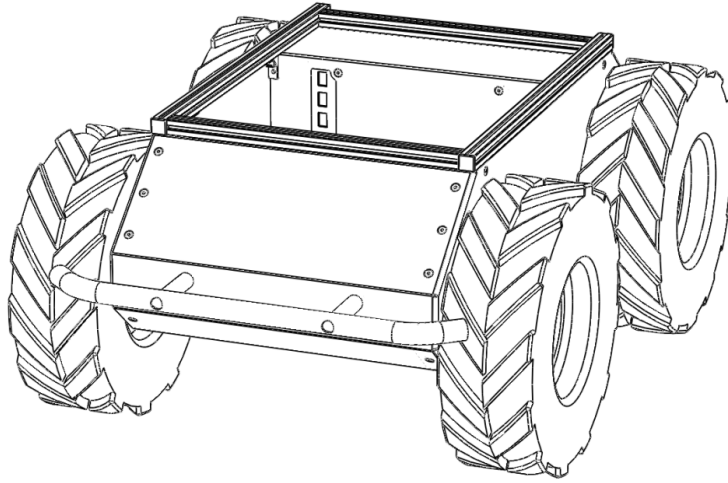


HUSKY

UNMANNED GROUND VEHICLE

USER MANUAL



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INTRODUCTION

Husky is a rugged and easy-to-use unmanned ground vehicle for rapid prototyping and research applications. In this guide, you will find information about the setup, operation, and maintenance of Husky.

What's Included

Included with the base Husky are the following:

- 1x Clearpath Robotics Husky
- 1x 24V Sealed Lead-Acid Battery Pack
- 1x Battery Door Cover
- 1x Battery Charger
- 2x Lockout Keys
- 3x Power Connectors

What's Required

To use Husky, you will require a PC capable of running Robot Operating System (ROS).

If a computer option was purchased from Clearpath Robotics with Husky, then the included laptop or minicomputer has already been configured with Ubuntu 12.04 and ROS Hydro, plus appropriate ROS packages and other configuration for use with Husky.

Expansions

To expand the capabilities of Husky, consider the following accessories offered by Clearpath Robotics:

- Spare Battery
- IMU
- LIDAR
- Network Camera
- GPS

Each sensor package ships from Clearpath Robotics with a custom mounting bracket and cabling for easy attachment to Husky's extruded aluminum payload mounting rail.

THE BASICS

This section provides an overview of the key specifications of the Husky platform. Figure 1 gives a tour of key Husky components.

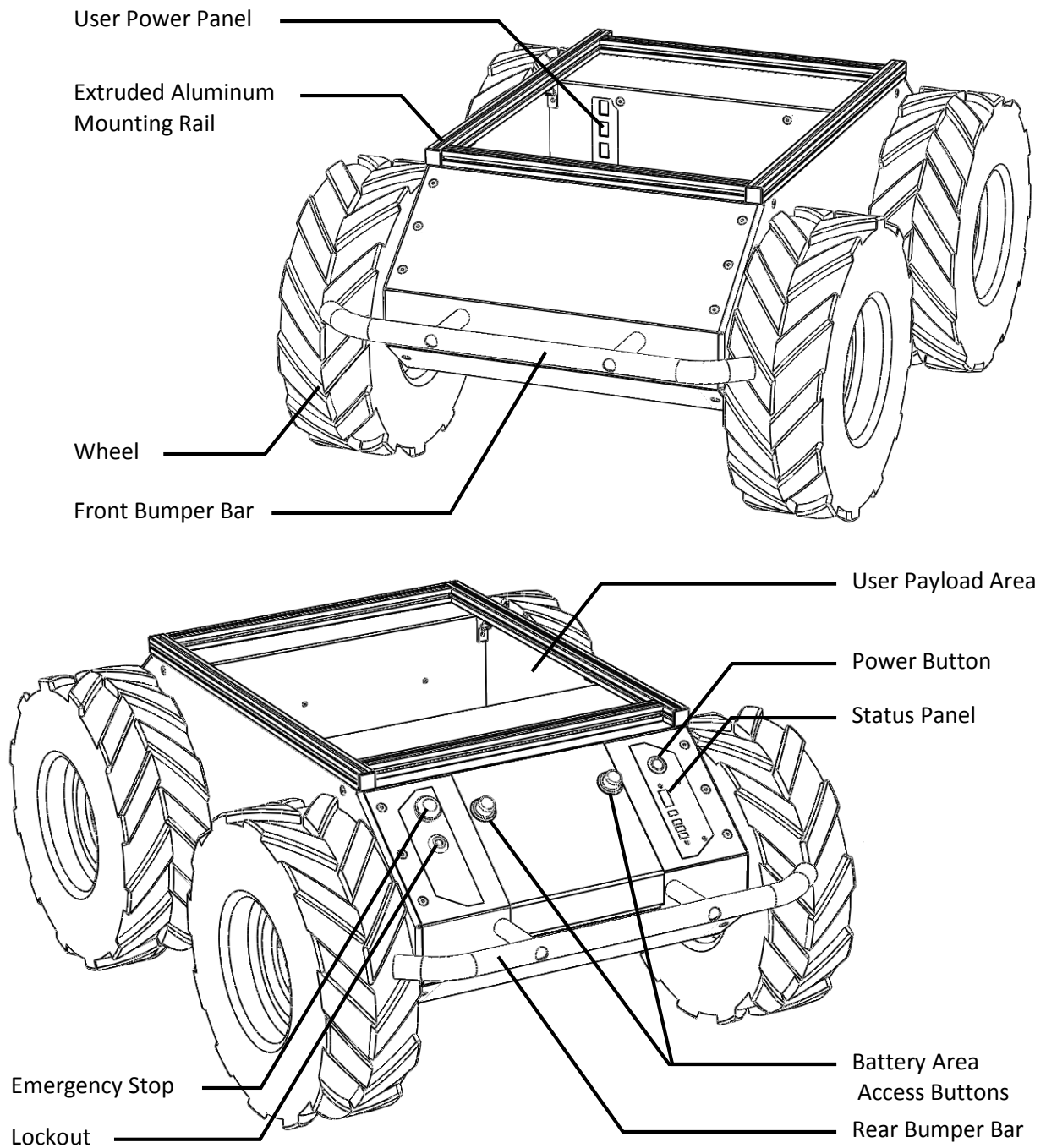


Figure 1: Husky at a Glance

Status Panel

The status panel is a display of LED indicators located on the rear of the chassis which provide information about the current status of Husky. The indicators are described in Table 1.






Icon	Description
	Battery status. The four LED segments provide an approximate indication as to the relative lifetime remaining in the battery.
	Communications status. When green, Husky is receiving a stream of correctly-formatted motion commands, and is ready to drive. When yellow, Husky is receiving commands but will not drive due to emergency stop or another error. When red, serial communications are currently timed-out.
	General error status. Illuminates red when Husky will not drive due to an error state. Such states include emergency stop, insufficient battery power, or an unspecified software error.
	Emergency stop status. Illuminates red when Husky will not drive due to the emergency stop being activated, either onboard or wireless (if available).
	Charge indicator. Illuminates red when Husky user power is being supplied externally.

Table 1: Husky Status Panel Icons

Orientation References

The reference frame used by all Clearpath Robotics ground vehicles is based on ISO 8855, and is shown in Figure 2. Husky is displayed from the front. When commanded with a positive translational velocity (forward), wheels travel in the positive x-direction.

The direction of the axes differs from those used for roll, pitch, and yaw in aircraft, and care should be taken to ensure that data is interpreted correctly.

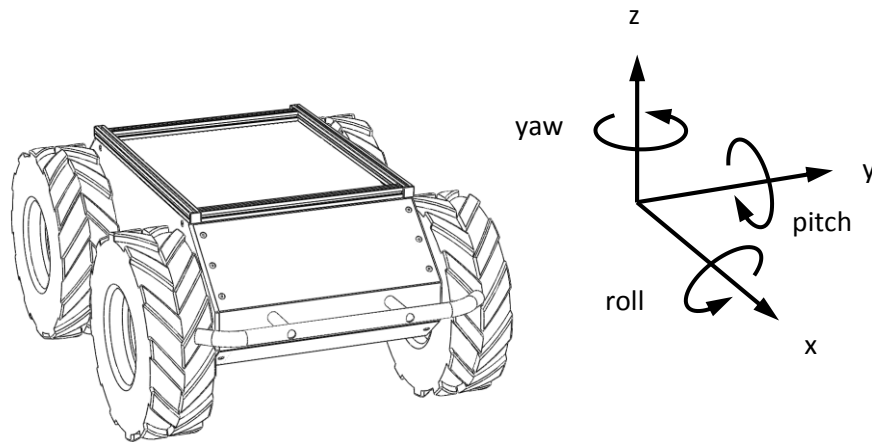
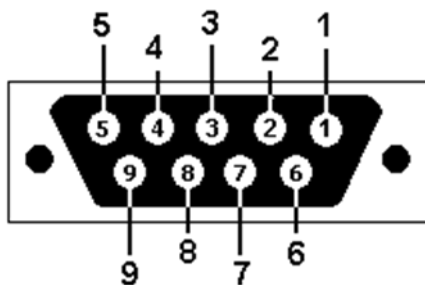


Figure 2: Husky Reference Frame

Pinout References

Husky provides a female DE-9 connector for communication with a host device. The pinout of this connector is shown in Figure 3.



Pin	Name	Dir	Description
2	RX	IN	Data from Platform
3	TX	OUT	Data to Platform
5	GND	N/A	Common Ground

Figure 3: Husky DE9 Pinout

System Specifications

Key specifications of Husky are shown in Table 2.

Dimensions	990 mm length 670 mm width 390 mm height	39 in length 26.4 in width 14.6 in height
Track	555 mm	21.9 in
Wheelbase	512 mm	20.2 in
Weight	50 kg	110 lbs
Maximum Payload ¹	75 kg	165 lbs
All-terrain Payload ²	20 kg	44 lbs
Speed (max)	1.0 m/s	3.3 ft/s
Ground Clearance	130 mm	5 in
Climb Grade	45°	100% slope
Traversal Grade	30°	58% slope
Operating Ambient Temperature	-10 to 30 ° C	14 to 86° F
Operating Time	3 hours typical 8 hours standby (no motion)	
Battery	24V 20 Ah Sealed Lead Acid	
Battery Charger	Short-circuit, over-current, over-voltage, and reverse voltage protection.	
Charge Time	10 hours	
User Power	5V / 12V / 24V Each fused at 5A	
Communication	RS-232 115200 Baud	
Wheel Encoders	78,000 ticks/m	
Internal Sensing	Battery status Wheel odometry Motor currents	

Table 2: Husky System Specifications

¹: Continuous operation on relatively flat terrain with wide turns

²: Vehicle climbing 30° grade with high-mounted payload, or turning in place in high-friction conditions

Vehicle Equations

As a starting point, Clearpath Robotics recommends using the following relationship between wheel velocity and platform velocity:

$$v = \frac{v_r + v_l}{2}, \omega = \frac{v_r - v_l}{w}$$

v represents the instantaneous translational speed of the platform and ω the instantaneous rotational speed. v_r and v_l are the right and left wheel velocities, respectively. w is the effective track of the vehicle (0.555 m).

Control Modes

Husky supports four distinct control modes:

- **Kinematic Control**, the default, uses a speed control feedback loop, and allows specifying the desired linear and angular speed of Husky. Access this mode by publishing a standard ROS Twist message to the `/husky/cmd_vel` topic.
- **Torque Control** may be used by switching the startup node in `base.launch` from `kinematic_node` to `torque_node`. In this mode, a Twist message is used as well, but the linear and angular values specified are multiplied by parameterized scaling factors and used for a current control feedback loop.
- **Raw Control** may be used by switching the startup node in `base.launch` from `kinematic_node` to `raw_node`. Raw mode works similarly to torque control, but disables feedback control altogether, instead using the scaling values to specify open-loop voltage for the motor drivers. This mode may be useful for novel control algorithms on the PC, or for debugging a suspected wheel encoder failure.

On included computers set up by Clearpath Robotics, the `base.launch` file may be found along with other roslaunch files in the `/etc/ros/hydro/husky-core.d/` folder. This folder is owned by root and sudo will be required to edit its contents, eg:

```
$ sudo nano /etc/ros/hydro/husky-core.d/base.launch
```

SAFETY

Clearpath Robotics is committed to high standards of safety. Husky contains several features to protect the safety of users and the integrity of the vehicle.

General Warnings

Husky is a rugged and high-performance vehicle. For the safety of yourself and others, always conduct initial experiments and software development with the vehicle raised off the ground. Place a wooden crate, a set of sawhorses, a sturdy storage tub, or any other solid flat structure having a height greater than 6 inches under Husky to keep the wheels clear of the ground (“up on blocks”).

When starting out, favor slower wheel speeds. Husky’s control loops can accurately maintain velocities as low as 0.1 m/s. Operating at such speeds will give you more time to react if things don’t go quite as you expect.

When Husky is operating, keep clear of the wheels, paying particular attention to the pinch hazard which exists between each wheel and the end of the corresponding bumper bar.

E-Stop and Lockout

The red emergency stop button (e-stop) and lockout are located on the back of Husky, opposite the status panel, shown in Figure 4. Power supply to Husky’s motor drivers is enabled by a normally-open relay, which is closed in series with the e-stop switch. When in e-stop mode, the status panel e-stop light will illuminate red, and Husky will not drive. The commands received during e-stop are not buffered; Husky will always act on the latest commands received. This means that if the commands are stopped before the e-stop is released, the Husky will not move. If the commands are continued, Husky will move at the speed commanded once the e-stop is released.

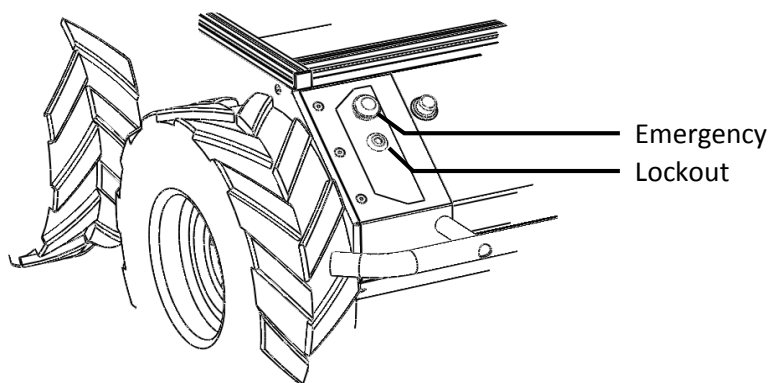


Figure 4: Husky Emergency Stop and Lockout

Always ensure the e-stop button is accessible at all times. Avoid mounting payloads that extend over the rear of Husky and would occlude the e-stop.

The lockout provides a secondary e-stop for periods during which Husky will be left unattended. When in lockout mode, the robot will still power on, but the motors will not drive.

Electrical System

Husky is powered by a single 24V sealed lead-acid battery, similar to the type found in electric wheelchairs, golf carts, and other devices. Husky's battery is capable of delivering 1800W—similar to wall mains. This gives Husky's motors their great performance, however, it is also enough power to cause severe bodily harm. Please observe the following precautions:

- Do not tamper with the plug attached to the battery.
- Do not tamper with the fuse panel, except to check and change the fuses, and to connect and disconnect the battery plug.
- Do not operate Husky without the battery door in place. The battery is insufficiently restrained without the door, and will come loose, damaging the fuse panel.
- Charge the battery only with the charger provided by Clearpath Robotics.
- Please dispose of the batteries properly, or return the battery to Clearpath Robotics to do so.

Lifting and Transport

For the safety of users and to maximize the lifetime of Husky, please observe the following when manually transporting the robot:

- Husky should be lifted by two persons, firmly gripping the front and rear bumper-bars. The battery can be removed to lighten the load of a manual transport.
- Ensure that Husky is e-stopped when transporting short distances and powered off when transporting longer distances.
- Note: It is not advised to push Husky, as this can cause damage to the motors

Performance Recommendations

Included in Husky are native software checks and limits to protect the vehicle. However, it is recommended to monitor the system's status during usage with `/diagnostics/rqt_robot_monitor`

It is also advised to have your software subscribe to the `/husky/data/system_status` topic. This topic provides useful information regarding voltages, currents and temperatures of the system in the following form:

Voltages: [battery voltage, left motor driver, right motor driver]

Currents: [total draw, left motor driver current, right motor driver current]

Temperatures: [Left motor driver temp, right motor driver temp, left motor temp, right motor temp]

The total current draw does not include the motors drivers; it is the current consumed by the MCU and user power ports. Husky's motors are rated to draw 8A continuous, but they will spike to several times this, particularly when traversing rough terrain and when turning on the spot. To reduce current draw, consider commanding wider-radius turns from your control software.

The temperature is measured in the motor drivers and on the motor casings; the coils inside the motor casings cannot be measured. Therefore, it is important to note that the temperature measured on the motor casings is a lagging indicator of the temperature of the coils inside the casing. Be aware of the delay in heat propagation on the motors during heavy use. The thermal limit of the system is 50⁰ C, and the system will shut down if this limit is reached

Monitoring these fields over longer periods of operation will allow you to ensure that you are not putting excessive wear on the motors.

GETTING STARTED

You are ready to go! This section details how to get Husky into action.

Before beginning, place Husky “up on blocks”, as described in the Safety section – make sure the wheels are clear of the ground.

Onboard PC Setup

If you purchased a computer from Clearpath Robotics with Husky, it is already installed, connected, and powered. Provided on this machine is the officially-supported ROS software for Husky, joystick teleoperation, and any sensor payloads purchased.

To set up your own onboard PC, please make sure you are running Ubuntu 12.04 with ROS hydro installed. The Husky software can be found at <http://ros.org/wiki/Robots/Husky>

Connecting Computer

Husky’s serial port is located in the user power panel accessible from the user area, shown in Figure 6.

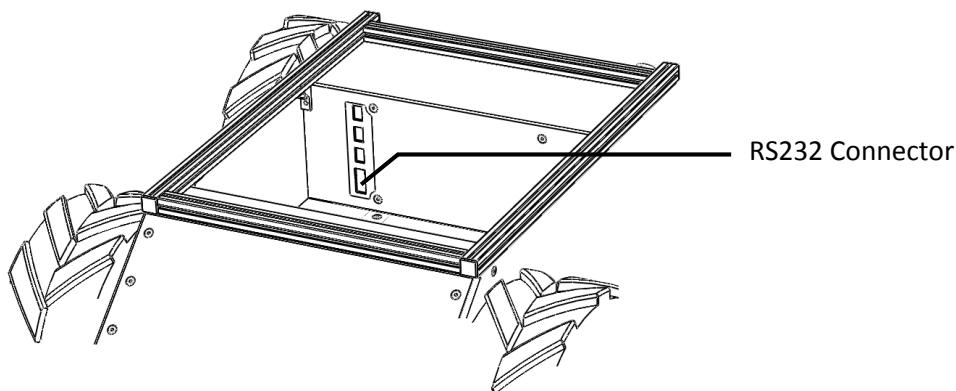


Figure 6: Husky RS232 Connector

The connector is a female DE9, suitable for connection directly to a USB-serial adaptor, or to a PC serial port via a straight-through modem cable (*not* a null modem cable). How you connect the PC to Husky depends on whether the PC has a dedicated serial port:

- **If your PC contains a serial port**, connect the male end of the provided serial cable to the female DE9 on Husky, and the female end of the cable to the male DE9 on the PC.
- **If your PC contains only USB ports**, connect the USB end of a USB-serial adaptor to the PC, and connect the male DE9 to Husky’s serial port.

Remote PC

Once you have a PC connected to your Husky with ROS installed, it is recommended to set up your Remote PC. Begin by either plugging the remote PC directly into Husky's router, or connecting to the same wireless network that your Husky was configured to connect to.



If your Husky is not yet connected to your wireless network, please refer to the RobotSmiths memo provided with your Husky.

It is now possible to communicate with Husky by either setting up a ROS master environment, or using SSH. To access the onboard PC, you can SSH into Husky:

```
$ ssh administrator@<IP_OF_HUSKY_PC>
```

Some features are not available through SSH, and it is recommended to set up a ROS master environment. In this situation, Husky will need to be configured as the master. To setup Husky as the master, refer to <http://wiki.ros.org/ROS/Tutorials/MultipleMachines>. **Note:** if you purchased a PC from Clearpath Robotics, Husky is already set as the master.

You can find the IP address of your remote PC using "ifconfig". To connect to the master on your remote PC, enter:

```
$ export ROS_MASTER_URI=http://<IP_OF_HUSKY_PC>:11311
$ export ROS_HOSTNAME=<IP_OF_REMOTE_PC>
```

You can then verify your connection by using:

```
$ rostopic list
```



If your Husky is equipped with an external radio that is connected to a subnet different than your remote PC, you will have to set up a static route to communicate with Husky. You can find the IP address of Husky's router using the routers built in interface or a third party application.

```
$ sudo route add -net <IP OF HUSKY> netmask 255.255.255.255 gw <ADDRESS OF EXTERNAL RADIO>
```

Connecting Power

Husky comes with the battery fully charged and installed, but disconnected for safety during shipping. To reconnect the battery:

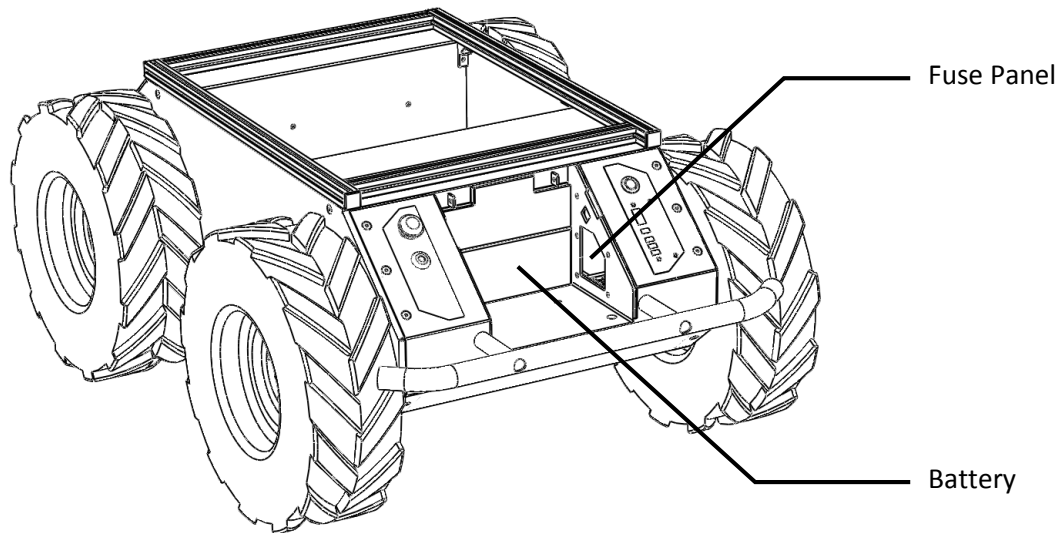


Figure 7: Husky Battery Area

1. Ensure Husky's main power button is in the outer "off" position and the e-stop is activated.
2. Using curled index fingers to grip the battery door latches, press with thumbs on the latch buttons and lift the battery door free of the chassis.
3. Carefully connect the battery plug to the mating connector in the fuse panel, shown in Figure 7. Ensure that it is firmly seated and clicks into place. It will be difficult to connect it in the incorrect polarity.
4. Replace the battery door cover, ensuring that it clicks into place and is flush with the rear panel.

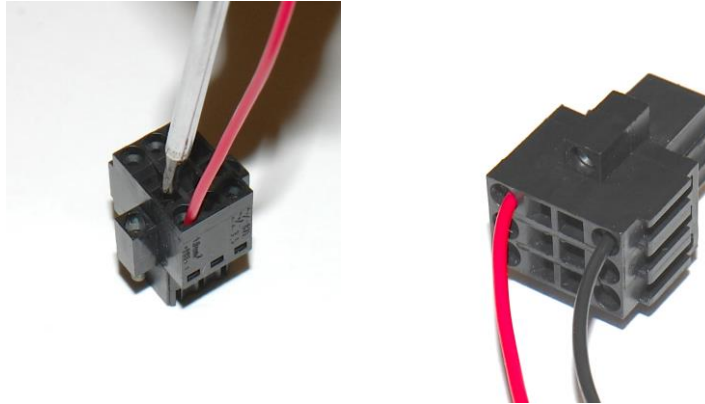
To power on Husky, firmly press the power button located above the status panel. It will illuminate blue, and the status panel lights will show a brief test pattern. The **comm** status light will turn red, as the PC is not yet communicating with Husky.

The stop status light will be red if the e-stop is pressed. If it is not, press the e-stop button and verify that the stop light illuminates. Leave the platform in an e-stop state until it is successfully receiving commands.

User Bay Power Connections

The user area power terminals are capable of supplying 5V, 12V, and 24V at up to 5A each for powering Husky's payloads. Each terminal comes equipped with a removable connector into which your payload power leads may connect.

To begin, expose about 5mm of bare wire from the payload power leads. The power connector features two openings on the top for each pin; a square hole and a round hole. Insert a 2mm wide flat head screwdriver into the square hole to "open" the adjacent round hole. Slide the power lead into the round hole, and then remove the screwdriver to lock the wire in place.



When connecting payloads be sure to observe correct polarity as marked on the inside of the user bay. Do not exceed the 5A maximum current limit of each power rail; failure to do so may result in damage to Husky or your payload.

Verification

If a computer was purchased with Husky, it will be setup to interface automatically upon startup. 60-90 seconds after booting up, the Husky comms light will change from red to green (or yellow, depending on e-stop status), indicating that ROS is up and has established communications with Husky.

To tele-operate Husky, plug a USB joystick into the included onboard computer, and release the emergency stop. After a few seconds, ROS should recognize the joystick and begin passing commands through to the mobile platform. Press the enable button (typically button 1), and use the main joystick axis or left thumbstick to drive Husky.

If Husky was purchased without a computer, ROS will need to be set up for use with Husky on a user-supplied PC. The intended model is for this PC to be running Ubuntu 12.0.4 LTS and have ROS Hydro installed <http://wiki.ros.org/hydro/Installation/Ubuntu>. Afterwards, instructions to download Husky software packages can be found at <http://ros.org/wiki/Robots/Husky>.

Direct control using the Python or C++ interfaces is also possible, the API is available at <http://www.clearpathrobotics.com/husky/downloads>. However, please note that Clearpath Robotics no longer provides support for these packages, and are supplied as is.

USING ROS

Robot Operating System (ROS) is an extensible framework for controlling and working with robotic systems. Clearpath Robotics recommends using ROS with Husky. If this is your first time using ROS, it is strongly recommended to run through our series of ROS101 blog articles to learn the basics of ROS <http://www.clearpathrobotics.com/blog/how-to-guide-ros-101/>.

Nodes

You can use `rostopic list` to see all the nodes running by default on a Husky computer. The baseline set of these is presented with commentary in Table 3.

/husky/husky_kinematic	Provides raw interface between serial protocol on Husky and ROS. Accepts motion commands on the <code>cmd_vel</code> topic, and provides feedback from Husky on the <code>data/*</code> topics.
/basic_basic_odom	Subscribes to the raw <code>data/encoders</code> topic and republishes an Odometry message and tf suitable for use with higher-level stacks like navigation .
/husky_base_diagnostics	Subscribes to other raw <code>data/*</code> topics and provides standard ROS diagnostics messages, suitable for visualization using runtime_monitor .
/husky_joystick /joy_node	These nodes connect to a joystick on <code>/dev/input/js0</code> and republish joystick-originated commands to the <code>cmd_vel</code> topic

Table 3: Standard ROS Nodes

Topics

You can view all topics that are active using `rostopic list`. Some of the base topics are listed in Table 4.

/husky/cmd_vel	Kinematic motion commands to Husky
/husky/cmd_freq	Reports how frequently Husky has received commands, useful to determine if commands were dropped over wireless
/encoder	Dead reckoning feedback from Husky
/diagnostics	System Diagnostic output
/husky/data/*	These topics provide system information to <code>/husky_base_diagnostics</code>

Table 4 Standard ROS Topics

Workspace

The expected model for extending Husky is to create a new ROS Workspace in the user's home directory, and add packages there. You can roslaunch additional nodes against the ROS Master already running on Husky without needing to stop or start anything else. See the Overlays page on the ROS wiki for more details: http://wiki.ros.org/catkin/Tutorials/workspace_overlaying

When it comes time for some of your own code to be launched on startup of Husky, edit the default workspace setup file, located in `/etc/ros/setup.bash`. Change the final line from the default to instead source your own workspace. When this is done, copy the launch file for your software into the `robot_upstart` folder, which is located at `/etc/ros/hydro/husky-core.d`. Now restart the Husky background service and your nodes should come up with the rest of Husky:

```
$ sudo service husky-core restart
```

For more details on this process, please see the ROS wiki page about upstart, located at: http://wiki.ros.org/robot_upstart

Payloads

You can find a list of supported packages and related documentation for payloads on Clearpath Robotics' ROS Wiki page here: <http://wiki.ros.org/ClearpathRobotics>

BATTERY & MAINTENANCE

Husky A200 is built for rugged, long-term use. Here are some steps that can be taken to maintain and extend the life of the platform even further:

Charging

The battery shipped with Husky A200 may be charged off-board, or while still inside of Husky. If charging while installed, you will need to open the access door to the battery area, and disconnect the battery from its connector in the fuse panel. From there:

1. Connect the DC output cable from the charger to the battery terminal connector.
2. Plug the charger power cord into the charger and then into a wall receptacle.
3. The POWER LED and CHARGING LED lights on the charger will illuminate.
4. When battery is fully charged, the CHARGING LED light will turn off. Unplug the charger from the wall, and then disconnect it from the battery.

The battery charger shipped with Clearpath Robotics' lead-acid battery-powered products uses a three-state charge cycle:

1. A fast, high current initial charge, until the battery voltage reaches 29.6V.
2. A topping charge, during which the battery charges at 29.6V constant voltage until the current decreases to 500 mA.
3. A precision float charge, during which the battery voltage is held at 27.6V. This mode allows the charger to remain connected to the battery during periods of non-use, keeping it in a state of full charge. When in this mode, the CHARGING LED will be off.

Battery Care

Husky's power supply is a sealed 24 V lead acid battery pack (VRLA), providing 20 ampere-hours of charge. To maximize the lifetime of the battery, recharge immediately after use, and keep charged to prevent loss in capacity. Battery life expectancy is shown in Table 4 and shelf charge retention in Table 5.

Cycles	Depth of Discharge
200	100%
225	80%
500	50%

Table 4: Battery Life Expectancy

Shelf Time	Battery Charge
None	100%
1 month	92%
3 month	90%
6 month	80%

Table 5: Battery Shelf Life

It is also recommended to power cycle Husky batteries at least once per month to maintain charge capabilities.

Husky's battery should never be used or stored in an environment exceeding 40 degrees Celsius (104 °F), and should always be charged at temperatures above freezing. At the optimal operating temperature of 25 degrees Celsius, the discharge time of the battery is seen in Figure 8.

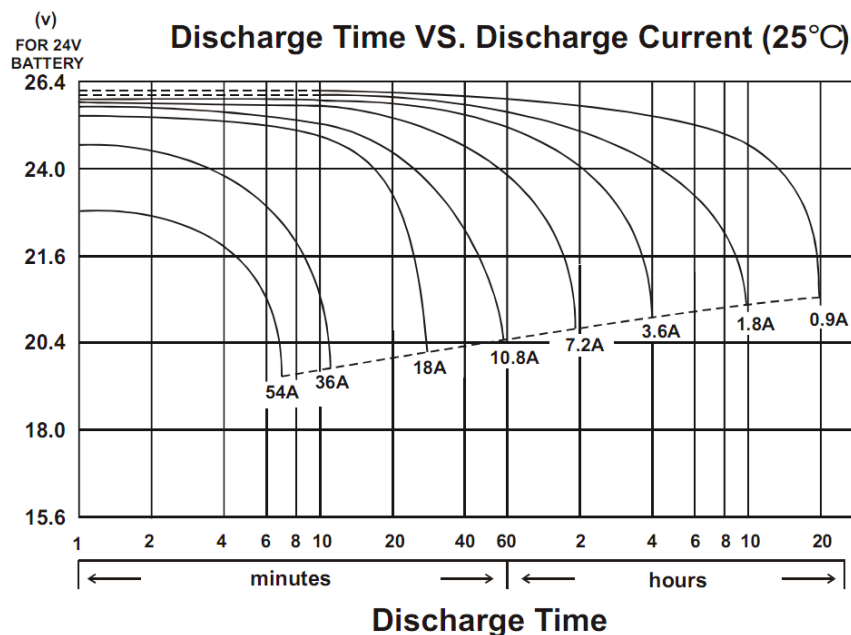


Figure 8: Husky Battery Voltage Characteristics

Wheels

Tire pressure may change with temperature and should be checked periodically with a pressure gauge. Inspecting tires, releasing pressure, and inflating tires are completed through the tire's inflation stem. Tire pressure should not exceed **20psi**, and lower pressure may be desired based on terrain requirements.

If a tire must be removed, first unfasten the four M5 Socket Head Cap Screws that join the wheel to the axle hub, and slide it off the axle. When replacing the tire, screws should be tightened to 3.7 ft-lb [5 N-m] torque.

Chassis

Husky is an all-terrain robot, but it is not waterproof. Care should be taken that no part of the main chassis is ever submerged in water. When the chassis becomes wet or dirty, wipe it down with a damp cloth and dry with a towel.

If water is suspected to have entered the Husky A200 chassis, remove the battery and allow Husky to fully dry for a minimum of 24 hours.

TIPS AND TROUBLESHOOTING

Mechanical Tips

Husky's wheels can handle a range of different terrains, but work best when inflated to the proper pressure. Lower tire pressures, for example **10 psi**, ensure better traction in rough and varied terrain, where rocks or other obstacles may be encountered. This has the adverse effect of lowering drivetrain efficiency and decreasing battery life, so high pressures up to a maximum of **20 psi** should be used when driving on flat surfaces.

Troubleshooting

This section lists a few possible issues which may be encountered:

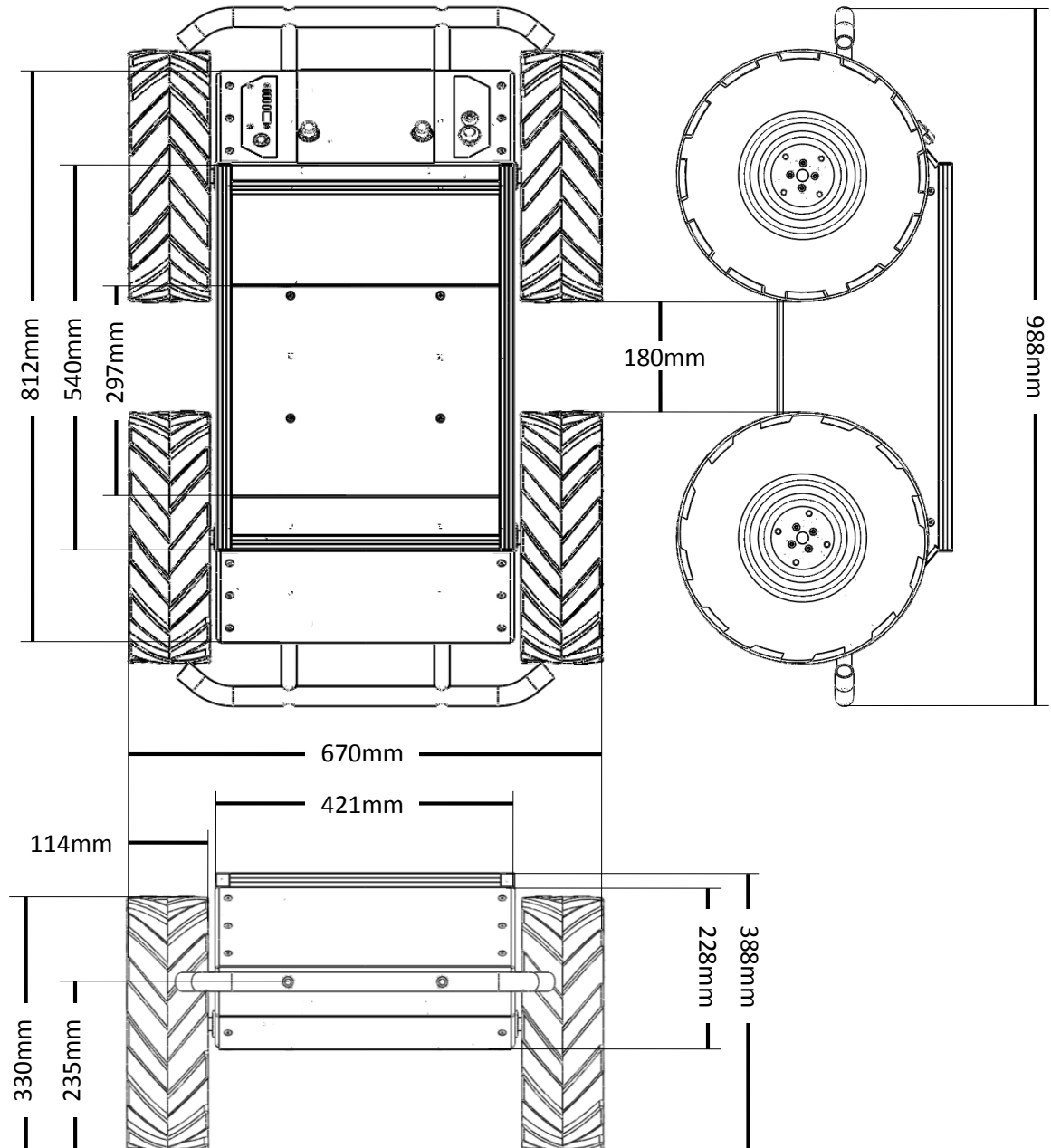
- **The blue light around the power button does not display when pressing the power button.** Ensure that the battery is charged and correctly connected. Use a multi-meter to verify the voltage on the battery terminals.
- **Comm light stays red/flickers.** Your program may not be sending motion commands faster than 10Hz. If there is a poor quality connection, some commands may be lost, so it may be necessary to increase the frequency of commands sent. The maximum frequency commands can be sent is 50Hz
- **E-stop light illuminated.** Twist the red e-stop to release it, and confirm that the robot is not locked out.
- **Battery indicator flashing.** Battery voltage is too low for Husky to drive the motors. Charge the battery and try again.

If you experience setup issues that aren't listed here, or the suggested solution isn't working out, please get in touch with our support team so we can help: support@clearpathrobotics.com.

FAQ

- **Q: After turning Husky 90 degrees, it reported that it turned more than that.**
A: A skid steer vehicle like Husky may slip when turning. The encoders cannot capture slippage and will report that the vehicle has turned more than in actuality. We suggest you couple the encoder data with an IMU that reports turns more accurately. The encoder and IMU can be combined using `robot_pose_ekf`. You can find information here http://www.clearpathrobotics.com/blog/blog_gps-using-pose_ekf/
- **Q: What is the Username and Password?**
A: Husky is shipped with the Username: administrator and password: clearpath
- **Q: How much power can be drawn from the user power lines?**
A: The absolute maximum recommended currents on each rail are as follows:
5V - 5A
12V - 4A
24V - 5A
Each rail is protected by a 5A fuse. For continued protection against risk of fire replace fuses only with those of the same type and rating.

A. PRODUCT DIMENSIONS



B. SERVICE AND SUPPORT

Clearpath Robotics is committed to your success and satisfaction. We are located in Kitchener, Ontario, and can accept phone calls from 9AM to 5PM EST Monday to Friday, at our toll-free number, or emails at any time. If you any questions or concerns, visit our support knowledge base for more information or to get in touch with our support team.

1-800-301-3863
support.clearpathrobotics.com