

High Performance Computing Project

Parallelization of the Probabilistic Roadmap

Method with GPU Acceleration

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Gliederung

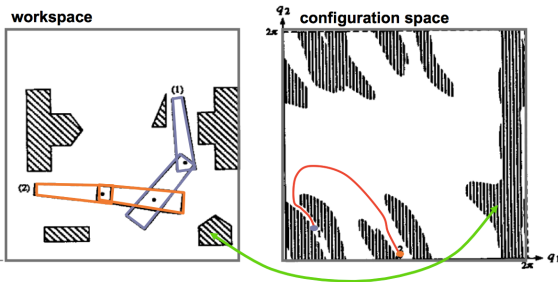
1 Motivation

2 Robotics Application

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Motivation



- Problem: find a feasible trajectory of a robot through a setting of obstacles
- often necessary to pass feasible initial trajectories to optimization algorithms

Problem Statement

- Obstacles can not be assumed to have a closed form
- Therefore they are defined by an indicator function

$$I : \Omega \subset \mathbb{R}^d \rightarrow \{0, 1\}$$

- collision for $q \in \Omega$, $I(q) = 1$

PRM Algorithm

PRM: Grow graphs from given start and endpoints $q_s, q_e \in \Omega$ until a connection is found, by repeating

- sample new node v randomly in environment of old nodes
- check for all possible neighbors w , if the linear connection is feasible, in this case add edge $\{v, w\}$ to the graph
- break, if the two graphs have been connected.

Definition

For two points v and w we define the connection with stepsize $h > 0$ as

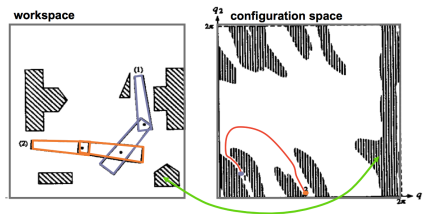
$$[v, w]_h := \{q = \lambda v + (1 - \lambda)w \mid \lambda \in [0, 1], \|q - v\| \in \mathbb{N}_0 h\}.$$

We say, q_1 and q_2 are connected with stepsize $h > 0$, if $l(q) = 0$ for all $q \in [q_1, q_2]_h$.

1 Motivation

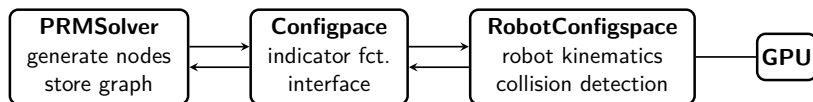
2 Robotics Application

Robotics Application



- For each linear connection, every intermediate configuration has to be checked for collisions
- \Rightarrow Many independent and similar kinematics and collision calculations
- \Rightarrow Well suited for usage of GPU

Project Overview

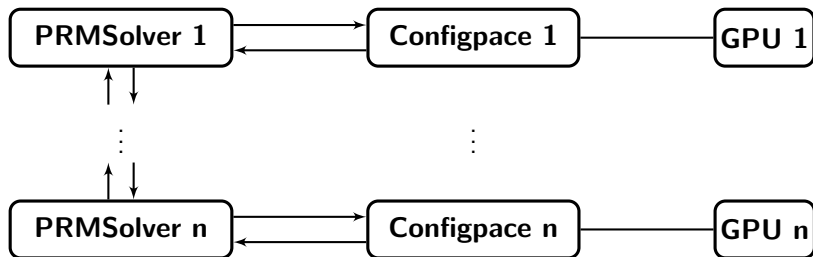


- PRM algorithm and Configuration space independent from each other
- Only connected through indicator function represented by Configspace interface

Second Level of Parallelization

Version 1:

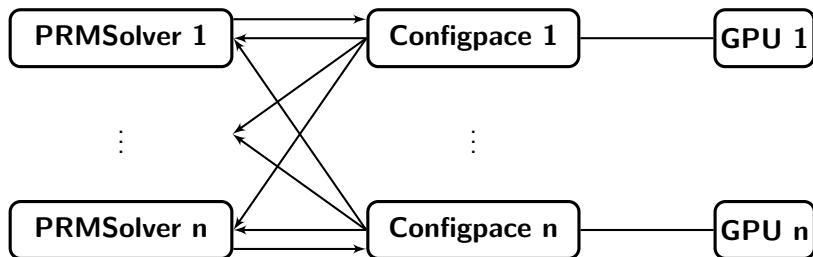
- Use multiple GPUs parallelly
- Sample and connect new nodes on each processor
- Exchange nodes and edges



Second Level of Parallelization

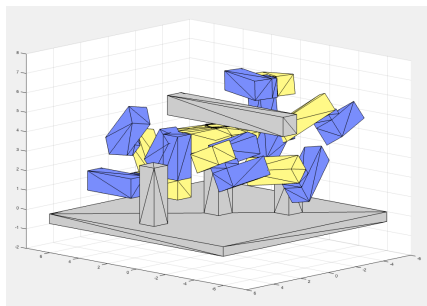
Version 2:

- Grow whole graphs on every processor
- Exchange only edges









Implementation and Testing

- GPU implementation with CUDA
- CPU Parallelization with MPI
- Tested with a 4 axis robot scenario created with CAD/Matlab



Literatur

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