

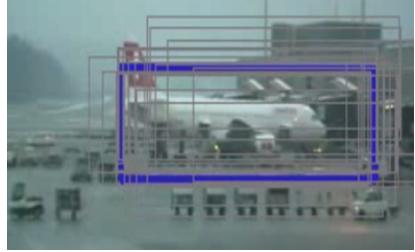
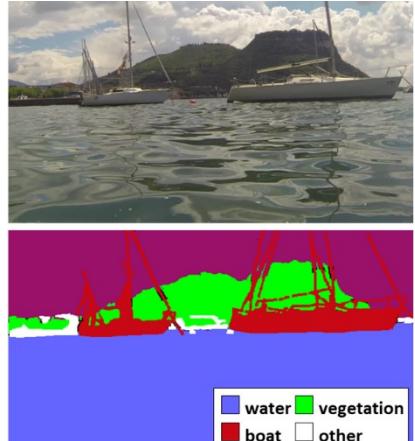
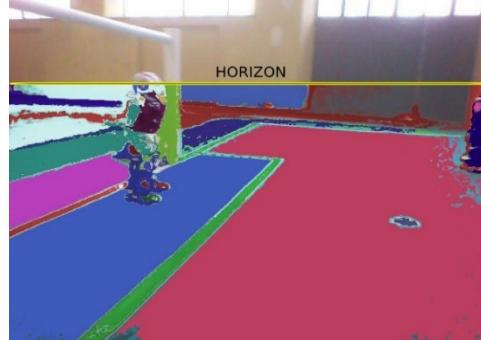


**UNIVERSITÀ DEGLI STUDI  
DELLA BASILICATA**

*Corso di Sistemi Informativi*  
A.A. 2018/19

# Navigazione in ROS

Maggio 2019



# References and credits

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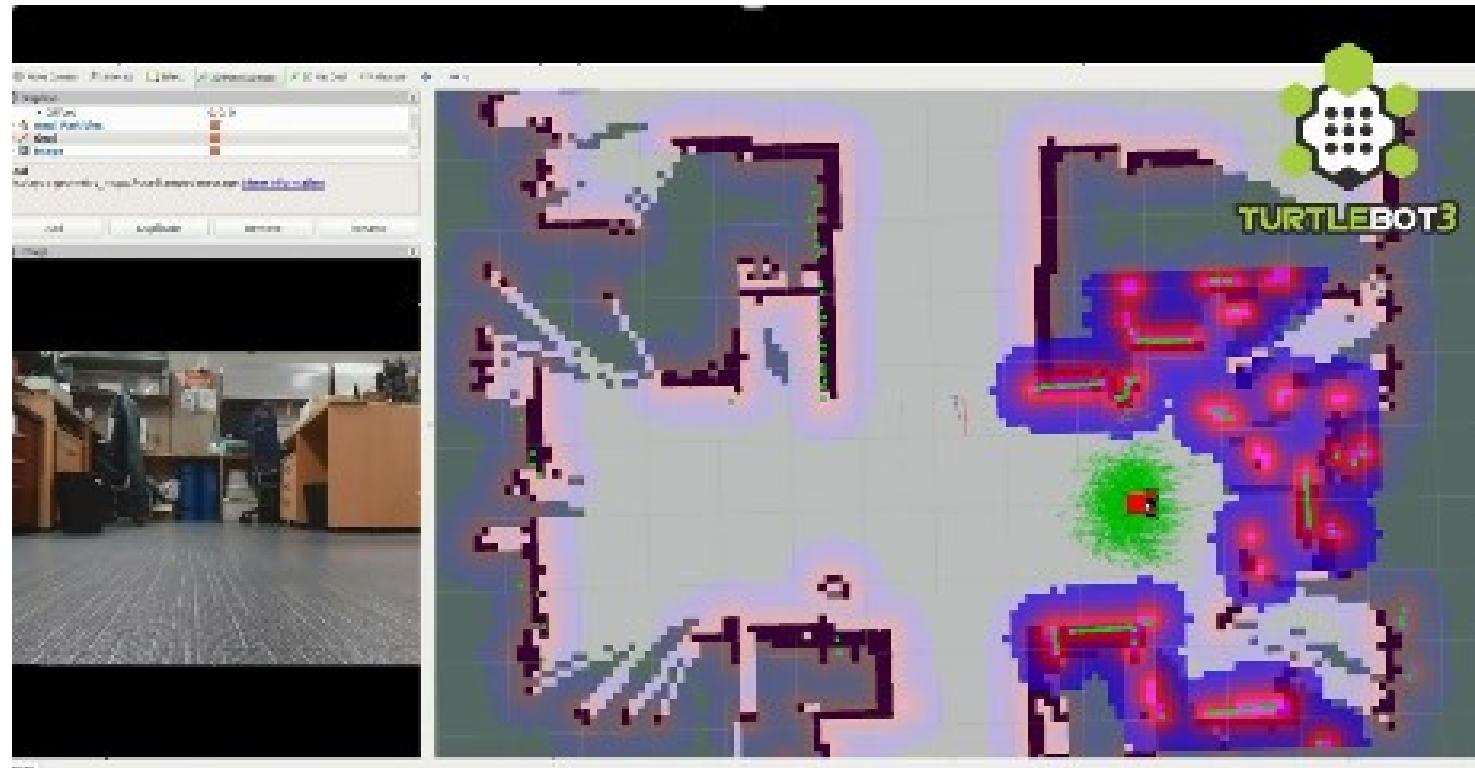
Alcune delle slide seguenti sono tratte da

- ❖ Giorgio Grisetti, “*Introduction to Navigation using ROS*”
- ❖ Giorgio Grisetti, “*Introduction*” in Probabilistic Robotics Course
- ❖ Giorgio Grisetti, “*Multi-Pose Registration Graph-SLAM*” in Probabilistic Robotics Course
- ❖ YoonSeok Pyo, HanCheol Cho, RyuWoon Jung, TaeHoon Lim,  
“*ROS Robot Programming - A Handbook Written by TurtleBot3 Developers*”  
<http://www.robotis.com/service/download.php?no=719>
- ❖ Learn TurtleBot and ROS (<http://learn.turtlebot.com/>)
  - Creating a Map
  - Autonomous Navigation

# Navigazione con robot mobili

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Il principale task che un robot autonomo mobile deve essere in grado di compiere è quello di saper muoversi nell'ambiente operativo



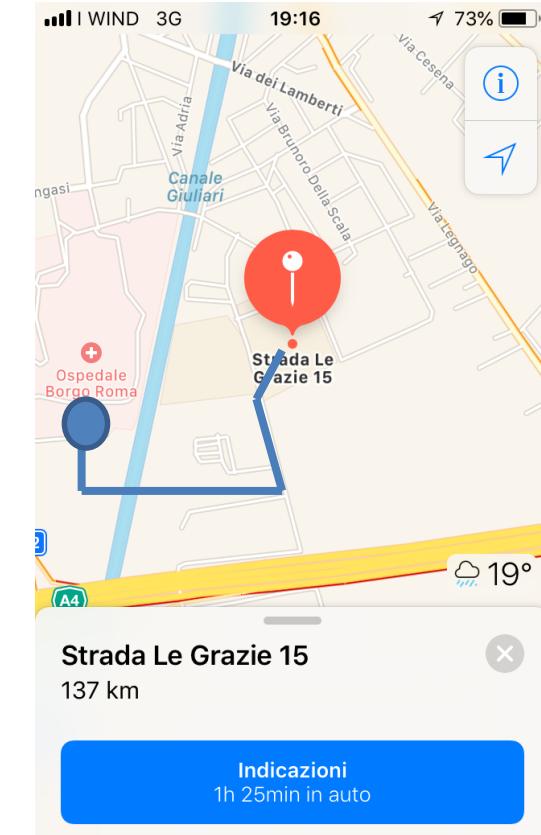
<https://www.youtube.com/watch?v=lOZmFC79S6A>

# Navigazione GPS

Il navigatore, che utilizziamo nella vita di tutti i giorni, ci fornisce tre elementi di base:

1. una **mappa**
2. la nostra **posizione** sulla mappa
3. una **rotta** per la destinazione desiderata

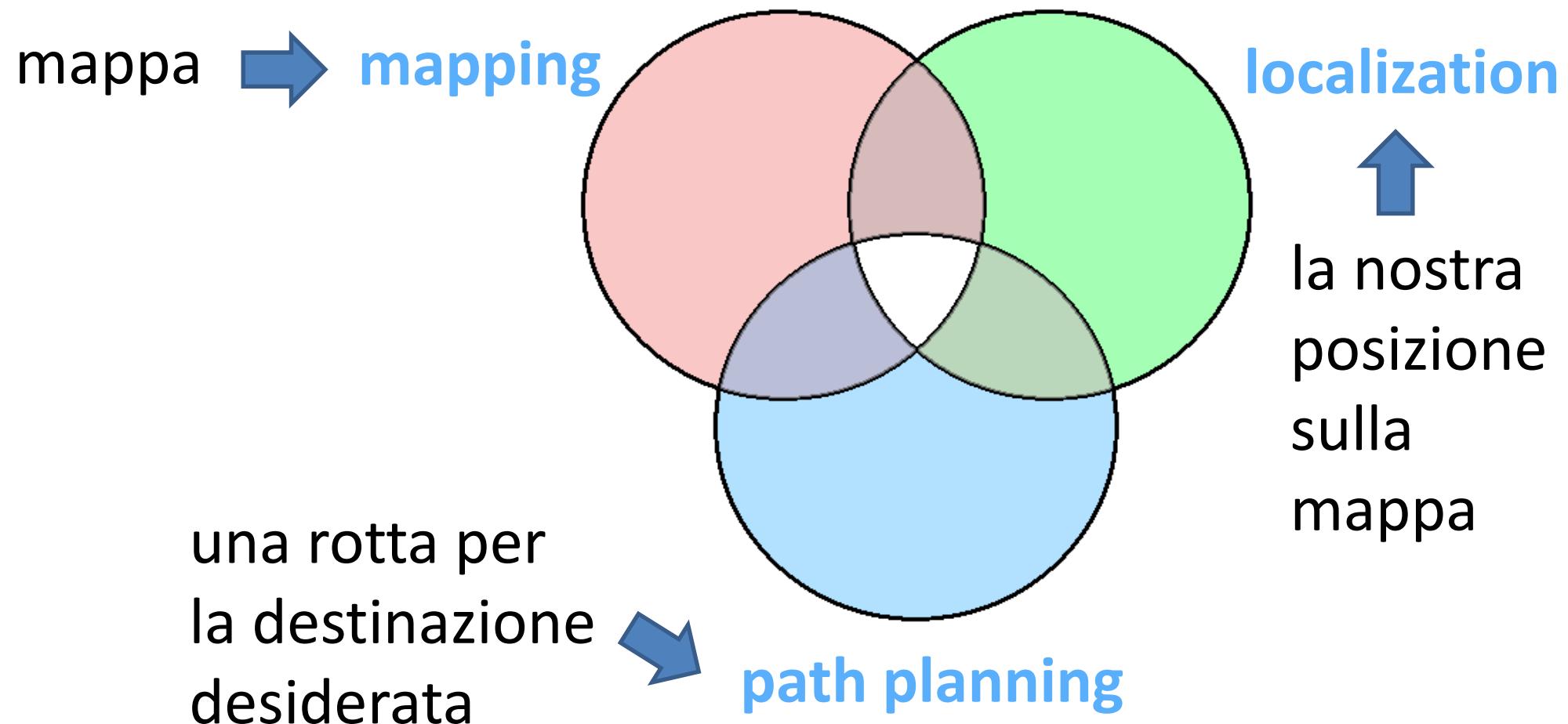
Questi tre elementi sono necessari per muoversi con successo nell'ambiente



Sono sufficienti?

# Mapping, localization, planning

---



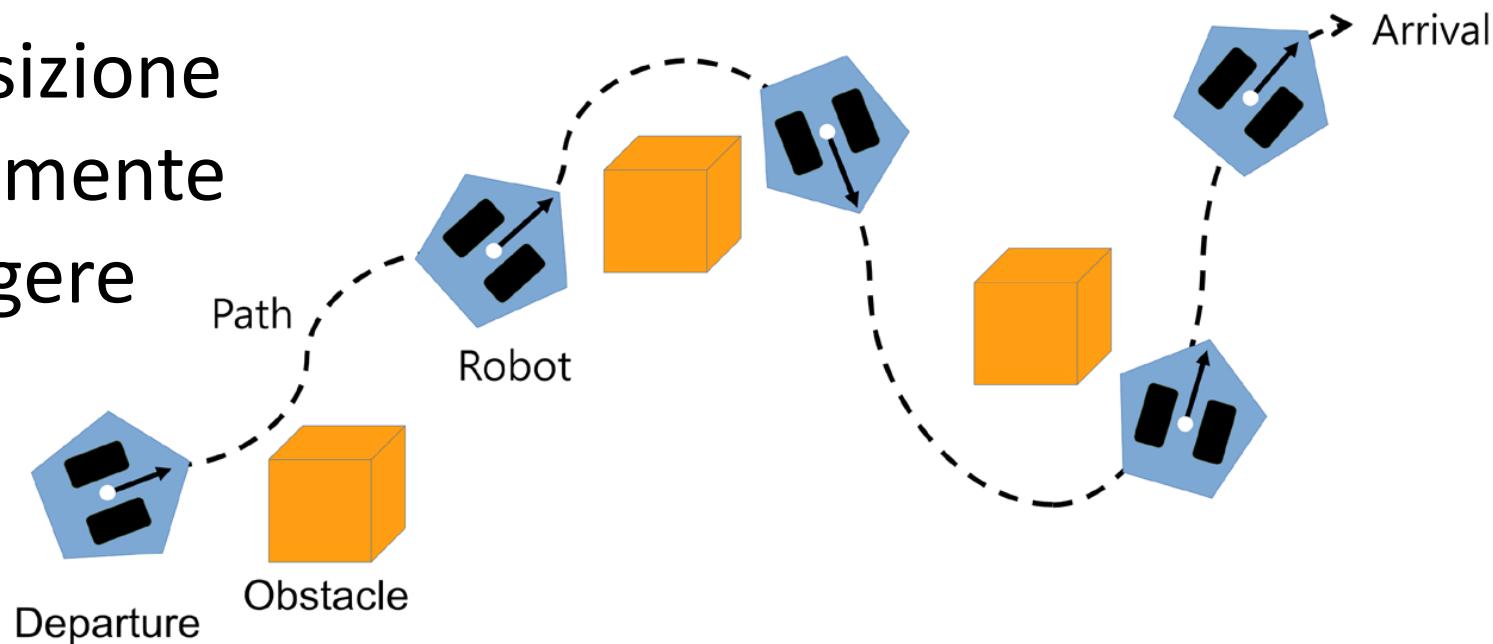
# Navigation

---

Con il termine **navigation** indichiamo il movimento del robot verso una destinazione predefinita

Per poter navigare, un robot ha bisogno di:

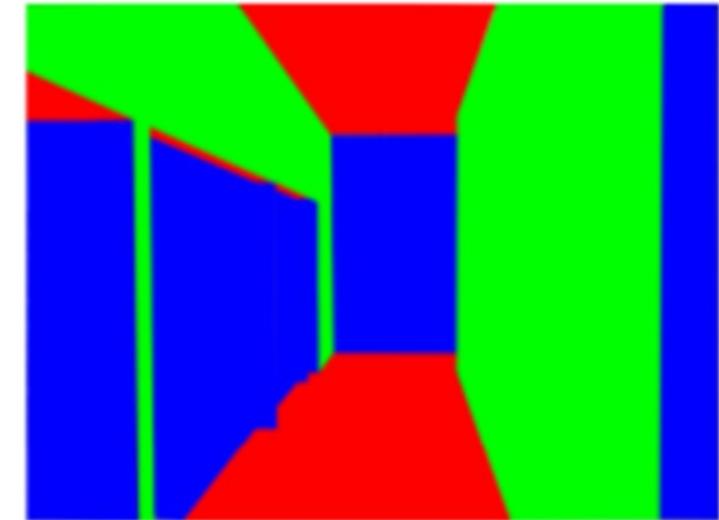
- Avere una mappa dell'ambiente
- Conoscere la propria posizione
- Avere una rotta (possibilmente ottimizzata) per raggiungere la destinazione
- **Evitare gli ostacoli presenti sul percorso**



# Ambiente

---

Strutturato



Non strutturato



# Ostacoli fissi e mobili

---

In base all'ambiente operativo in cui il robot si trova ad agire, si avranno

- ❑ **ostacoli fissi**

muri e scale sono esempi di ostacoli fissi

- ❑ **ostacoli mobili**

persone e sedie sono esempi di ostacoli mobili

# Basic features

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Affinché il robot sia in grado di navigare autonomamente nell'ambiente, avremo bisogno di

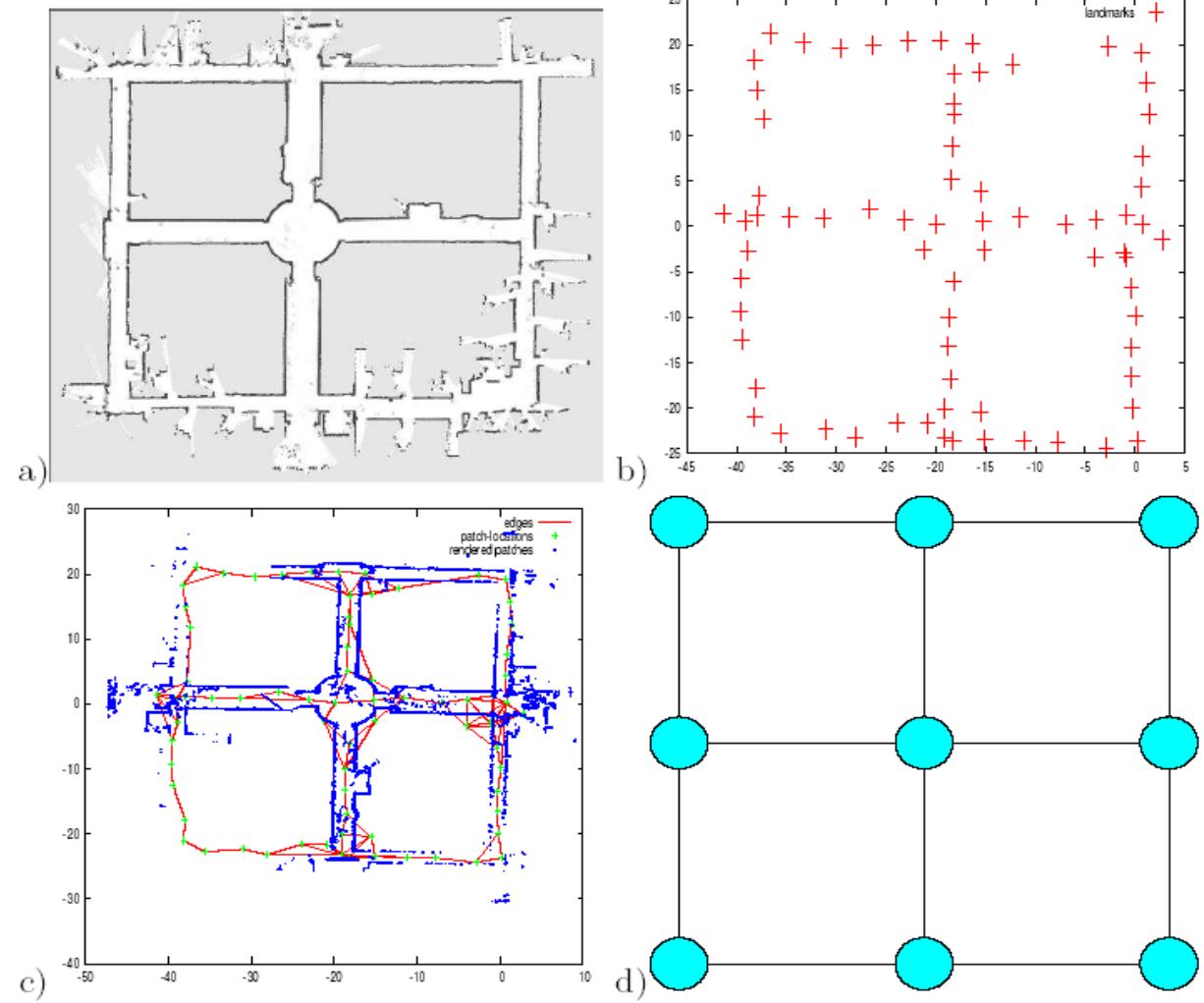
- ① Map
- ② Pose of Robot
- ③ Sensing
- ④ Path Calculation and Driving

# Map

- A map is a representation of the environment where the robot is operating
- It should contain enough information to accomplish a task of interest

Representations:

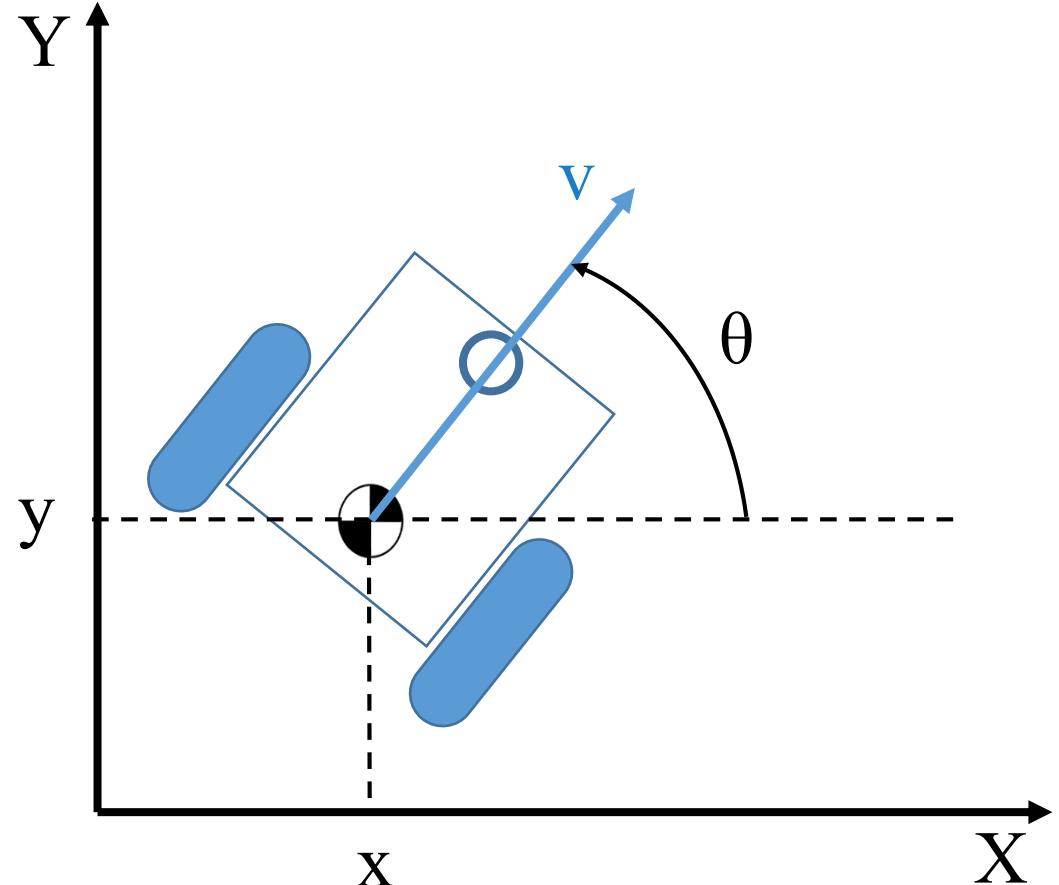
- Metric
  - Grid Based
  - Feature Based
  - Hybrid
- Topological
- Hybrid



# Robot pose

---

- La *robot pose* è definita come la posizione del robot e la sua orientazione in un dato sistema di riferimento
- Per un robot mobile che si muove su un piano, la *pose* è definita dalla tripla  $[x, y, \theta]$



# Pose in ROS

---

## [geometry\\_msgs/Pose Message](#)

---

File: [geometry\\_msgs/Pose.msg](#)

### Raw Message Definition

```
# A representation of pose in free space, composed of position and orientation.  
Point position  
Quaternion orientation
```

### Compact Message Definition

```
geometry_msgs/Point position  
geometry_msgs/Quaternion orientation
```

# Position in ROS

---

pose = position + orientation



**geometry\_msgs/Point Message**

---

File: **geometry\_msgs/Point.msg**

Raw Message Definition

```
# This contains the position of a point in free space
float64 x
float64 y
float64 z
```

Compact Message Definition

```
float64 x
float64 y
float64 z
```

# Orientation in ROS

---

pose = position + orientation

**geometry\_msgs/Quaternion Message**

File: **geometry\_msgs/Quaternion.msg**

**Raw Message Definition**

```
# This represents an orientation in free space in quaternion form.  
  
float64 x  
float64 y  
float64 z  
float64 w
```

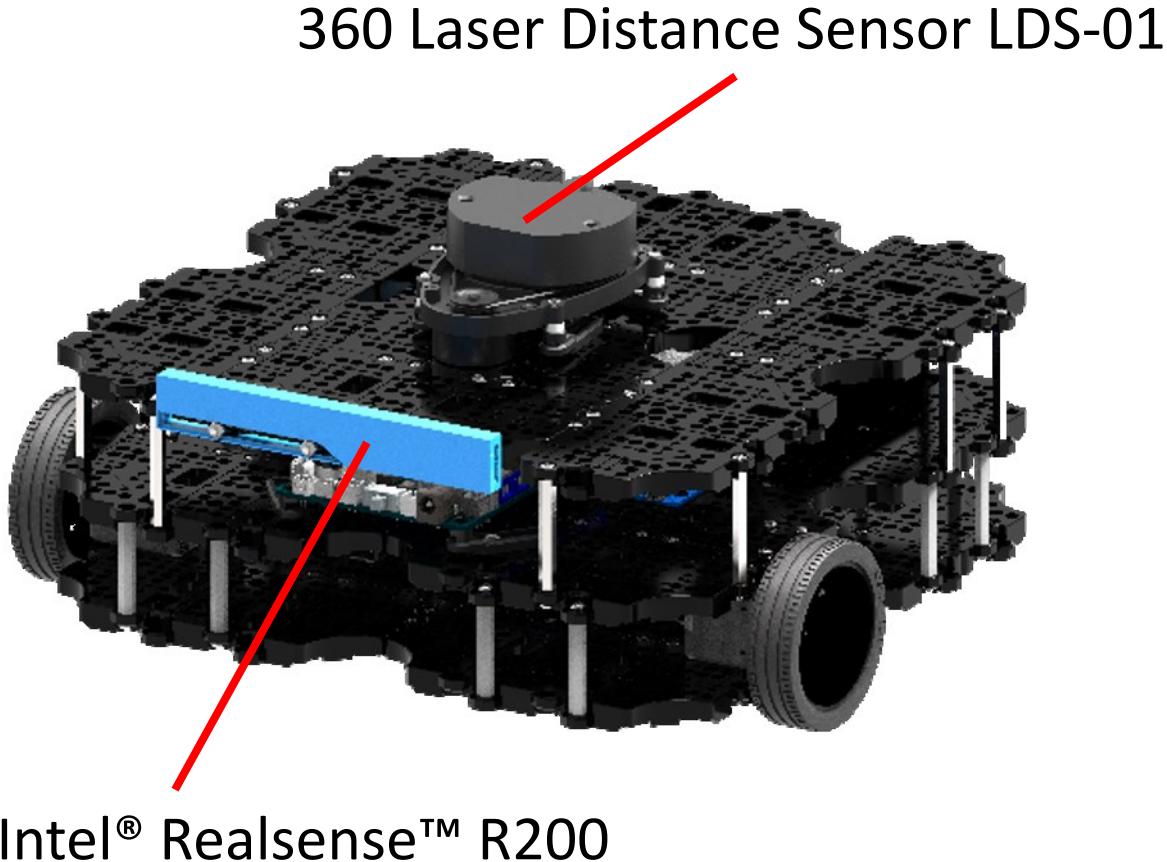
**Compact Message Definition**

```
float64 x  
float64 y  
float64 z  
float64 w
```

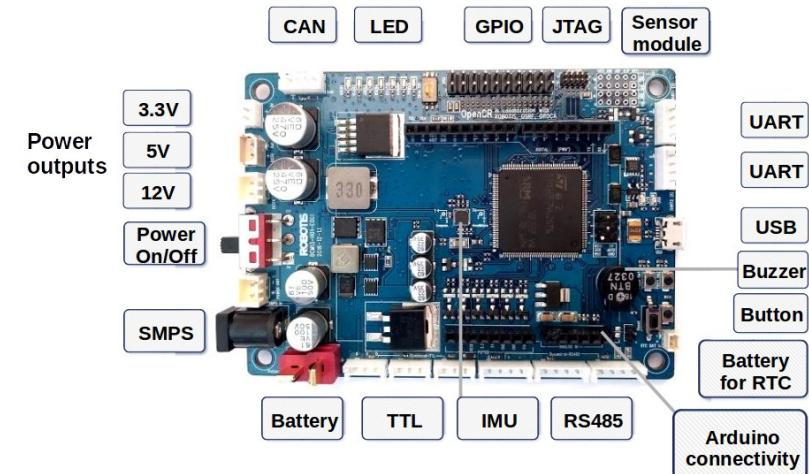
<http://wiki.ros.org/tf2/Tutorials/Quaternions>

<http://run.usc.edu/cs520-s12/quaternions/quaternions-cs520.pdf>

# Sensing – Turtlebot3



OpenCR1.0



Gyroscope 3Axis, Accelerometer 3Axis,  
Magnetometer 3Axis

# Sensori di distanza

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- Sonar
- Laser range finder
- Time of Flight Camera



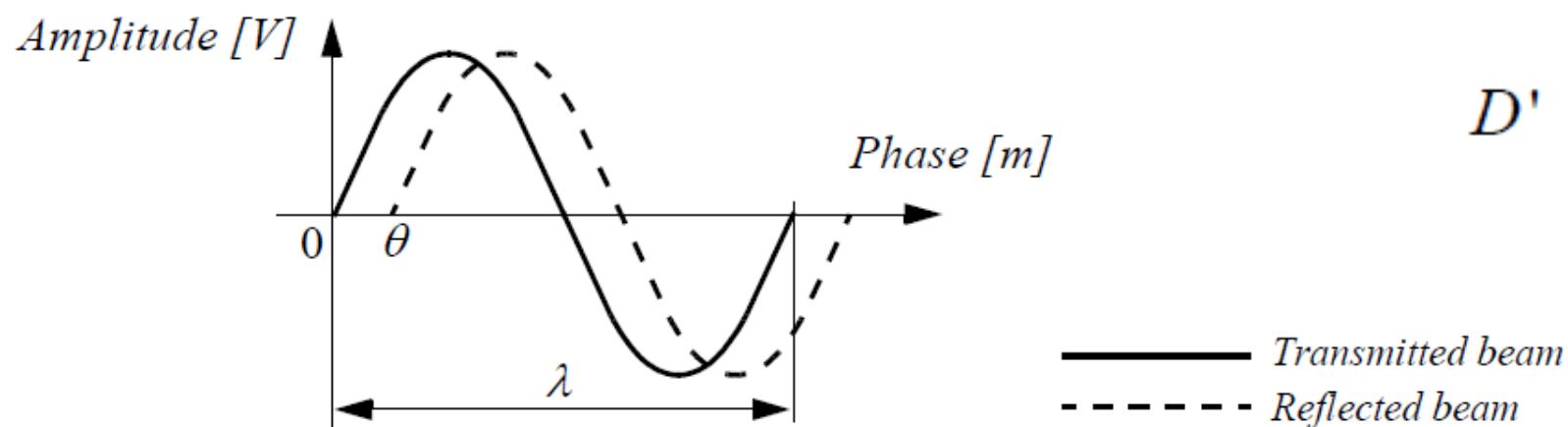
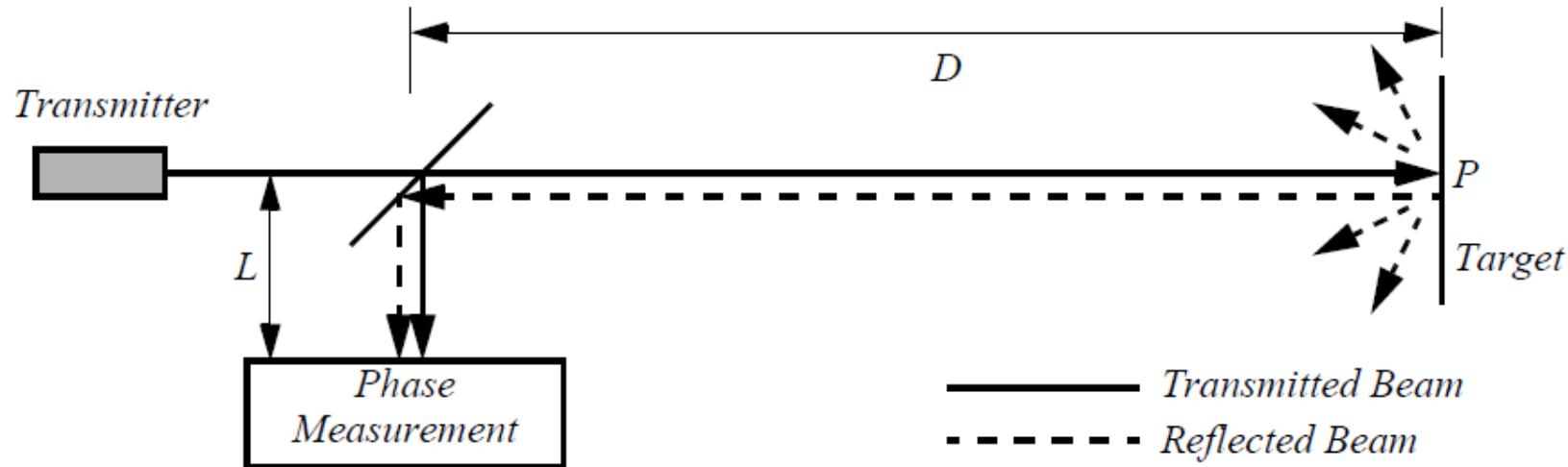
I sensori di distanza basati sul time-of-flight sfruttano la velocità di propagazione del suono o delle onde elettromagnetiche per calcolare la distanza



KINECT  
for XBOX 360

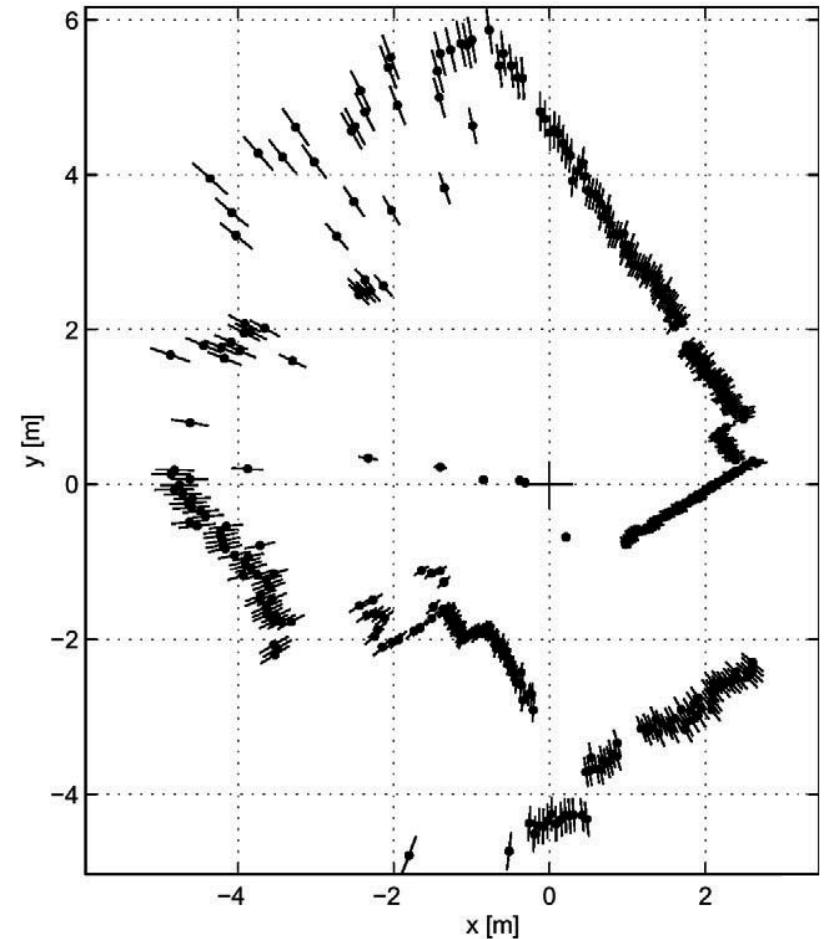
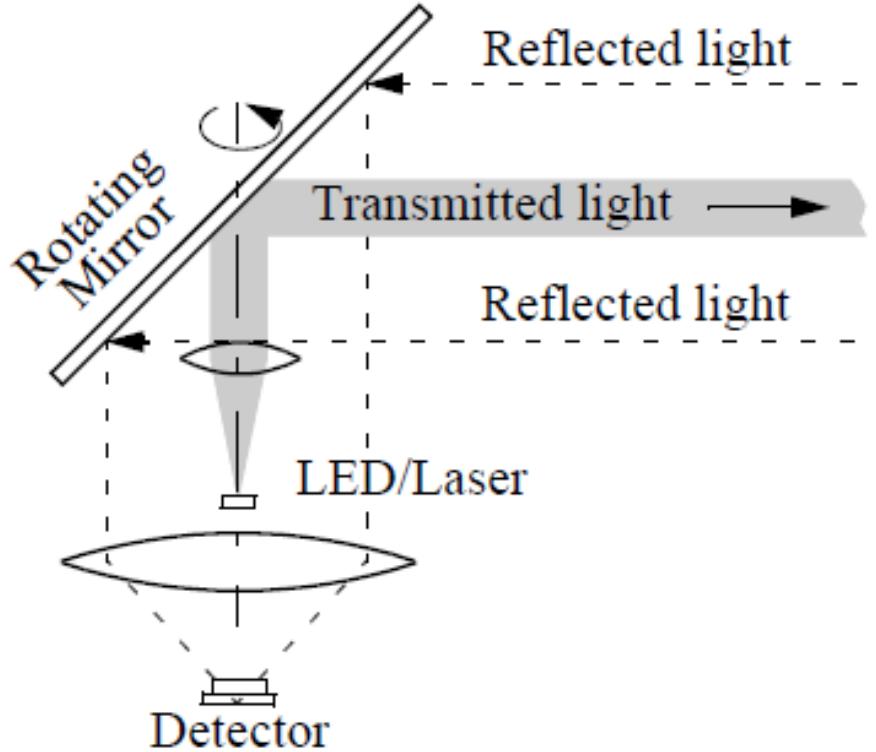


# Laser Range Finder



$$D' = L + 2D = L + \frac{\theta}{2\pi}\lambda$$

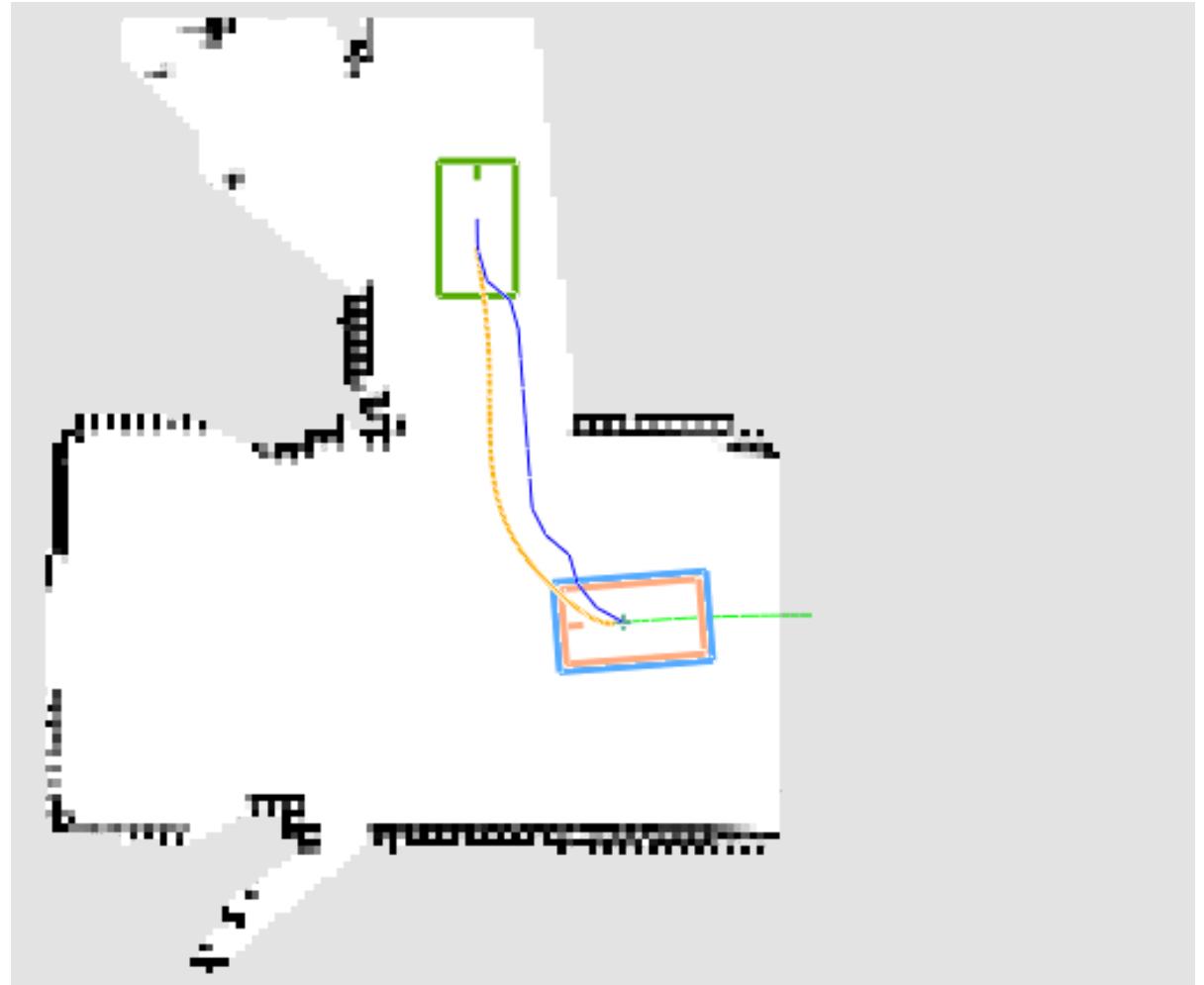
# Laser range sensor with rotating mirror



# Path

---

- A metric map defines a **reference frame**
- To operate in a map, a robot should know its position in that reference frame
- A sequence of **waypoints** or of actions to reach a goal location in the map is a **path**



# Mapping

---

Mapping Problem.

Given

1. a robot that has a perfect ego-estimate of the position
2. a sequence of measurements

Determine the map of the environment

However,

- a perfect estimate of the robot pose is usually not available



Usually, we solve a more complex problem:

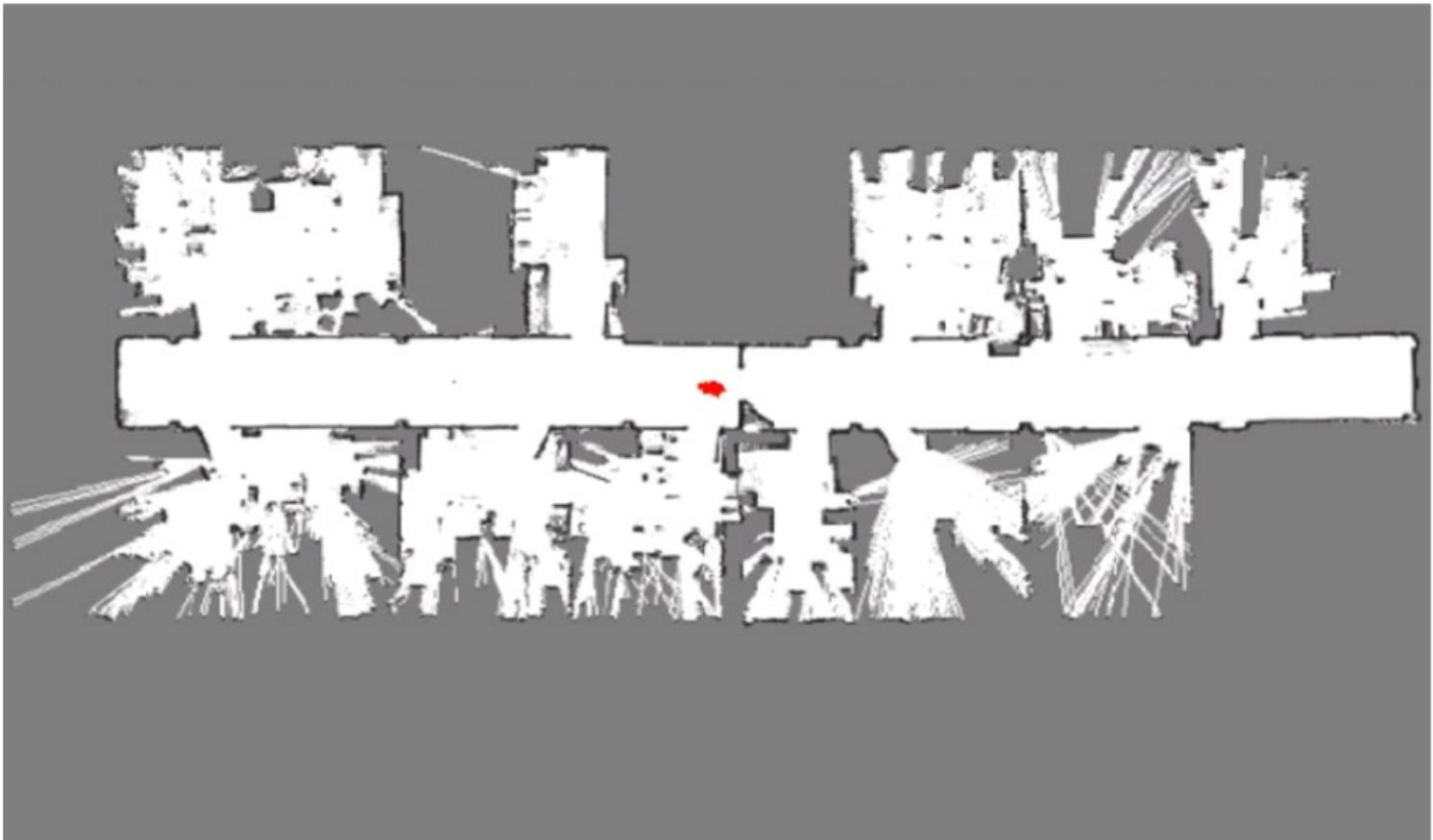
**Simultaneous Localization and Mapping (SLAM)**

# Localization

---

Determining the current position of a robot, given

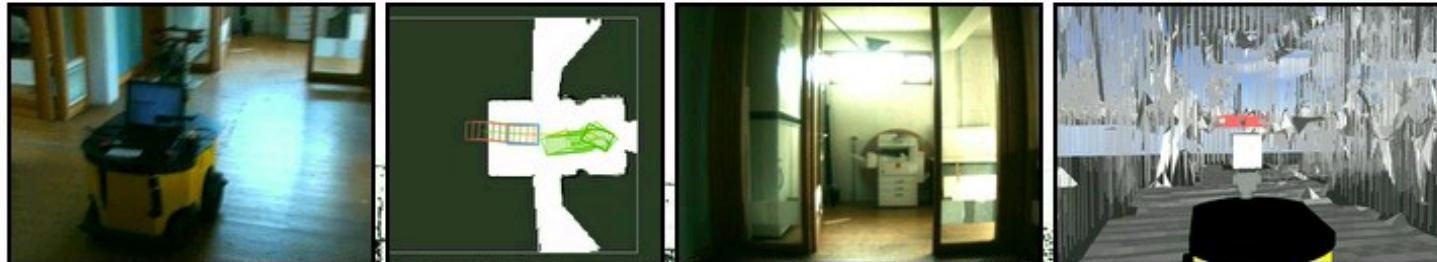
1. The knowledge of the map
2. All sensor measurements up to the current time



# Path planning

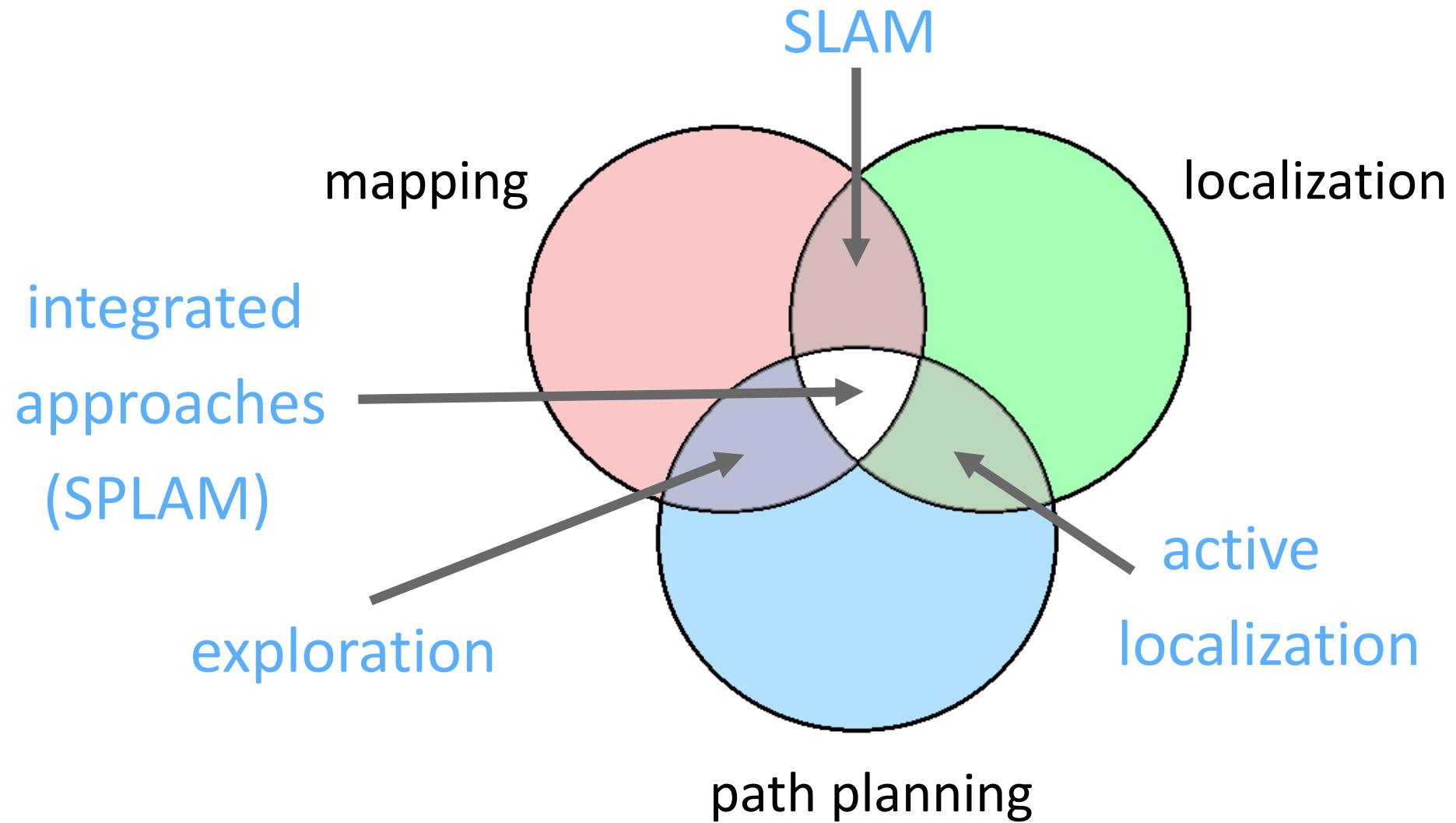
---

Determine (if it exists) a path to reach a given goal location given a localized robot and a map of **traversable** regions



# Mapping, localization, planning

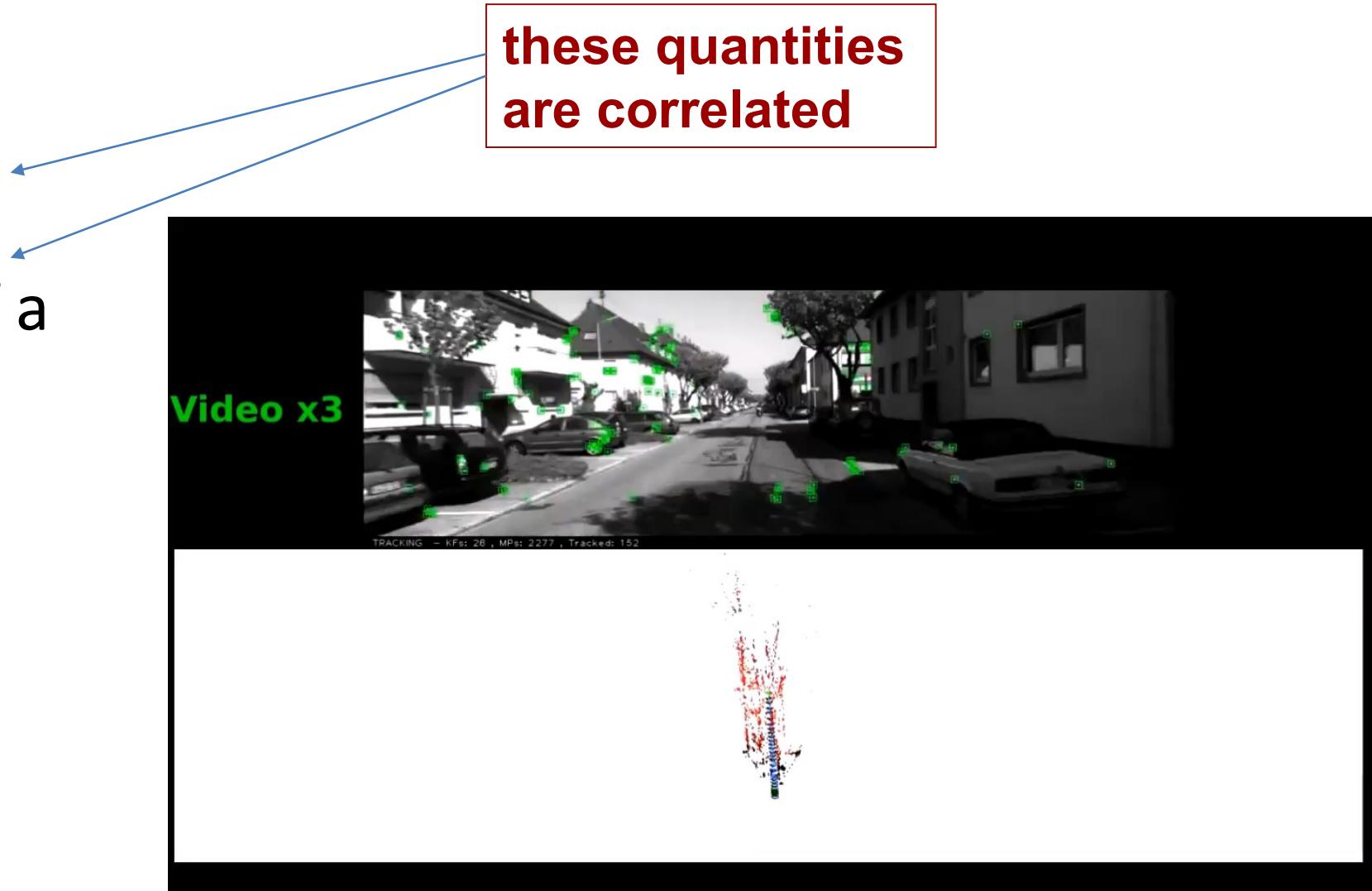
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# Simultaneous Localization and Mapping

Estimate:

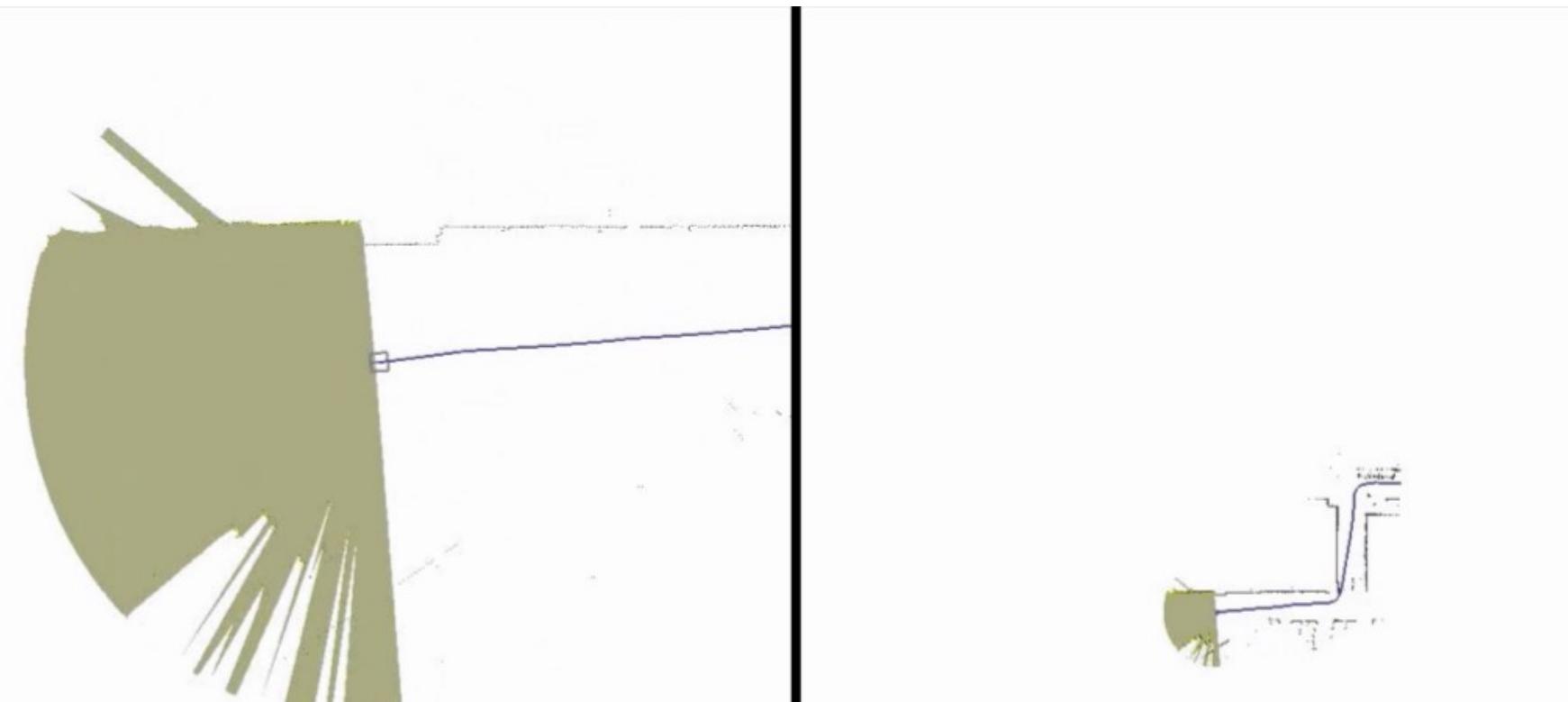
1. the map of the environment
  2. the trajectory of a moving device
- using a sequence of sensor measurements



# SLAM

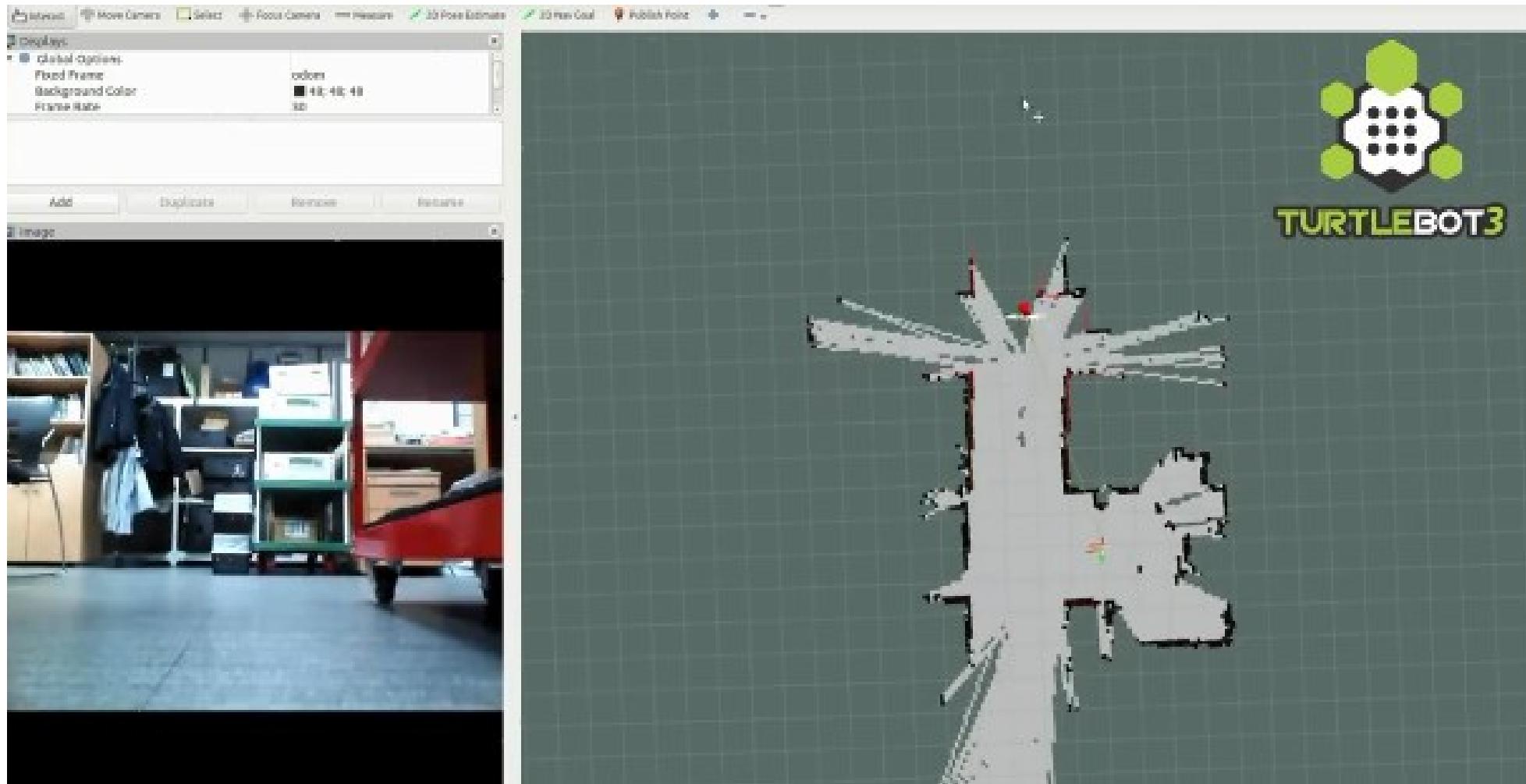
---

Determine the robot position **AND** the map,  
based on the sensor measurements



# SLAM – Turtlebot3

---



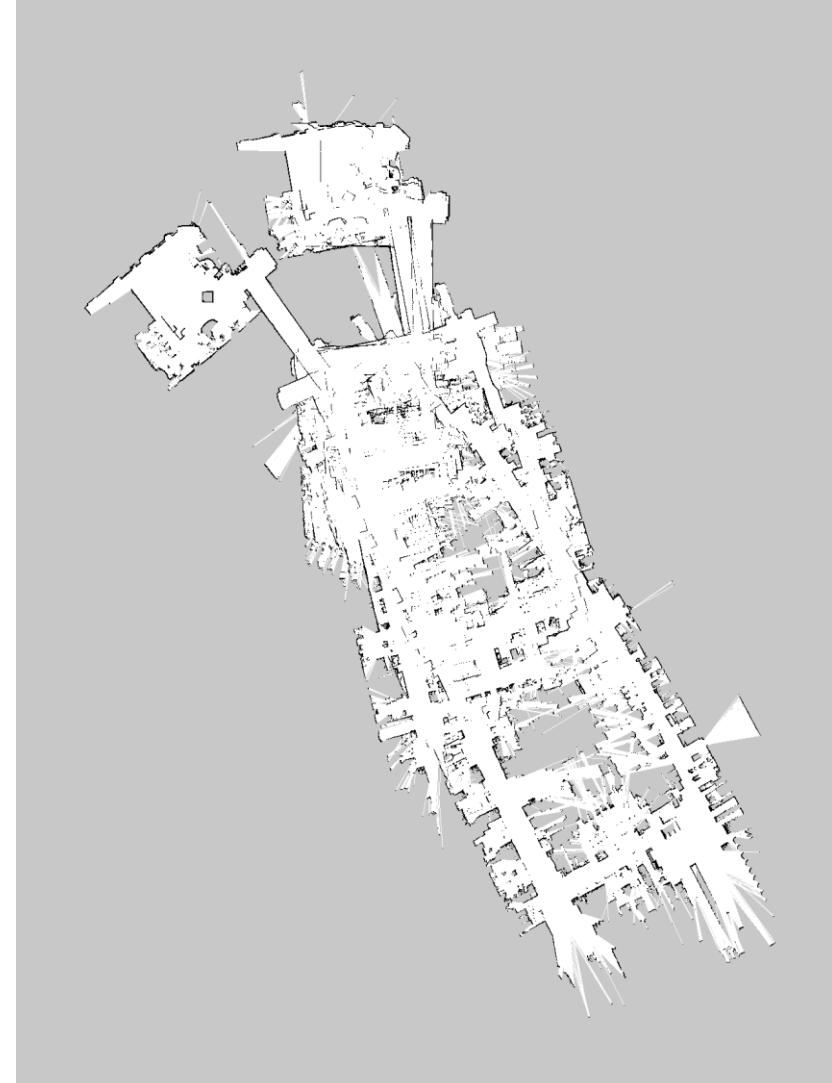
<https://www.youtube.com/watch?v=hX6pFcfr29c>

# Graph-based SLAM

---

Problem described as  
a graph

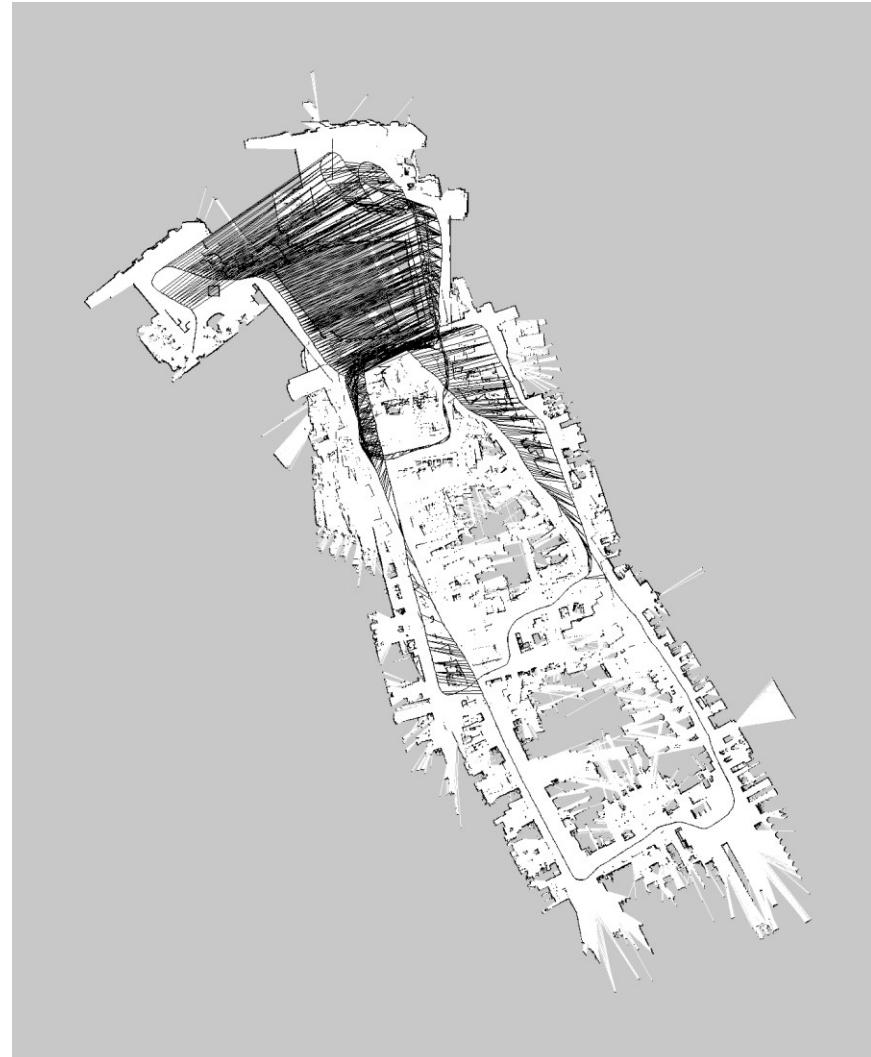
Every node  
corresponds to a robot  
position and to a laser  
measurement



# Graph-based SLAM

---

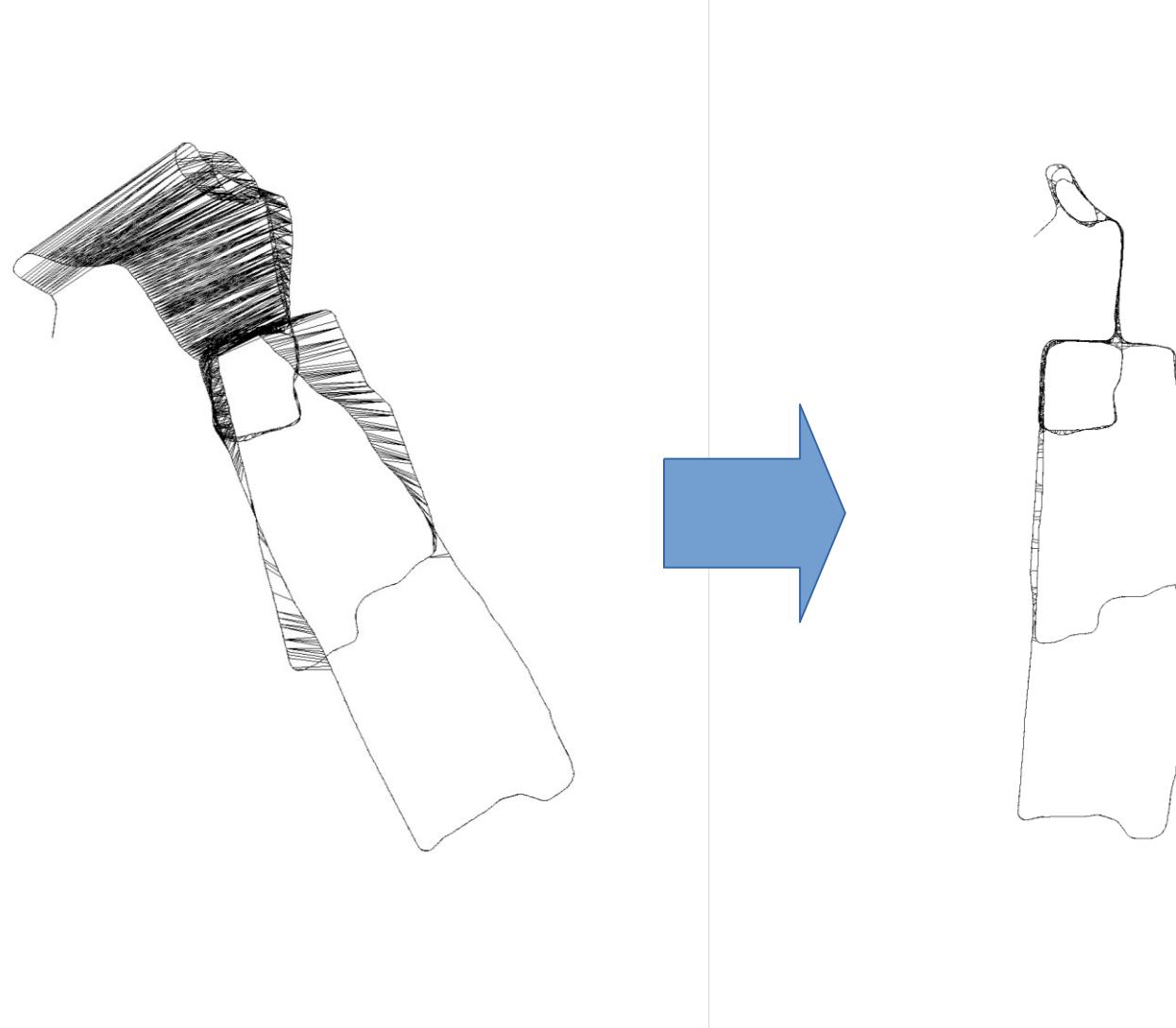
An edge between two nodes represents a data-dependent spatial constraint between the nodes



# Graph-based SLAM

---

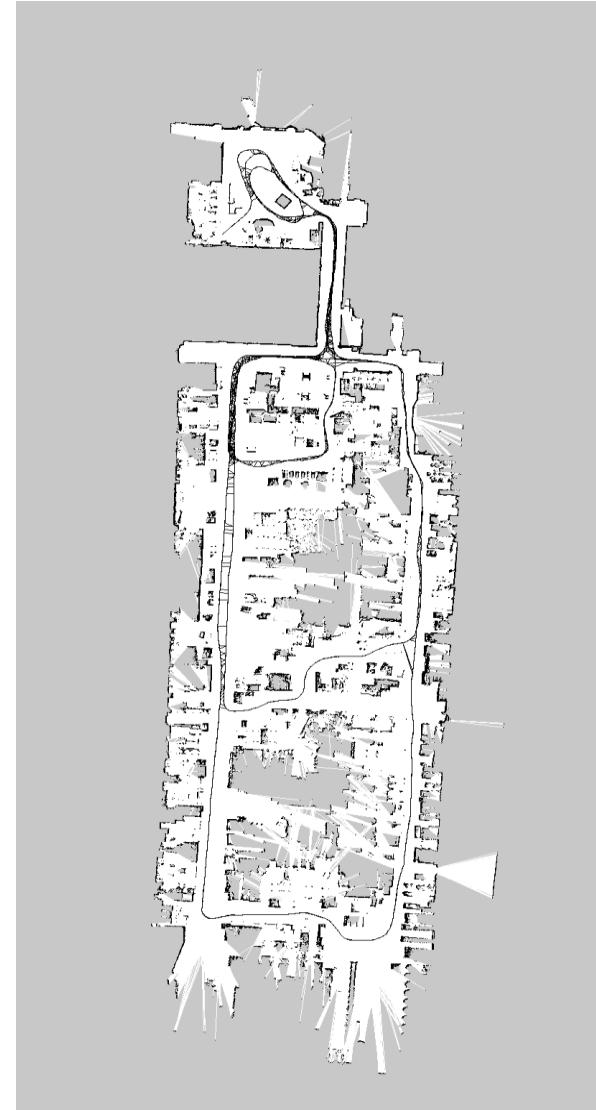
Once we have the graph we determine the most likely map by “moving” the nodes



# Graph-based SLAM

---

Then, we can render a map based on the known poses

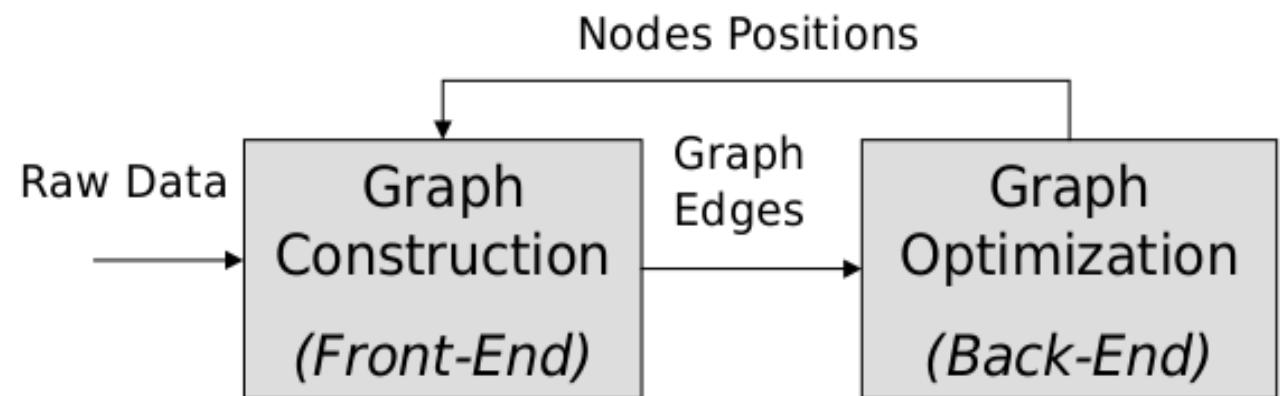


# Graph optimization

---

A general Graph-based SLAM algorithm interleaves the two steps

1. Graph construction
2. Graph optimization

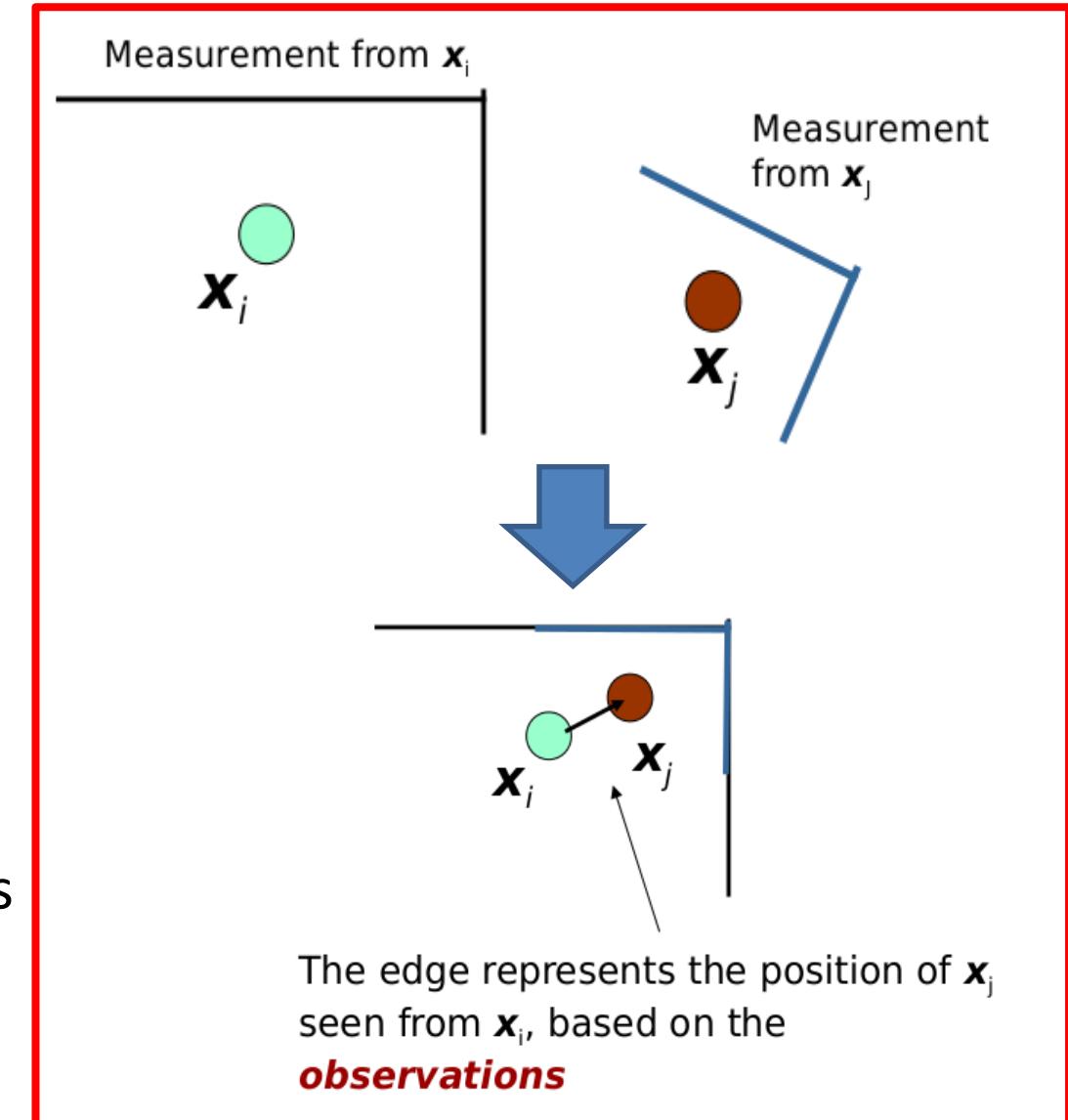


# What Does the Graph Look Like?

Each node  $x_i$  is a 2D or 3D transformation representing the pose of the robot at time  $t_i$

There is a constraint  $e_{ij}$  between the node  $x_i$  and the node  $x_j$  if

- either
  - the robot observed the same part of the environment from both  $x_i$  and  $x_j$  and, via this common observation, it constructs a “virtual measurement” about the position of  $x_j$**
- or
  - the positions are subsequent in time and there is an odometry measurement between the two

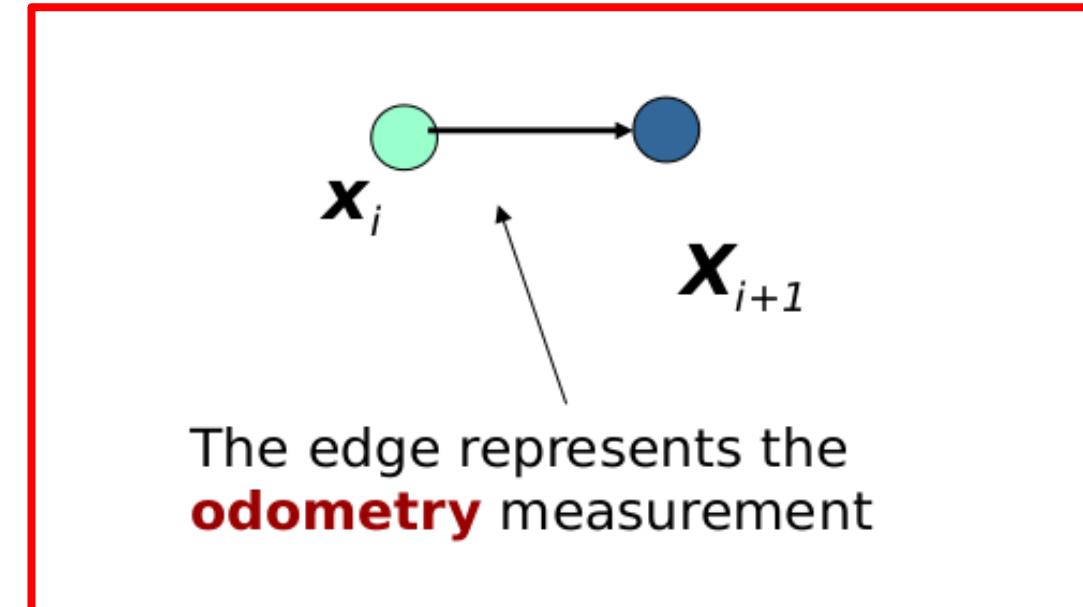


# What Does the Graph Look Like?

Each node  $x_i$  is a 2D or 3D transformation representing the pose of the robot at time  $t_i$

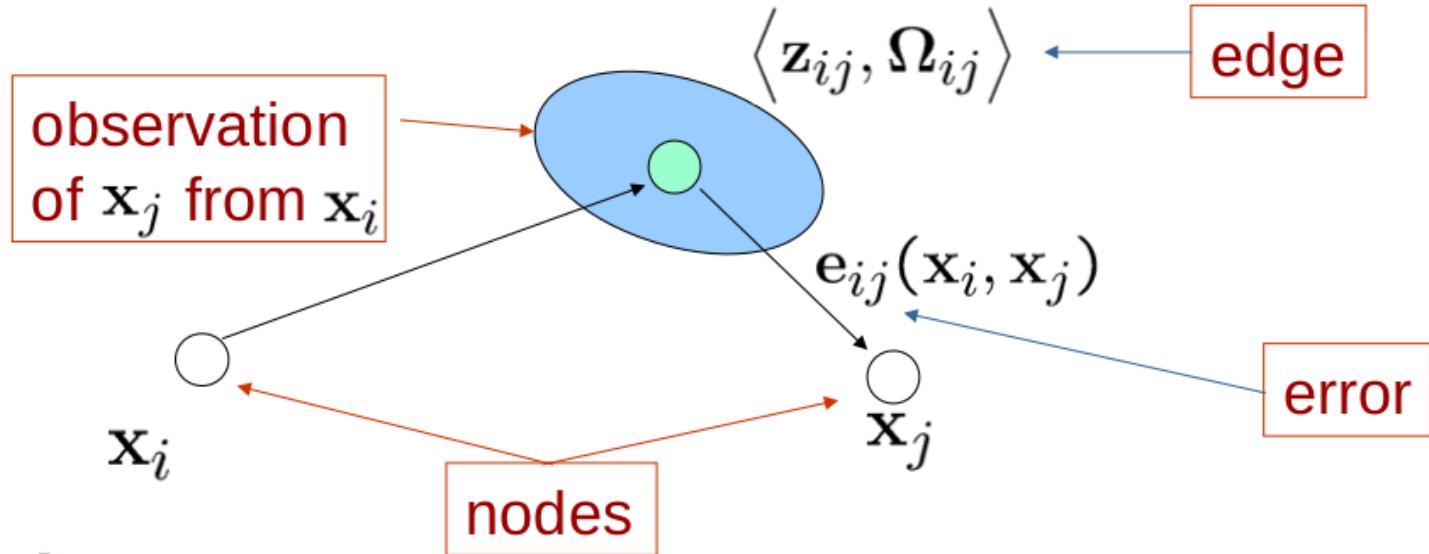
There is a constraint  $e_{ij}$  between the node  $x_i$  and the node  $x_j$  if

- either
  - the robot observed the same part of the environment from both  $x_i$  and  $x_j$  and, via this common observation, it constructs a “virtual measurement” about the position of  $x_j$
- or
  - the positions are subsequent in time and there is an odometry measurement between the two**



# Pose graph

- The input for the optimization procedure is a graph annotated as follows:



- Goal:**

- Find the assignment of poses to the nodes of the graph which minimizes the negative log likelihood of the observations:

$$\hat{\mathbf{x}} = \operatorname{argmin} \sum_{ij} \mathbf{e}_{ij}^T \boldsymbol{\Omega}_{ij} \mathbf{e}_{ij}$$

$z_{ij}$  is a measurement of the robot pose  $j$ , performed from robot pose  $i$

$\boldsymbol{\Omega}_{ij}$  is a matrix to encode the uncertainty of the edge

# Getting started - Navigation

---

To navigate a robot we need

1. a map
2. a localization module
3. a path planning module

These components are sufficient if

- ✓ the map fully reflects the environment
- ✓ the environment is static
- ✓ there are no errors in the estimate

# Getting started - Navigation

---

However

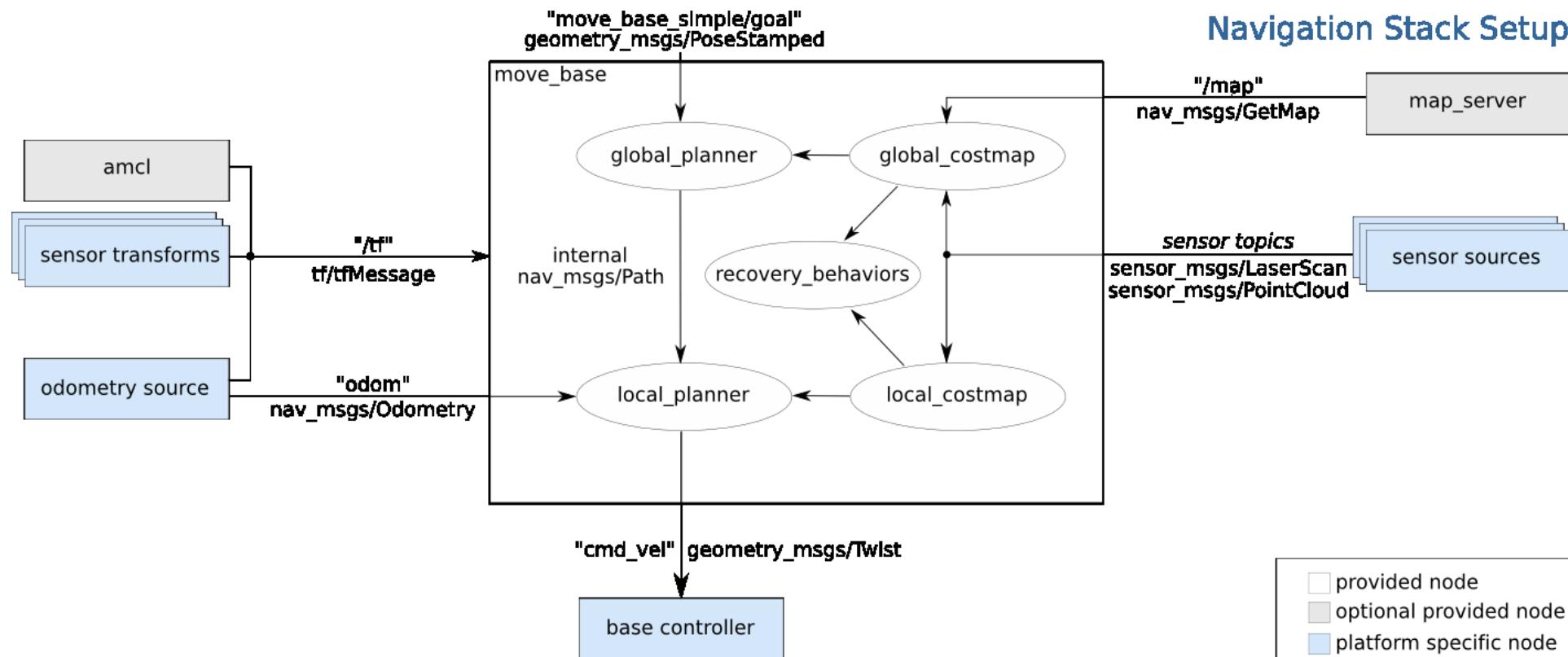
1. The environment changes (e.g., opening/closing doors)
2. It is dynamic (things might appear/disappear from the perception range of the robot)
3. The estimate is “noisy”

Thus we need to complement our ideal design with other components that address these issues, namely

1. Obstacle-Detection/Avoidance
2. Local Map Refinement, based on the most recent sensor reading

# ROS navigation stack

- Map provided by a “Map Server”
- Each module is a node
- Planner has a layered architecture (local and global planner)
- Obstacle sensing refined on-line by appropriate modules (local and global costmap)



# Building the map in ROS

---

- ROS uses [GMapping](#), which implements a particle filter to track the robot trajectories
- To build a map you need to
  1. Record a bag with [/odom](#), [/scan](#) and [/tf](#) while driving the robot around in the environment it is going to operate in
  2. Play the bag and the [gmapping-node](#) (see the ros wiki), and then save it
- The map is an occupancy map and it is represented as
  1. An image showing the [blueprint](#) of the environment
  2. A configuration file ([yaml](#)) that gives meta information about the map (origin, size of a pixel in real world)

# Localizing the robot

---

ROS implements the Adaptive Monte Carlo Localization algorithm

1. [AMCL](#) uses a particle filter to track the position of the robot
2. Each pose is represented by a particle
3. Particles are
  - Moved according to (relative) movement measured by the odometry
  - Suppressed/replicated based on how well the laser scan fits the map, given the position of the particle

# Virtual SLAM and Navigation

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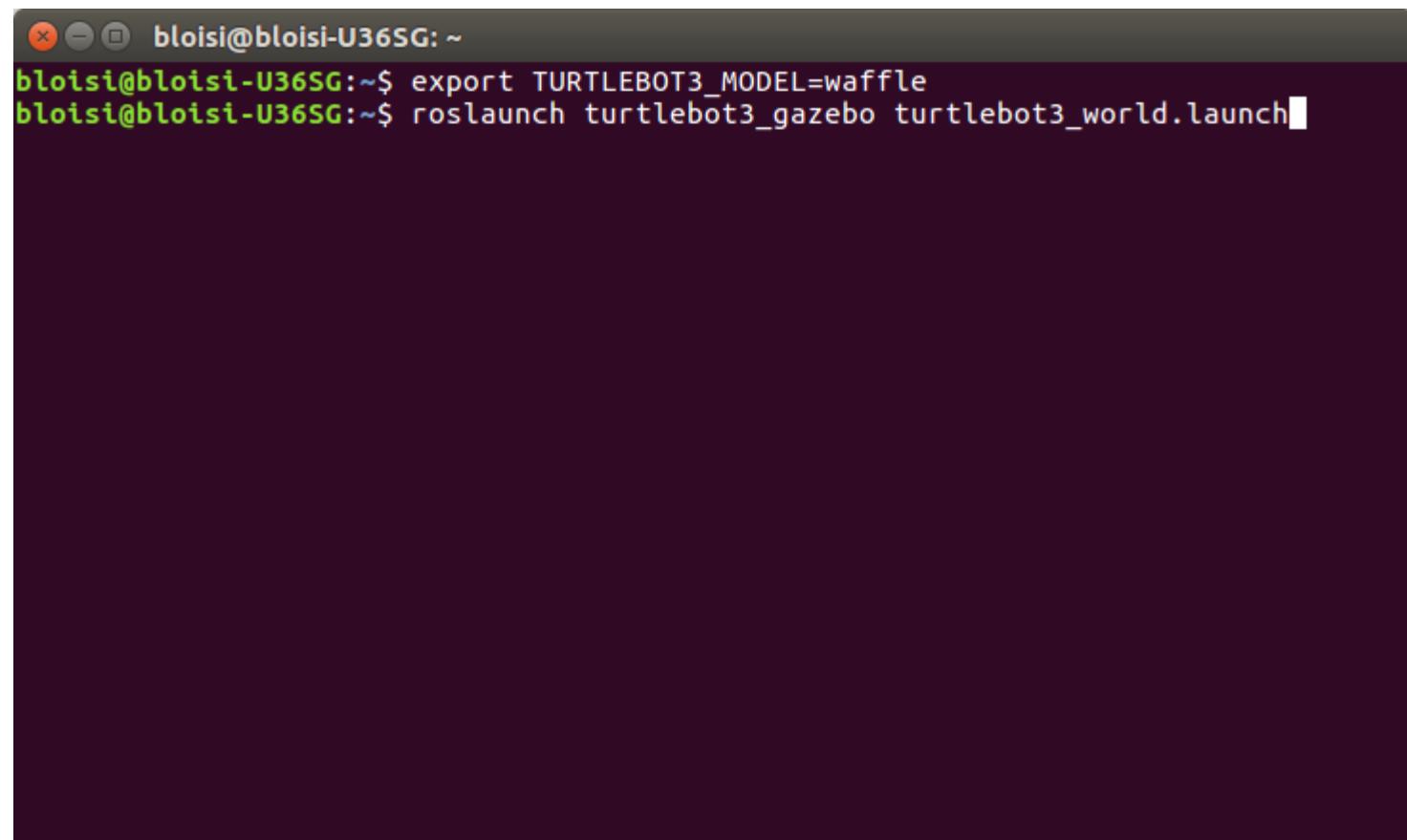
Useremo

- i package ROS per lo SLAM per creare una mappa di un mondo simulato tramite Gazebo
- lo stack ROS per la navigazione per far muovere il TurtleBot3 verso una destinazione sulla mappa

# Launch Gazebo

---

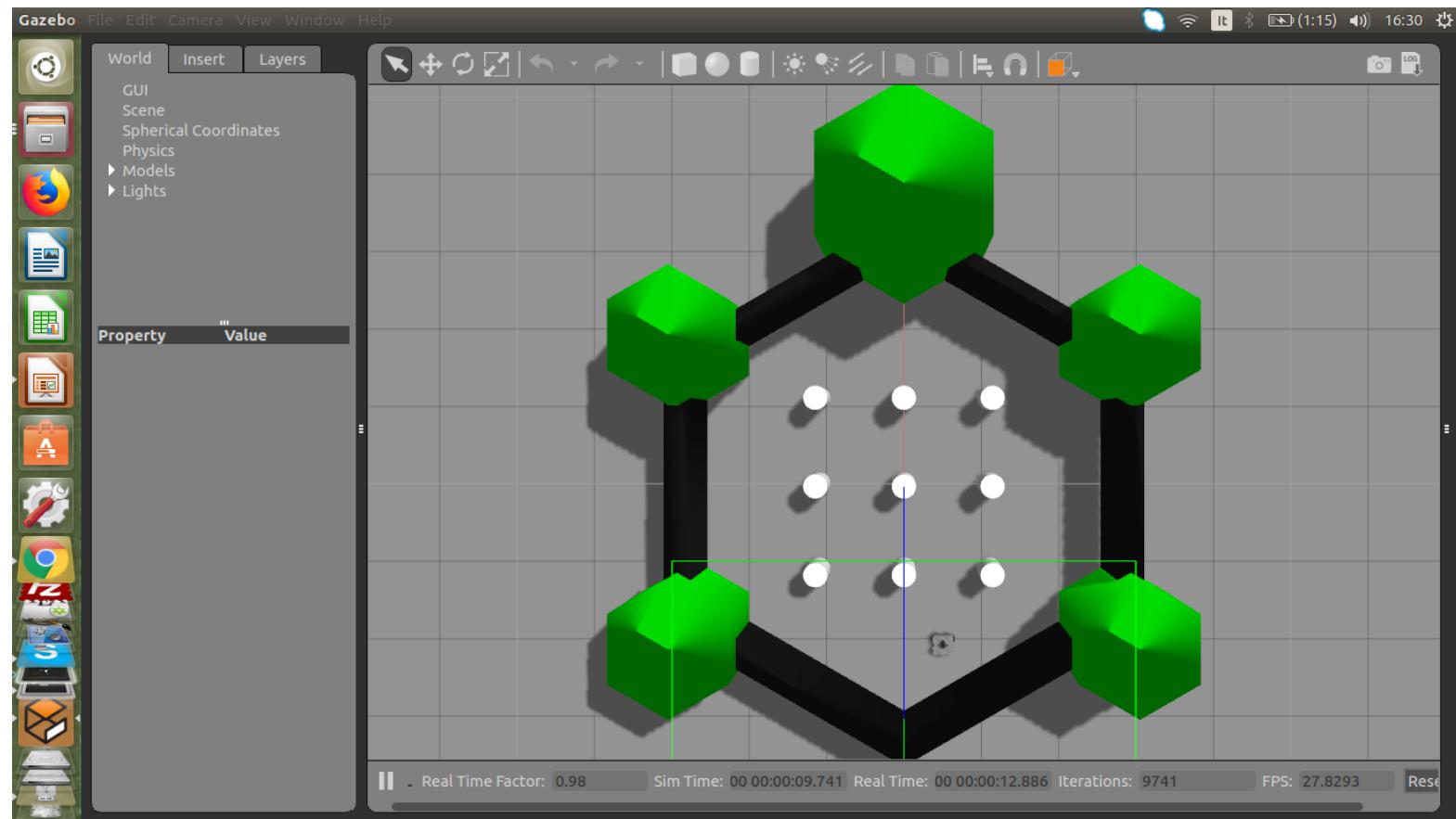
```
$ export TURTLEBOT3_MODEL=waffle  
$ roslaunch turtlebot3_gazebo turtlebot3_world.launch
```

A screenshot of a terminal window titled "bloisi@bloisi-U36SG: ~". The window contains two lines of text: "bloisi@bloisi-U36SG:~\$ export TURTLEBOT3\_MODEL=waffle" and "bloisi@bloisi-U36SG:~\$ roslaunch turtlebot3\_gazebo turtlebot3\_world.launch". The text is white on a dark background, and the window has a standard Linux-style title bar.

# Launch Gazebo

---

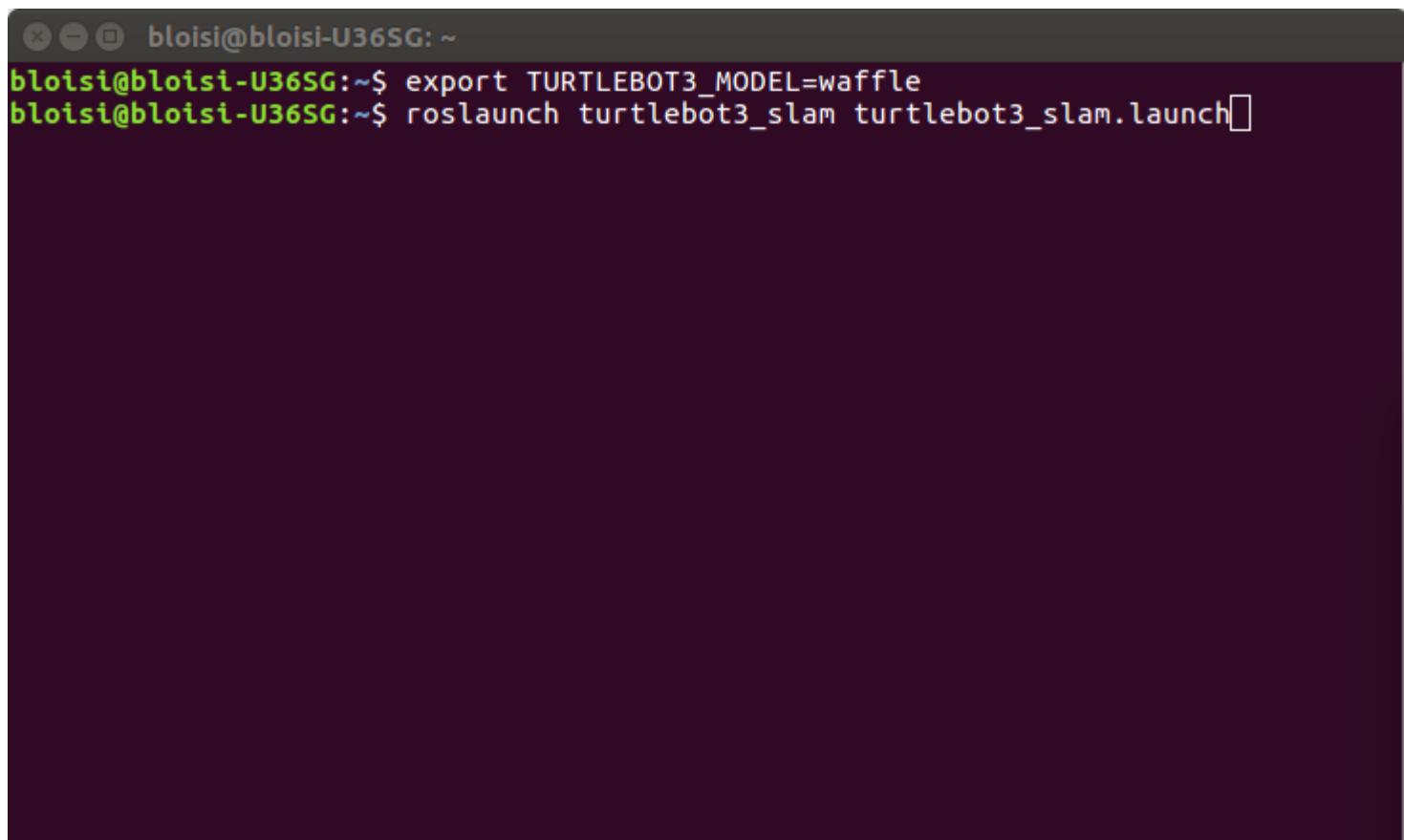
```
$ export TURTLEBOT3_MODEL=waffle  
$ roslaunch turtlebot3_gazebo turtlebot3_world.launch
```



# Launch SLAM

---

```
$ export TURTLEBOT3_MODEL=waffle  
$ roslaunch turtlebot3_slam turtlebot3_slam.launch
```

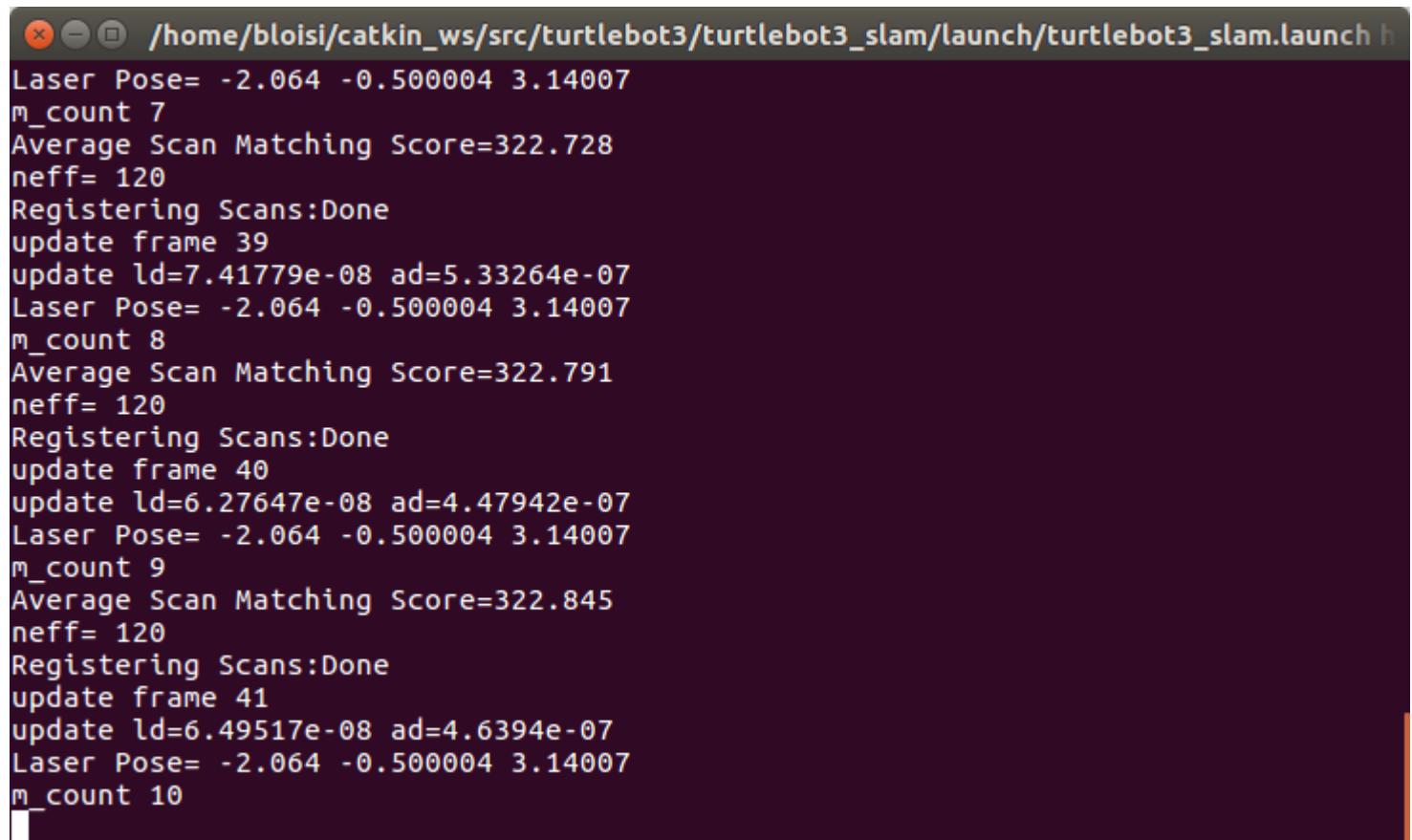
A screenshot of a terminal window titled "bloisi@bloisi-U36SG: ~". The window contains two lines of text in white on a black background: "bloisi@bloisi-U36SG:~\$ export TURTLEBOT3\_MODEL=waffle" and "bloisi@bloisi-U36SG:~\$ roslaunch turtlebot3\_slam turtlebot3\_slam.launch". The cursor is visible at the end of the second line.

```
bloisi@bloisi-U36SG:~$ export TURTLEBOT3_MODEL=waffle  
bloisi@bloisi-U36SG:~$ roslaunch turtlebot3_slam turtlebot3_slam.launch
```

# Launch SLAM

---

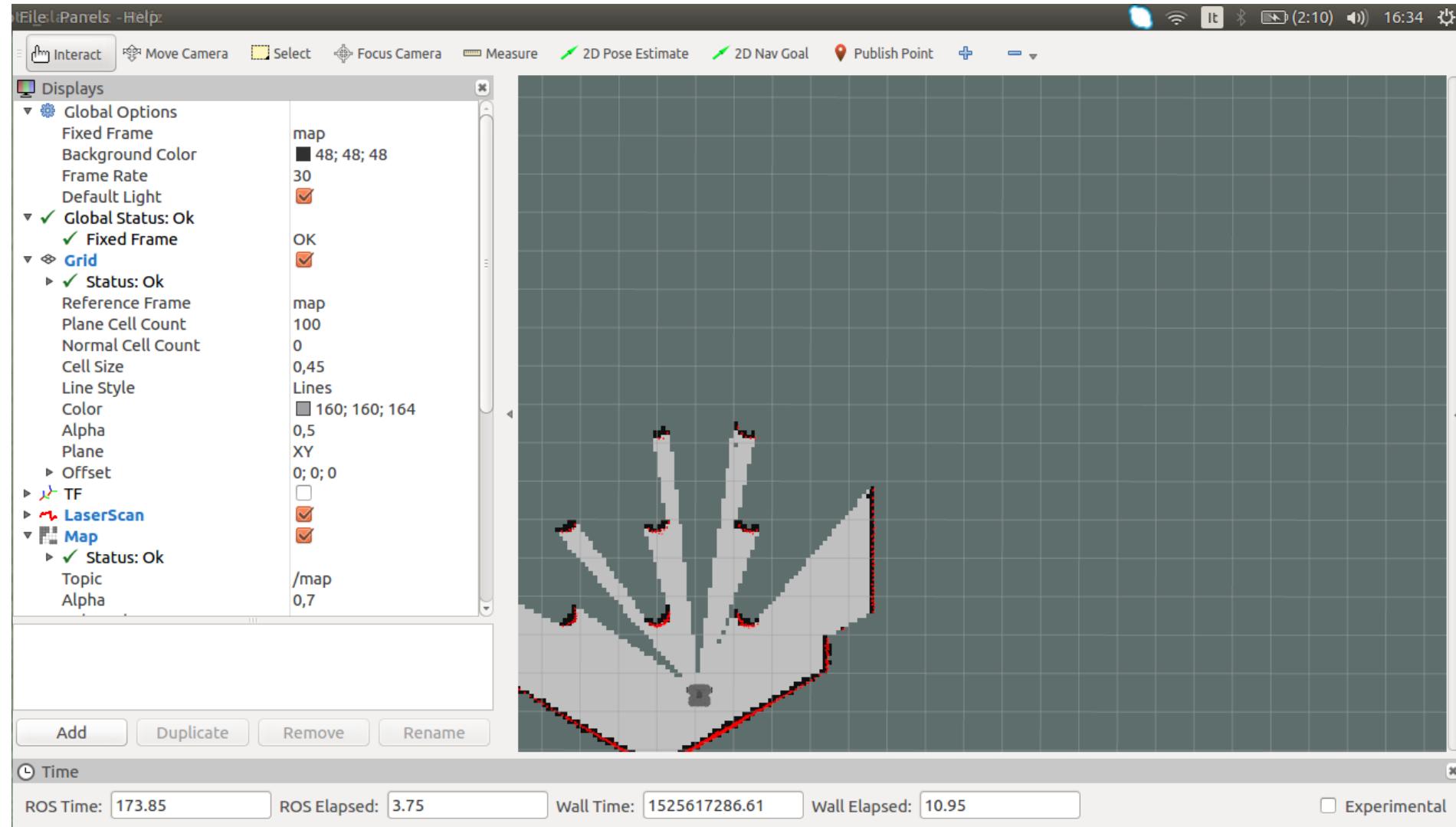
```
$ export TURTLEBOT3_MODEL=waffle  
$ roslaunch turtlebot3_slam turtlebot3_slam.launch
```



A screenshot of a terminal window showing the output of a SLAM process. The window title is '/home/bloisi/catkin\_ws/src/turtlebot3/turtlebot3\_slam/launch/turtlebot3\_slam.launch h'. The log output shows the robot's pose, scan matching statistics, and registration progress over several frames.

```
Laser Pose= -2.064 -0.500004 3.14007  
m_count 7  
Average Scan Matching Score=322.728  
neff= 120  
Registering Scans:Done  
update frame 39  
update ld=7.41779e-08 ad=5.33264e-07  
Laser Pose= -2.064 -0.500004 3.14007  
m_count 8  
Average Scan Matching Score=322.791  
neff= 120  
Registering Scans:Done  
update frame 40  
update ld=6.27647e-08 ad=4.47942e-07  
Laser Pose= -2.064 -0.500004 3.14007  
m_count 9  
Average Scan Matching Score=322.845  
neff= 120  
Registering Scans:Done  
update frame 41  
update ld=6.49517e-08 ad=4.6394e-07  
Laser Pose= -2.064 -0.500004 3.14007  
m_count 10
```

# RViz



# Remotely Control Turtlebot3

---

```
$ roslaunch turtlebot3_teleop turtlebot3_teleop_key.launch
```



# Remotely Control Turtlebot3

---

```
$ rosrun turtlebot3_teleop turtlebot3_teleop_key.launch
```

```
/home/bloisi/catkin_ws/src/turtlebot3/turtlebot3_teleop/launch/turtlebot3_teleop_key
* /rosversion: 1.12.13

NODES
/
  turtlebot3_teleop_keyboard (turtlebot3_teleop/turtlebot3_teleop_key)

ROS_MASTER_URI=http://localhost:11311

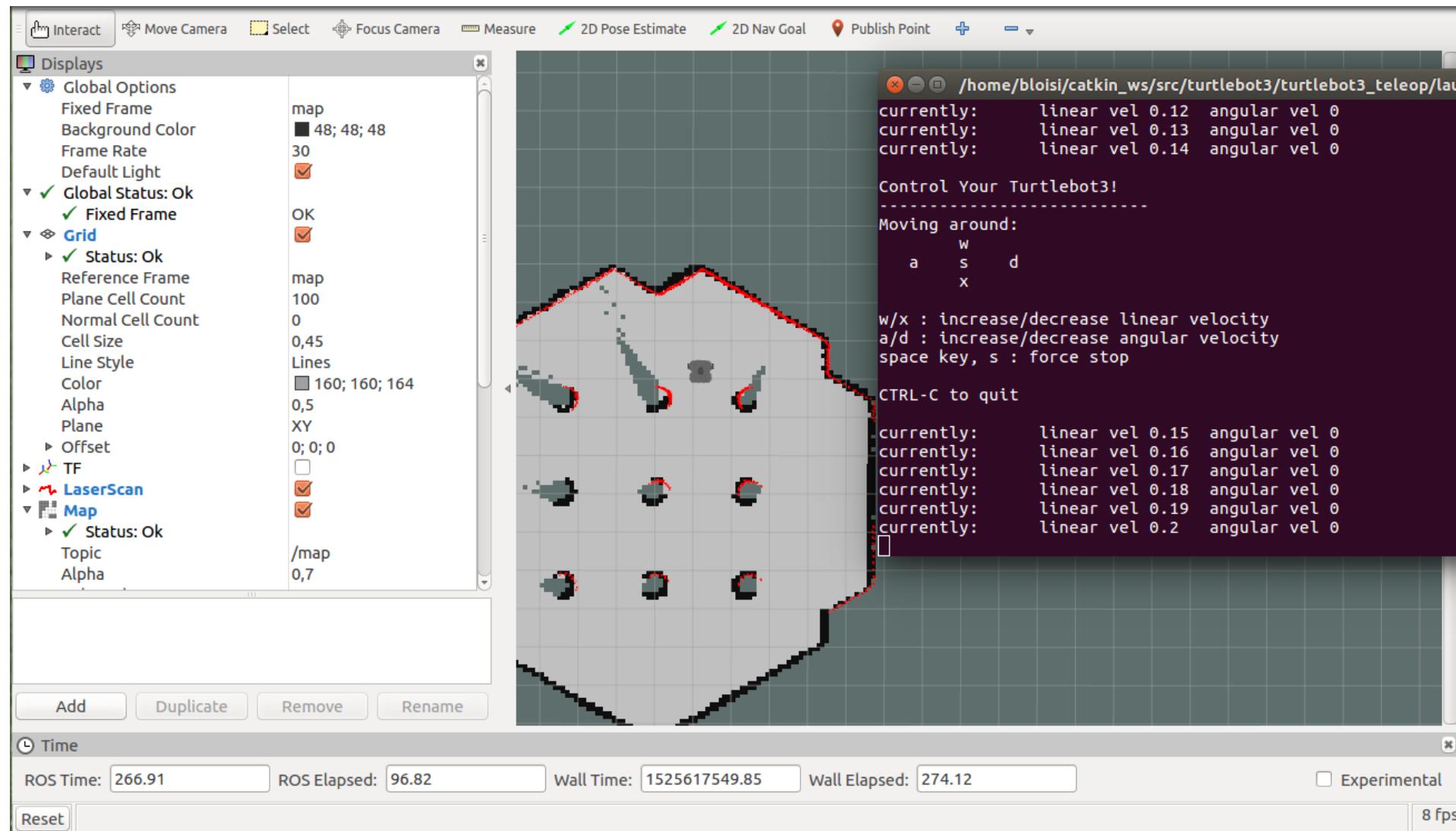
process[turtlebot3_teleop_keyboard-1]: started with pid [6305]

Control Your Turtlebot3!
-----
Moving around:
      w
    a   s   d
      x

w/x : increase/decrease linear velocity
a/d : increase/decrease angular velocity
space key, s : force stop

CTRL-C to quit
```

# Exploration



# Exploration

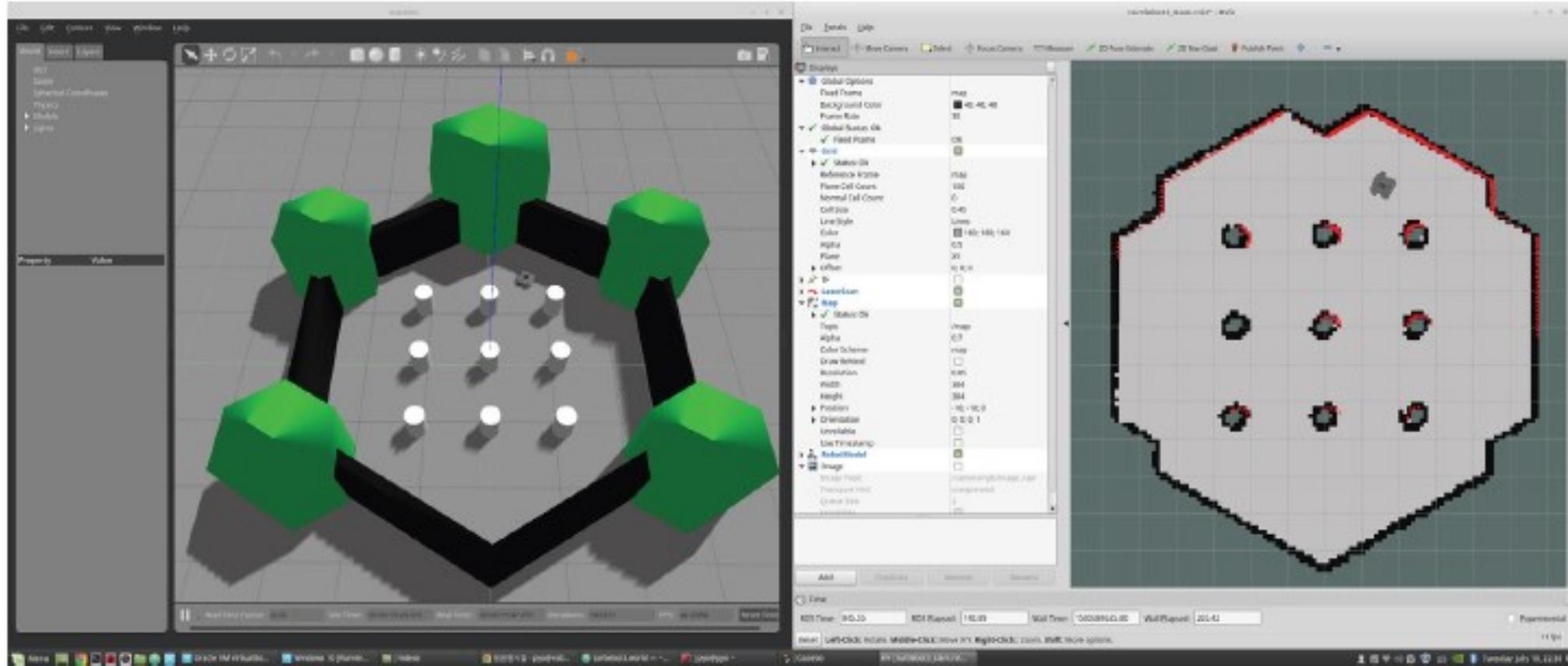


FIGURE 10-20 Running SLAM on Gazebo (Left: Gazebo, Right: RViz)

# Save the Map

---

Terminata l'esplorazione, possiamo salvare la mappa che è stata generata con il `map_server`

```
$ rosrun map_server map_saver -f ~/map
```

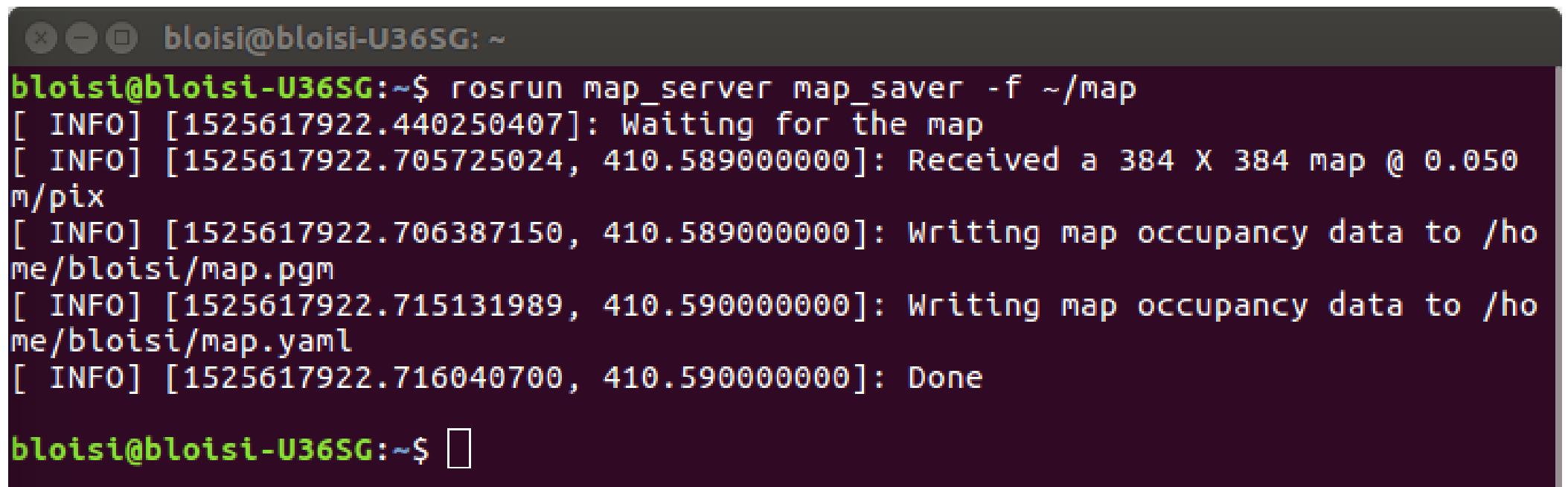


# Save the Map

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$ rosrun map_server map_saver -f ~/map
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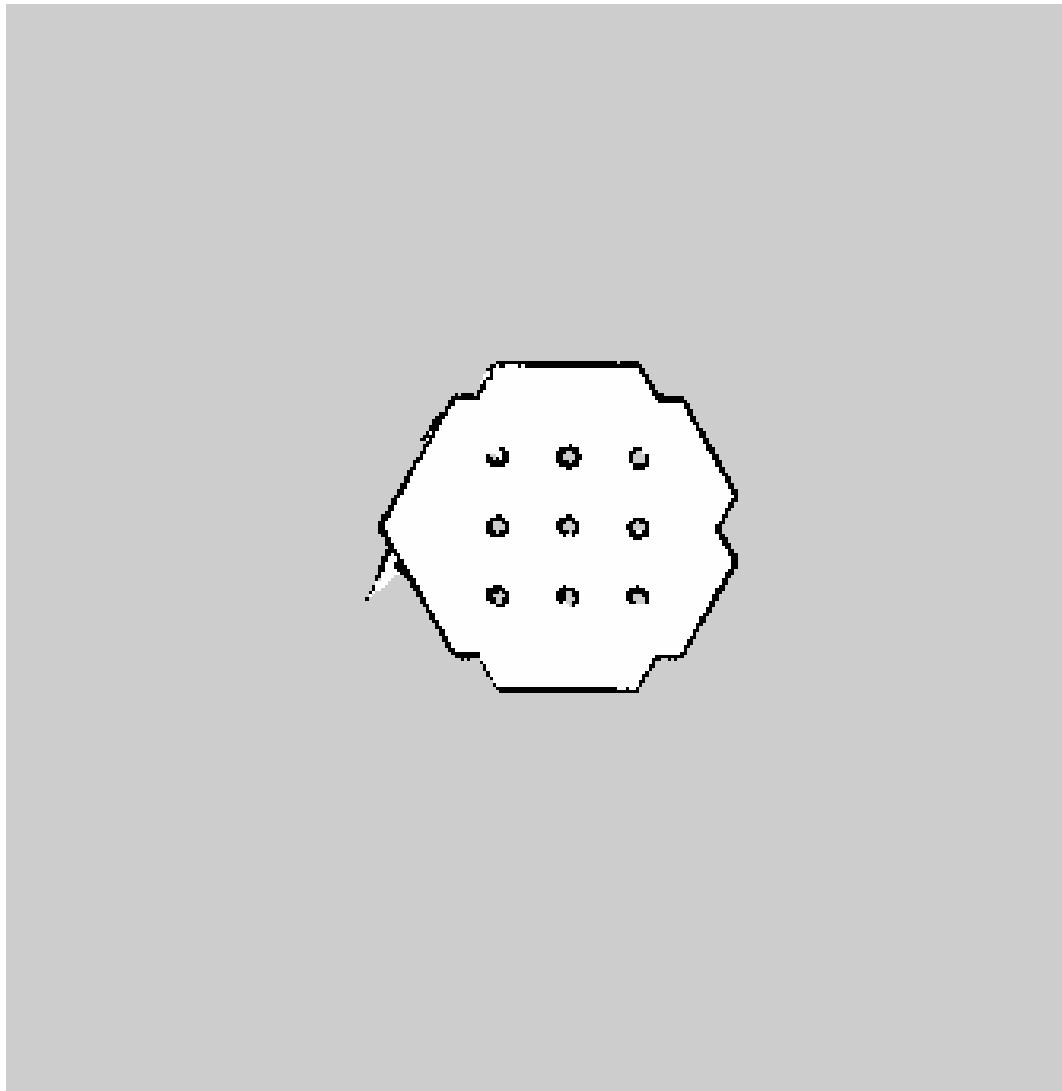


```
bloisi@bloisi-U36SG: ~
bloisi@bloisi-U36SG:~$ rosrun map_server map_saver -f ~/map
[ INFO] [1525617922.440250407]: Waiting for the map
[ INFO] [1525617922.705725024, 410.589000000]: Received a 384 X 384 map @ 0.050
m/pix
[ INFO] [1525617922.706387150, 410.589000000]: Writing map occupancy data to /ho
me/bloisi/map.pgm
[ INFO] [1525617922.715131989, 410.590000000]: Writing map occupancy data to /ho
me/bloisi/map.yaml
[ INFO] [1525617922.716040700, 410.590000000]: Done

bloisi@bloisi-U36SG:~$ 
```

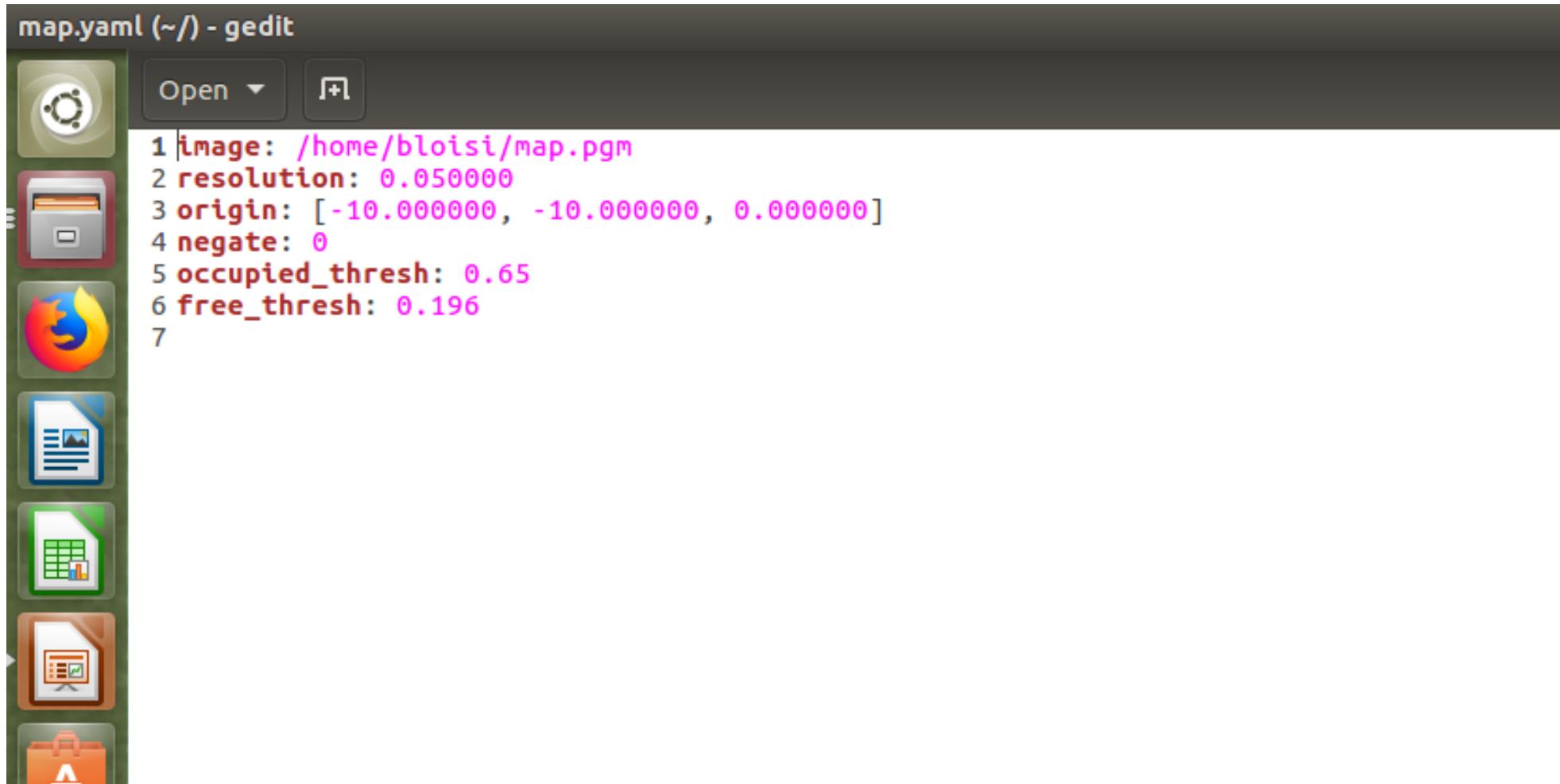
# map.pgm

---



# map.yaml

---



The screenshot shows a Gedit text editor window titled "map.yaml (~/) - gedit". The window has a dark theme. On the left, there is a vertical docked panel containing icons for various applications: a terminal, Nautilus (file manager), Firefox, LibreOffice Calc, LibreOffice Writer, and a terminal. The main editing area contains the following YAML configuration:

```
1 image: /home/bloisi/map.pgm
2 resolution: 0.050000
3 origin: [-10.000000, -10.000000, 0.000000]
4 negate: 0
5 occupied_thresh: 0.65
6 free_thresh: 0.196
7
```

# Navigazione

---

Per poter procedere con la navigazione

1. Terminare tutti i processi attivi
2. Lanciare in un terminale

```
$ export TURTLEBOT3_MODEL=waffle  
$ roslaunch turtlebot3_gazebo turtlebot3_world.launch
```

3. Aprire un secondo terminale e digitare

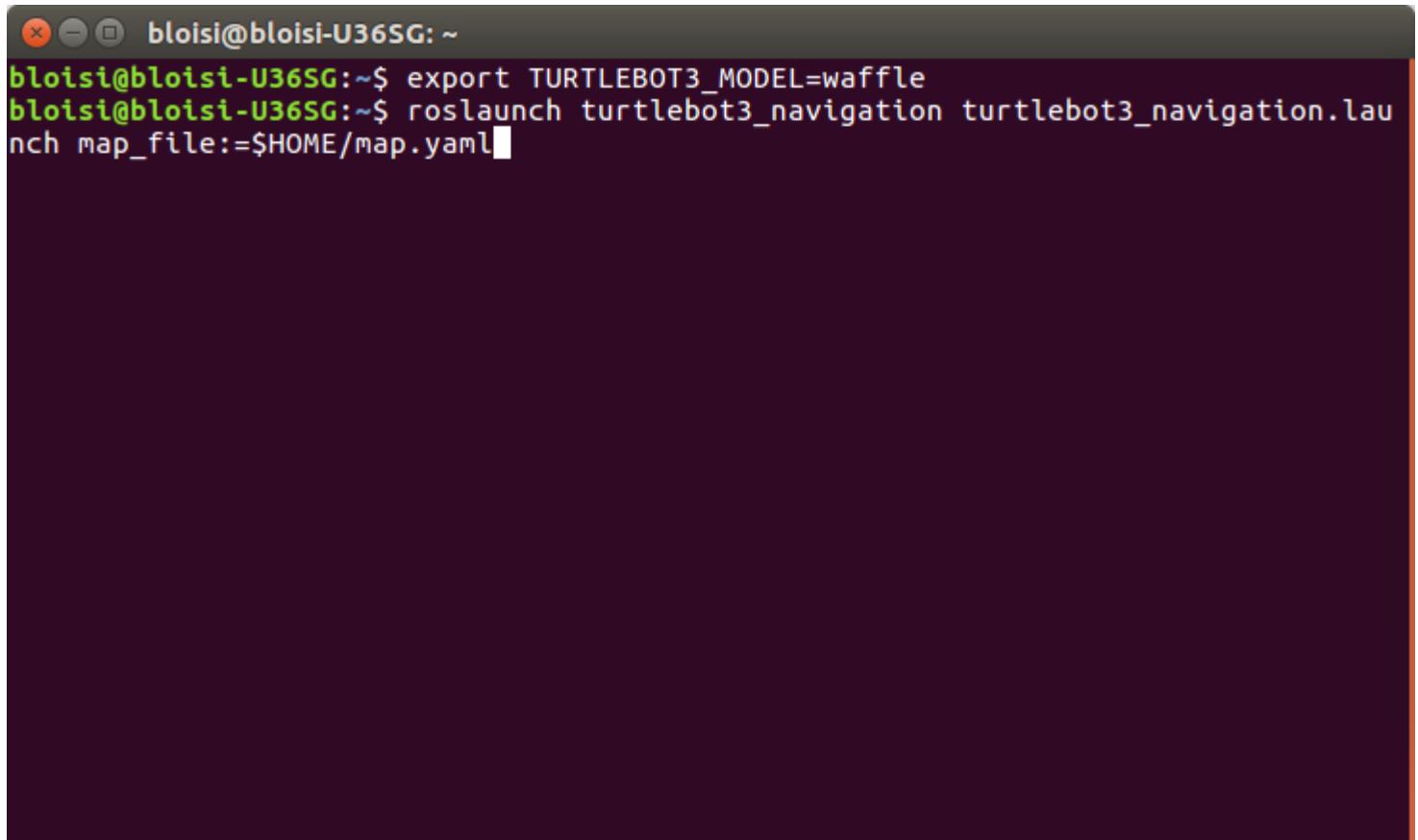
```
$ export TURTLEBOT3_MODEL=waffle  
$ roslaunch turtlebot3_navigation  
turtlebot3_navigation.launch map_file:=$HOME/map.yaml
```



# map\_file

---

```
$ export TURTLEBOT3_MODEL=waffle  
$ roslaunch turtlebot3_navigation turtlebot3_navigation.launch  
map_file:=$HOME/map.yaml
```

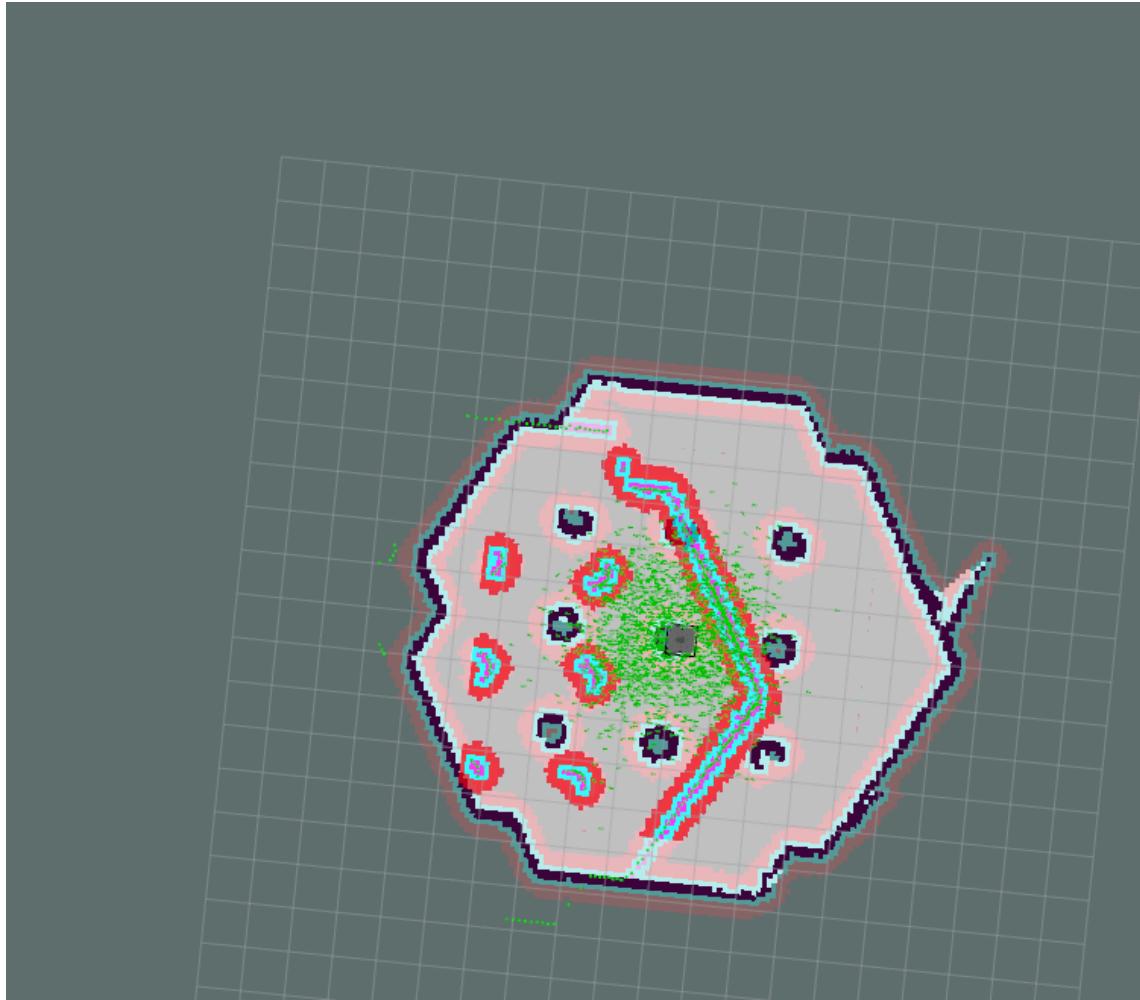
A screenshot of a terminal window titled "bloisi@bloisi-U36SG: ~". The window contains the following text:

```
bloisi@bloisi-U36SG:~$ export TURTLEBOT3_MODEL=waffle  
bloisi@bloisi-U36SG:~$ roslaunch turtlebot3_navigation turtlebot3_navigation.lau  
nch map_file:=$HOME/map.yaml
```

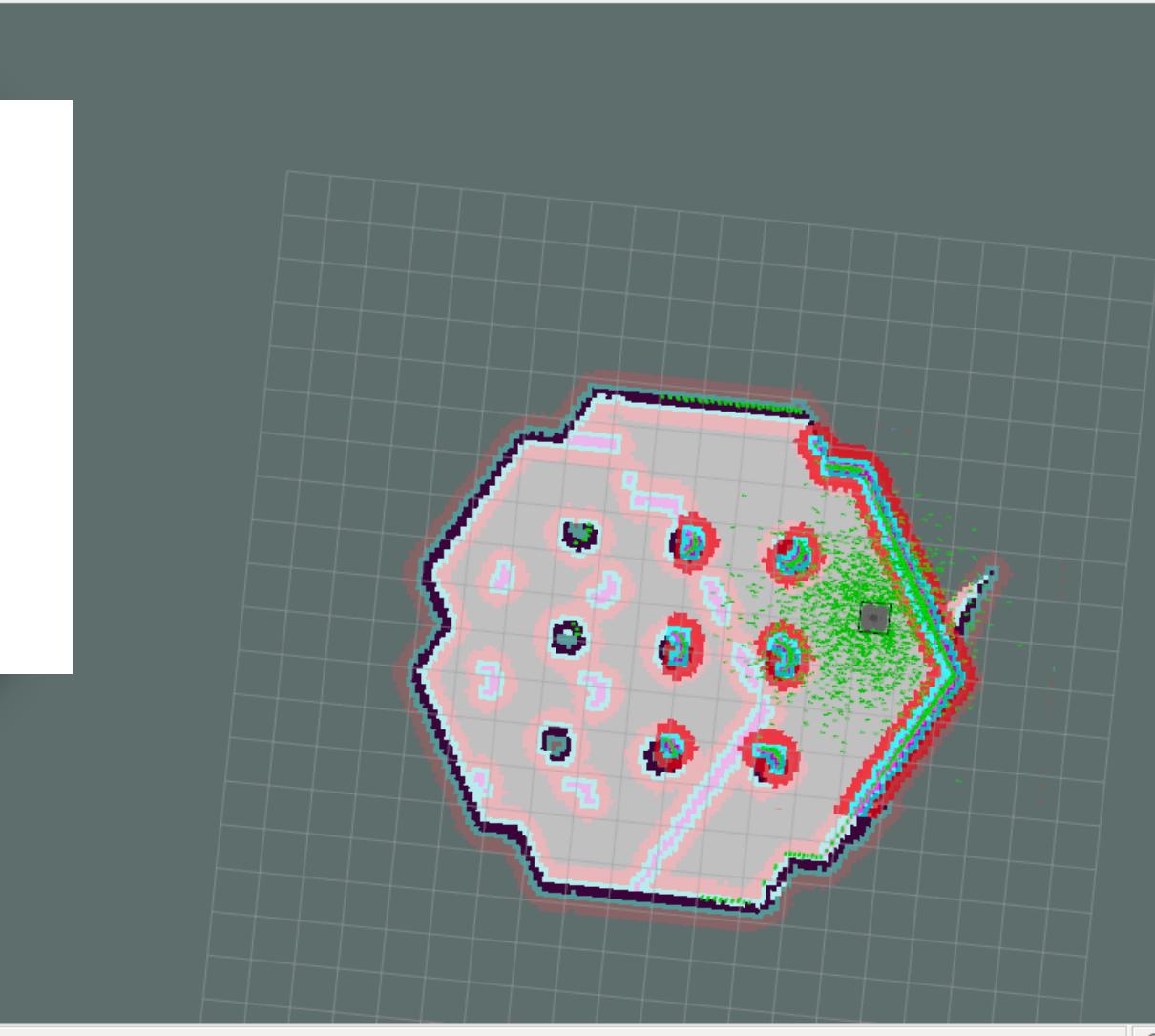
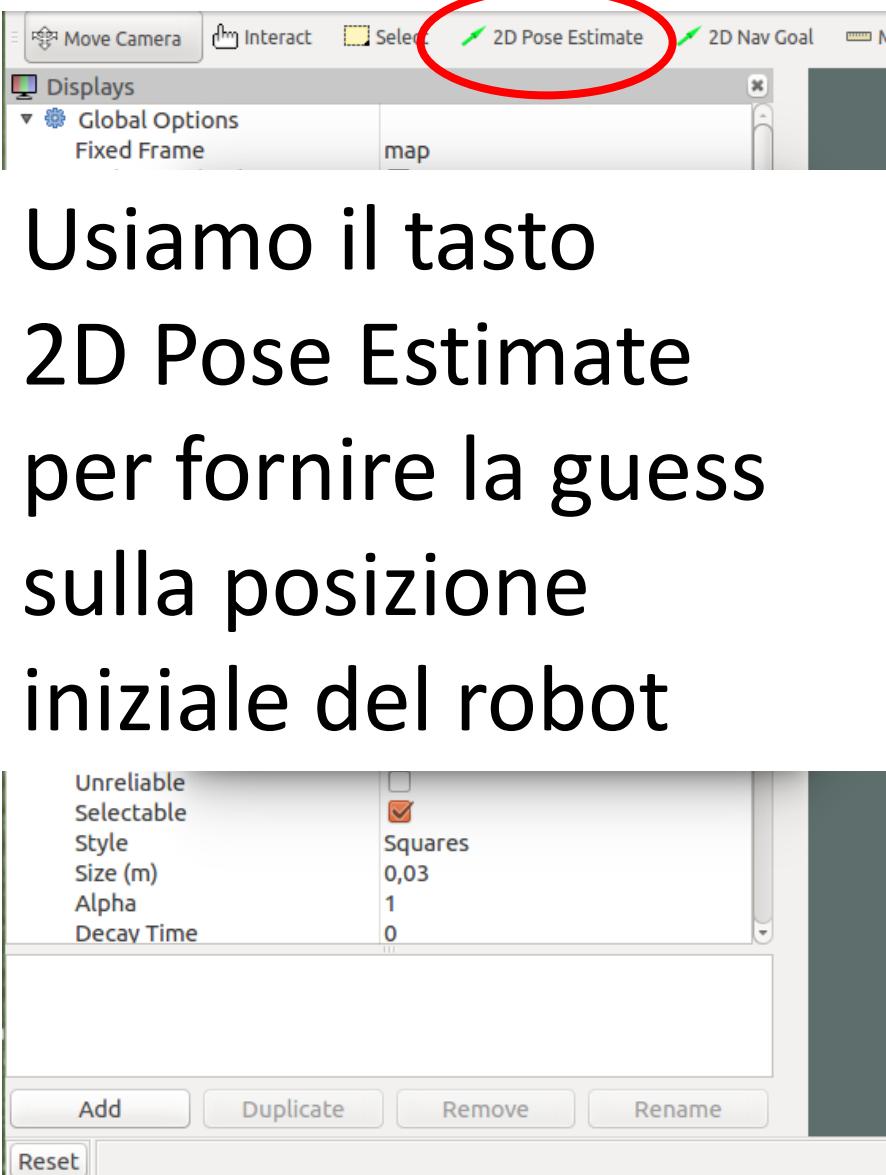
The text is in white on a dark background, with the terminal title and prompt also in white.

# Navigazione - RViz

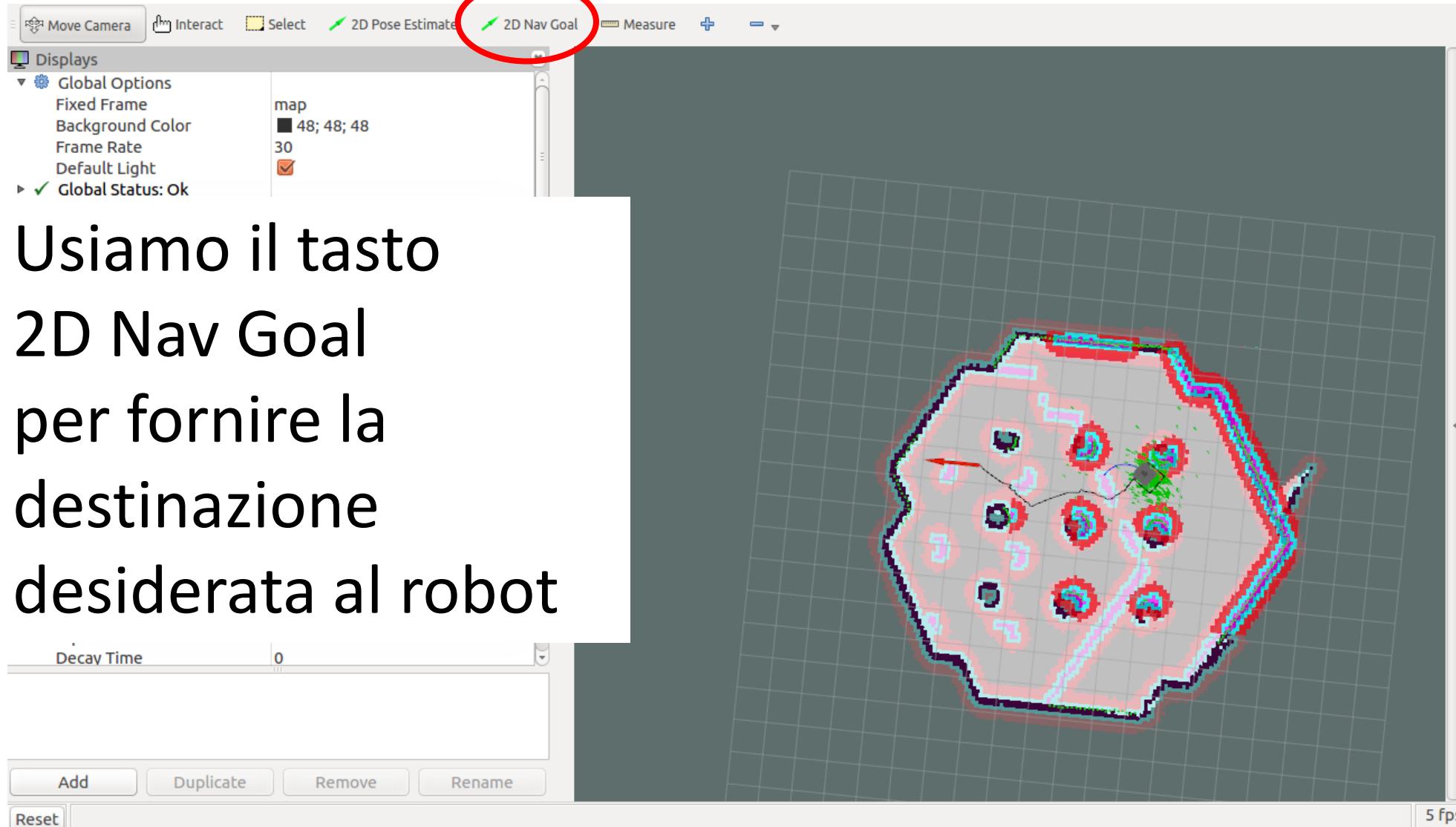
---



# Pose Estimate

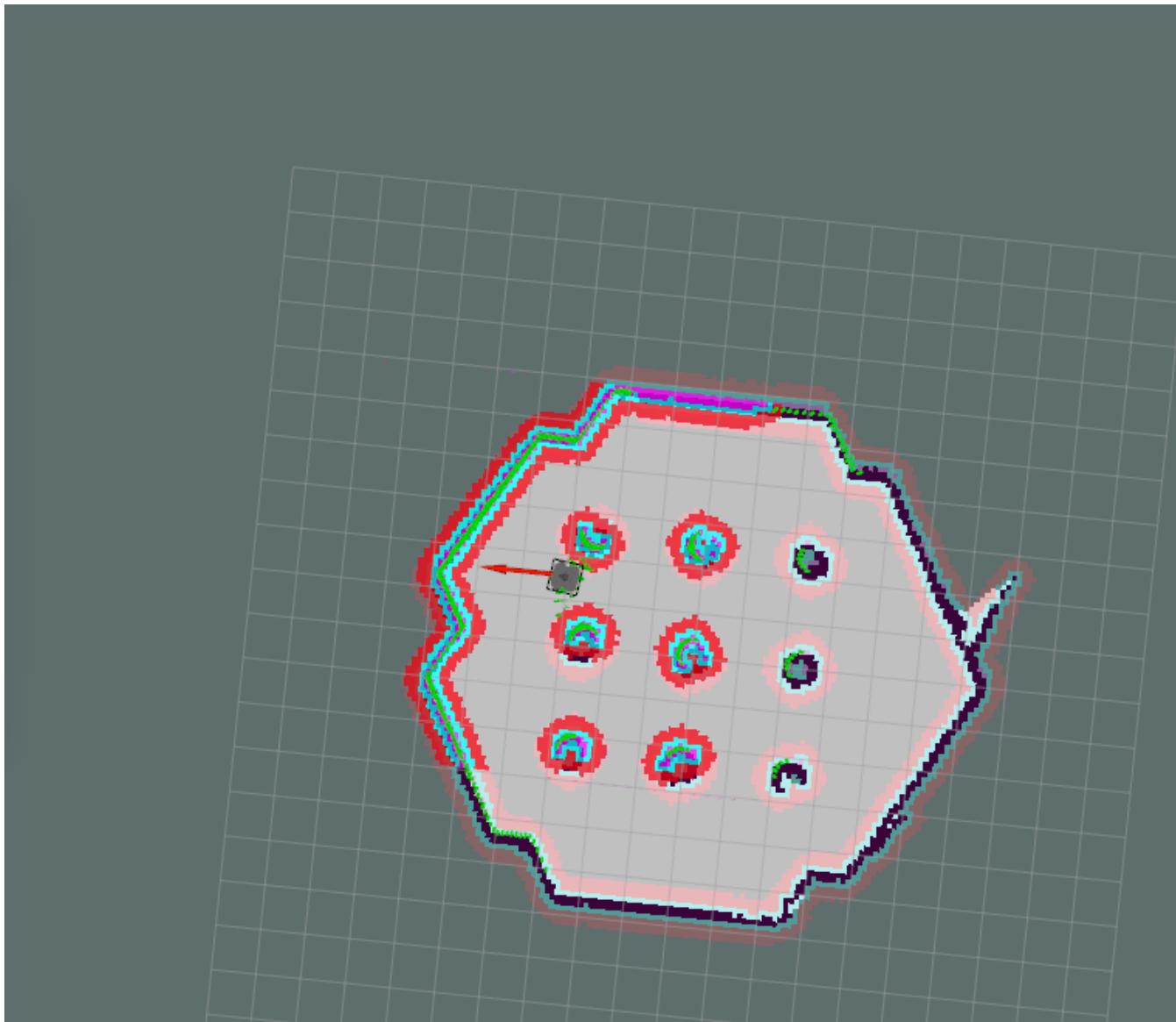


# Navigation Goal



# Goal raggiunto

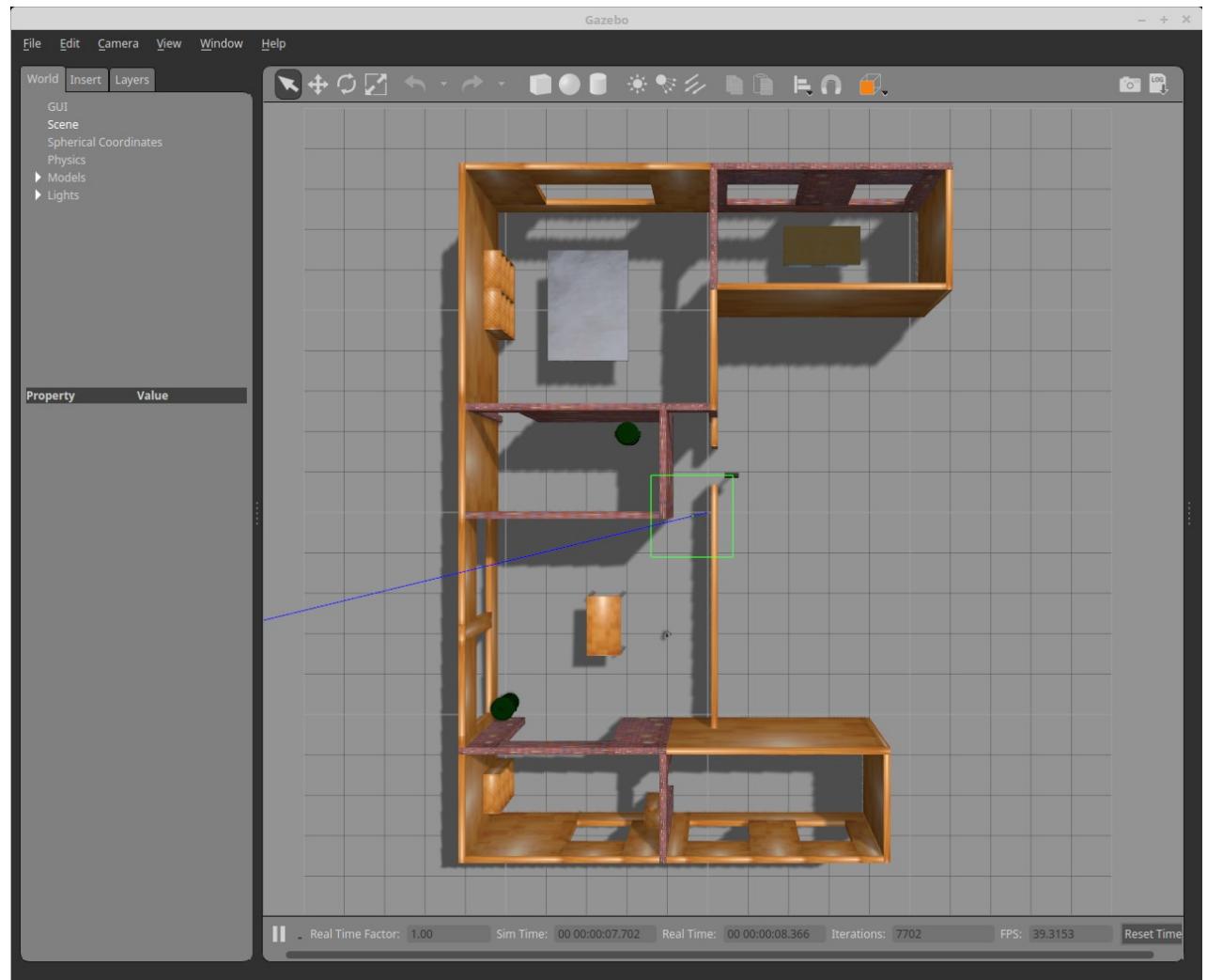
---



# Esercizio 1

---

Creare una mappa  
dell'ambiente Turtlebot3  
House e utilizzarla per far  
navigare il robot



<http://emanual.robotis.com/docs/en/platform/turtlebot3/simulation/>

# Esercizio 2

---

1. Provare a creare una mappa dell'ambiente cyber\_lab (scaricabile da [https://github.com/dbloisi/cyber\\_lab\\_gazebo](https://github.com/dbloisi/cyber_lab_gazebo))
2. Utilizzare il turtlebot3 per navigare autonomamente nel mondo cyber\_lab

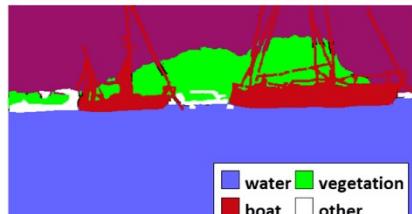
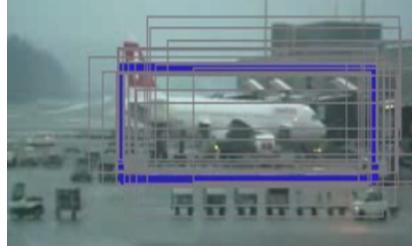
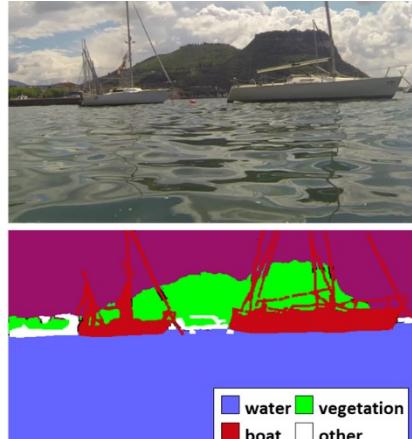
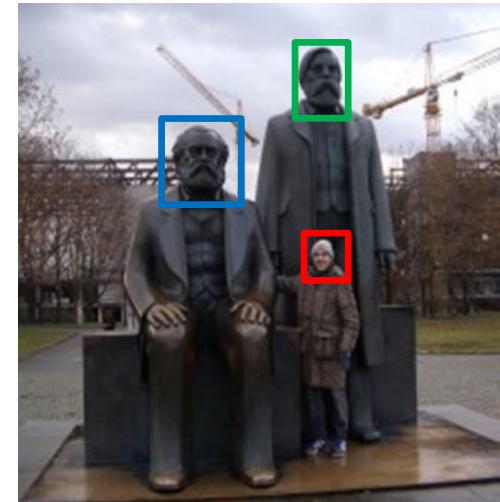
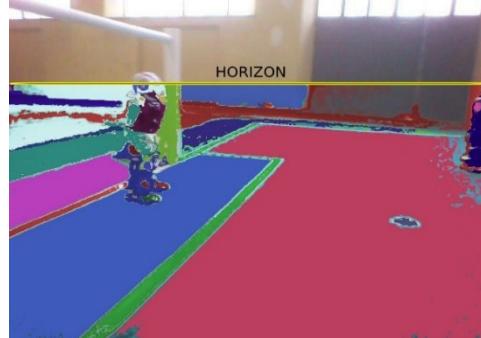


**UNIVERSITÀ DEGLI STUDI  
DELLA BASILICATA**

*Corso di Sistemi Informativi*  
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# Navigazione in ROS

Maggio 2019



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