-x_2^2+y_1^2-y_2^2 \\ d_3^2-d_1^2+x_1^2-x_3^2+y_1^2-y_3^2 \\ \ldots \\ d_n^2-d_1^2+x_1^2-x_n^2+y_1^2-y_n^2 \end{bmatrix}$$

$$A\,X = B$$

$$A = \begin{bmatrix} 2(x_1 - x_2) & 2(y_1 - y_2) \\ 2(x_1 - x_3) & 2(y_1 - y_3) \\ \dots & \dots \\ 2(x_1 - x_n) & 2(y_1 - y_n) \end{bmatrix} \quad X = \begin{bmatrix} x \\ y \end{bmatrix}$$

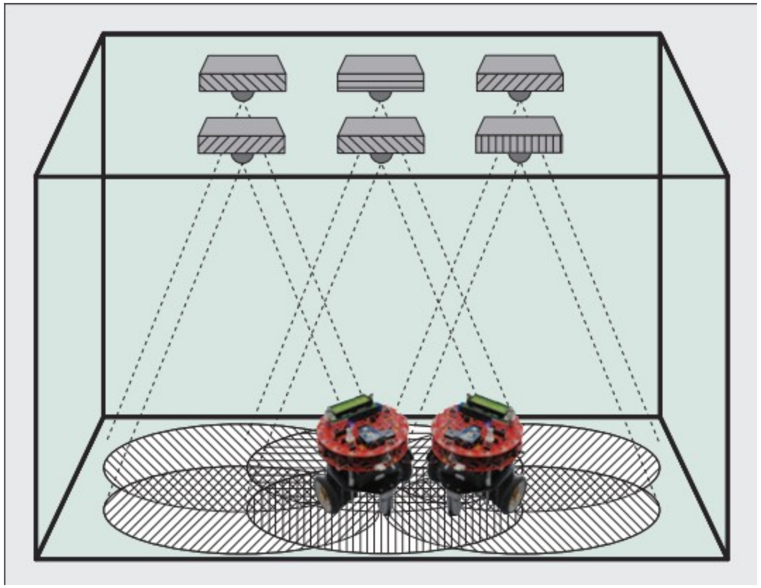
A least-square approximation can be found by using the Moore-Penrose pseudo-inverse:

$$X = (A^T \cdot A)^{-1} A^T B$$

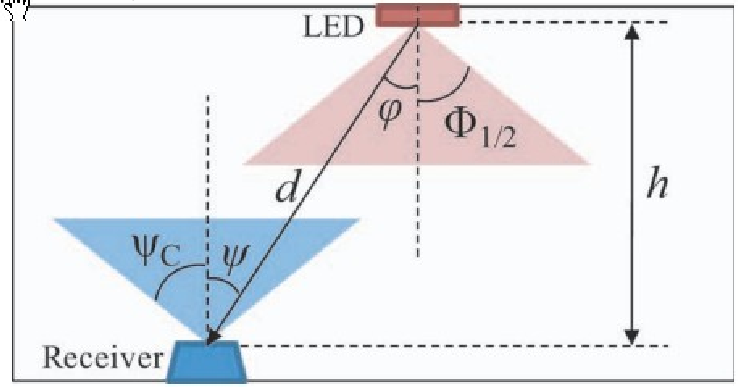
$$B = \begin{bmatrix} d_2^2 - d_1^2 + x_1^2 - x_2^2 + y_1^2 - y_2^2 \\ d_3^2 - d_1^2 + x_1^2 - x_3^2 + y_1^2 - y_3^2 \\ \dots \\ d_n^2 - d_1^2 + x_1^2 - x_n^2 + y_1^2 - y_n^2 \end{bmatrix}$$

visible light positioning (VLP)

- Conditions
  - widespread use of LED for illumination
  - LEDs allow light modulation → VLC (visible light communication)
- VLC + AOA (Angle of Arrival) = VLP
  - AOA is not the only method



J. Armstrong, Y. Sekercioglu, e A. Neild, «Visible light positioning: a roadmap for international standardization», *Communications Magazine, IEEE*, vol. 51, n. 12, pp. 68–73, Dez. 2013.



S.-Y. Jung, S. Hann, S. Park, e C.-S. Park, «Optical wireless indoor positioning system using light emitting diode ceiling lights», *Microwave and Optical Technology Letters*, vol. 54, n. 7, pp. 1622–1626, 2012.

visible light positioning (VLP)

environment perception

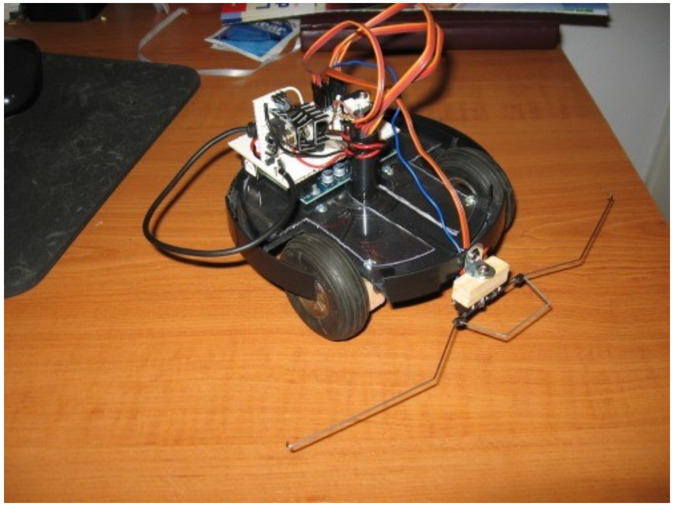
- Obstacle detection
- Mapping
- Targets

Where can I go to?

Where do I want to go to?

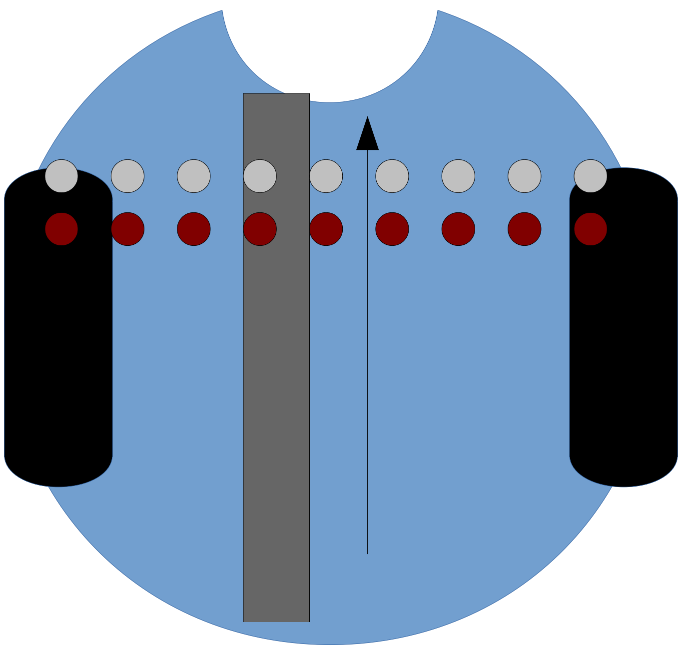
contact sensors

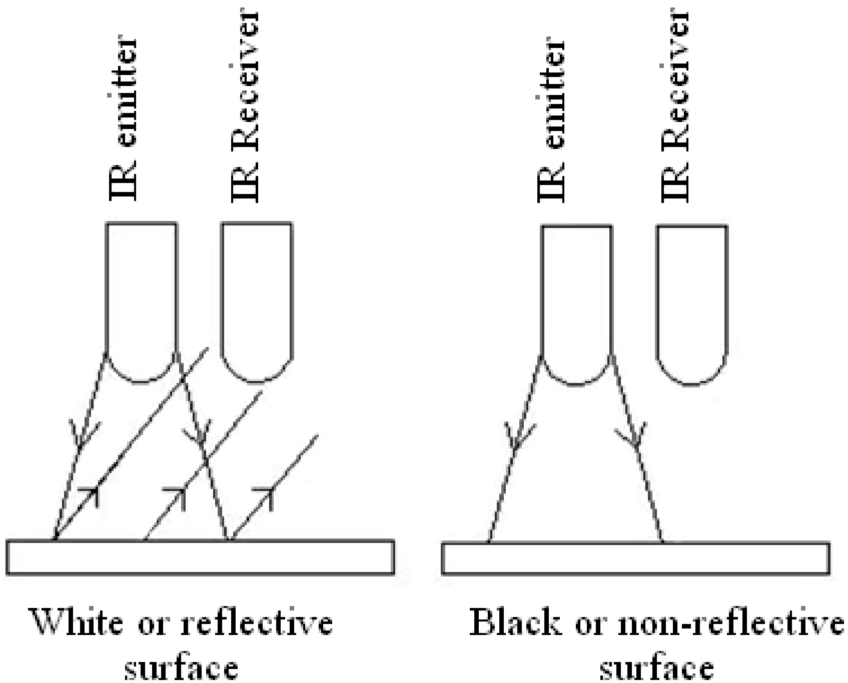
- **mechanically actuated switch**
  - whisker
  - bumper



infra-red

- Reflection on a object
- Detection depends on the object colour
  - can be a plus or a minus



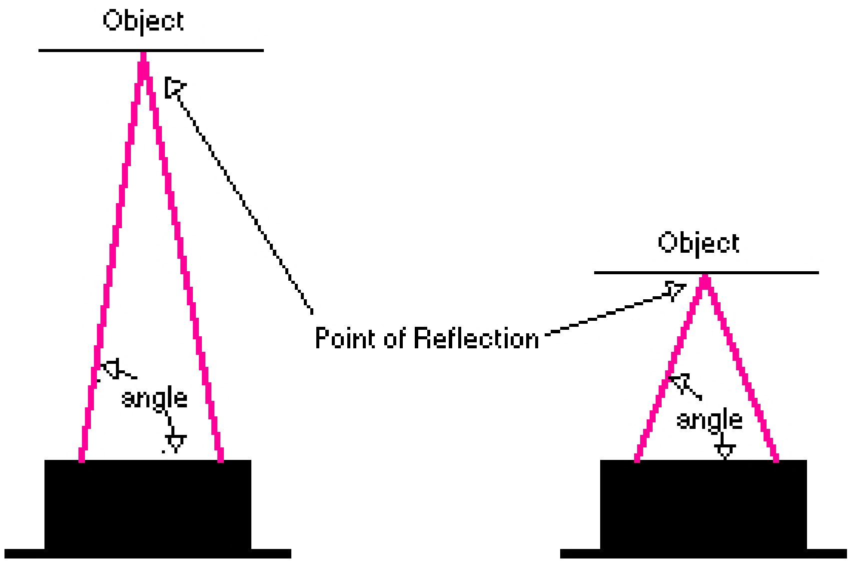


Object is detected

Object is not detected

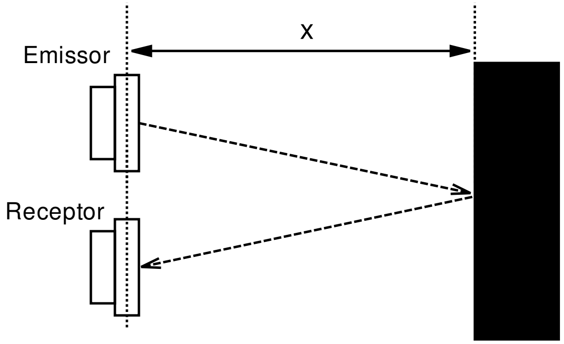
infra-red

- Sharp sensor
  - Distance information



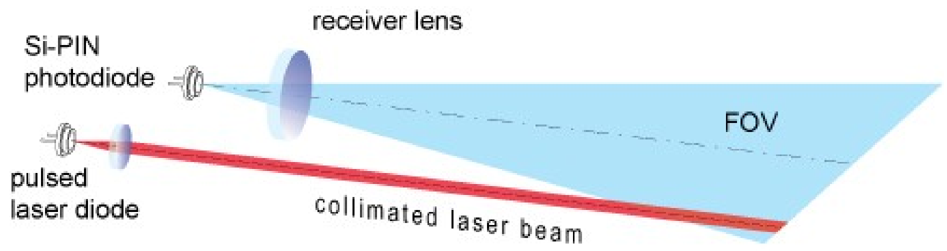
ultra-sound

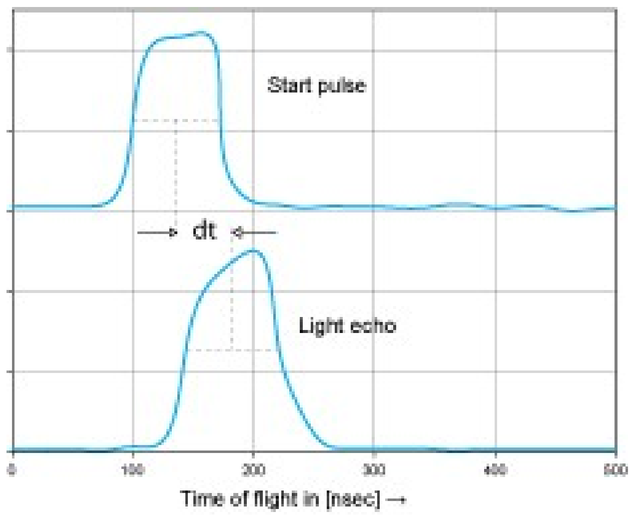
- Detection based on the reflection by an object



Laser range finder

- Laser scans the space ahead or around the robot
- Measuring obstacle distance
  - Limited to the bean working plan
  - Sometimes used with beam oscillation (⊥ to the plan of beam)





Laser range finder

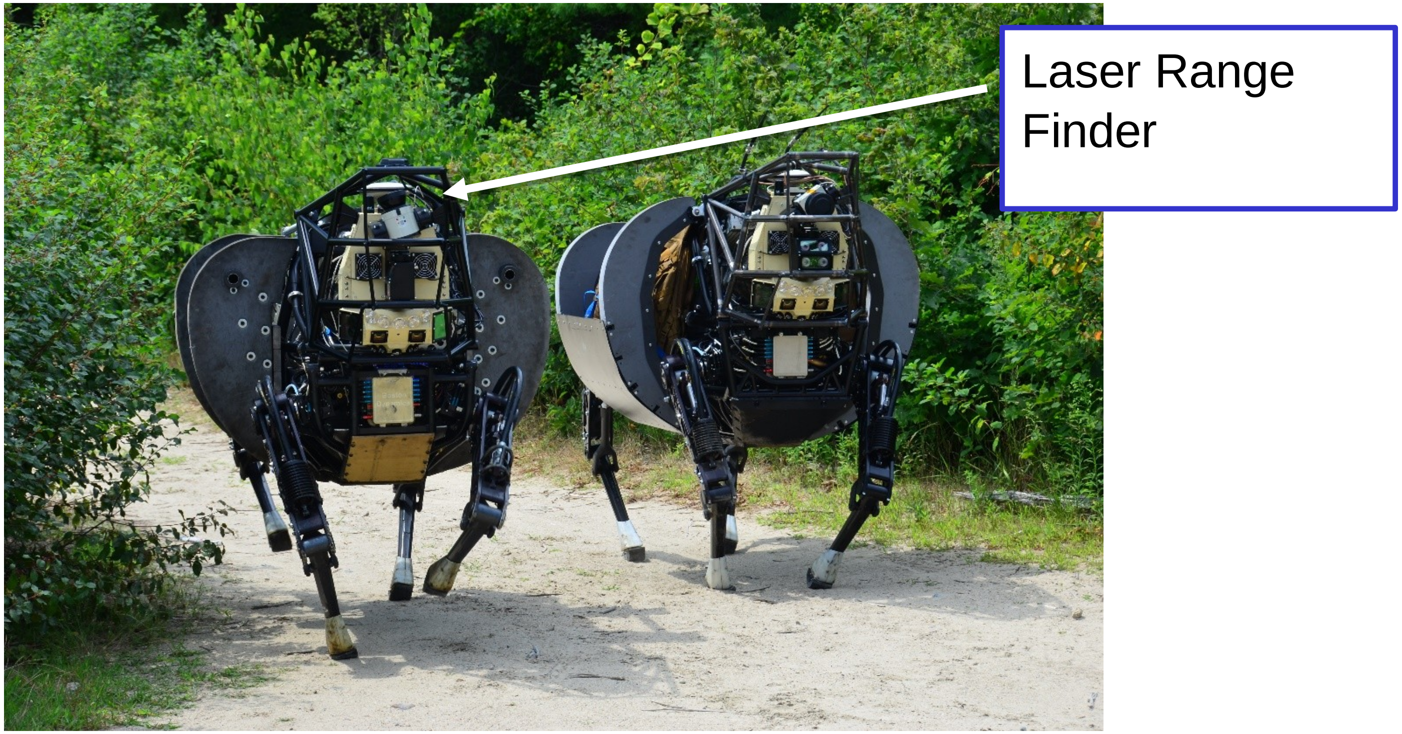
- Image of Sick’s LRF software application

Mapa of IEETA's building level 0 do IEETA, obtained by LRF scanning

LS3 – Legged Squad Support System

- The LS3 (Legged Squad Support System) is an example of a robot using LRF.
  - For example, in the YouTube video, at 1:17 you can clearly see the LFR oscillating to create a 3D perception of space ahead.

    http://youtu.be/R7ezXBEBE6U?t=1m17s



sensor classification

- Proprioceptive / exteroceptive
  - Proprioceptive information internal to the robot.
    - Ex: motor speed, battery voltage, ...
  - Exteroceptive: external information to the robot
    - Ex .: distance to objects, light intensity
- Passive / Active
  - Passive: have no explicit source of energy; energy required comes from the measurement process itself
    - Ex temperature probes .:
  - Active: have internal power source, necessary for the measurement process; uses that energy to interact with the environment
    - Ex .: laser range finder

Classification	Sensor	PC/EC	A/P
Tactile Sensors	Switches	EC	P
	Optical barrier	EC	A
	Contactless proximity sensors	EC	A
Wheels and motors	Potentiometers	PC	P
	Synchros and resolvers	PC	A
	Optical encoders	PC	A
Orientation	Compass	EC	P
	Gyroscope	PC	P
	Inclinometer	EC	A/P
Localization	GPS	EC	A
	RF beacons	EC	A
	Reflected beams	EC	A
Ranging	Sensores ultrassons	EC	A
	Laser Range Finder	EC	A
	Optical triangulation	EC	A
Visão	CCD/CMOS cameras	EC	P

R. Siegwart e I. R. Nourbakhsh, *Introduction to autonomous mobile robots*. Cambridge Mass.: MIT Press, 2004.

Challenge

- Think of a mobile robot mission
- Devise the sensor structure required for that mission
  - What sensors will the robot need?