

Hardware optimizations for anytime perception and control

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I. PROBLEM SETUP

In this work, we focus on the particular case of autonomous corridor navigation. For this purpose we use the vanishing point algorithm [1], [2] and feedback control to maintain heading parallel to the corridor and stay in the middle of it. We implement our algorithm on a 1/10th scale car we developed.

A. The hardware

For our experiments, we converted a Radio controlled Traxxas Rally car into an autonomous robot shown in Fig. ??[carFig], similar to the ones used in [3]. The computation platform is a NVIDIA Jetson TK1. The Jetson has a quad-core ARM Cortex-A15 CPU and a NVIDIA Kepler GPU. This setup allows us to schedule tasks on the CPU or GPU while observing the effect of this on power consumption and timing of the algorithm. The Jetson runs Ubuntu for Tegra as the operating system, and the algorithms are implemented using ROS [4]. The control signals for the drive and steer motor on the platform are generated by a Teensy 3.1 microcontroller running a ROS node which converts the continuous output of the control software to a PWM signal that acts as an input to the motor controller on the Traxxas. Finally, the vanishing point algorithm implemented in OpenCV [5] gets images from a front facing Point Grey Firefly MV camera capable of recording color images at upto a resolution of 752x480 pixels and upto a frame rate of 60 FPS.

B. Vanishing point-based corridor navigation

The Vanishing point algorithm [1] has been used extensively in indoor settings for navigating corridors autonomously [2], [6] and for outdoor lane detection [7]. The algorithm outputs the horizontal distance of the frame's vanishing point and middle point from the center of the frame. These two measurement signals are used as feedback by the controller to center and align the robot along the corridor. Figure 1 shows a visualization of Vanishing point operating on a frame collected from our robot navigating in a corridor.

*This work was supported by STARnet a Semiconductor Research Corporation program sponsored by MARCO and DARPA, NSF MRI-0923518 and the US Department of Transportation University Transportation Center Program

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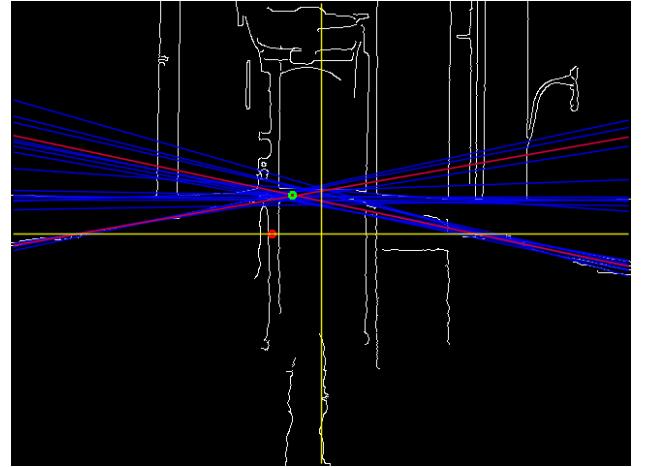


Fig. 1. Visualization of the Vanishing point algorithm. The green dot shows the vanishing point while the red dot shows the middle point.

We focus on the major computational tasks that comprise the vanishing point algorithm, which are briefly explained below:

- Blur: A Gaussian blur is applied on the image for denoising.
- Edge detection: We use the Canny Edge detector to find edges in the image.
- Hough Transform: used to detect straight lines in the image.
- RANSAC: used to select the parallel straight lines that best describe the sides of the corridor. These lines intersect in the image plane at the Vanishing Point.

C. Problem statement

Note, on the Jetson, we can schedule any of these tasks to be run on either the CPU or the GPU as shown in Fig. 2 In addition, we can also change the CPU and GPU frequencies during run-time, resulting in different execution times for the vanishing point algorithm and different power consumption for the Jetson. With this in mind, the problem we want to solve is that of picking the best operating mode for the perception algorithm, the vanishing point algorithm in our case, in order to minimize computation energy without overly affecting the closed loop control performance of the system. For this, we propose a two step solution and evaluate it for our problem setup. This is explained in more detail in the following sections.

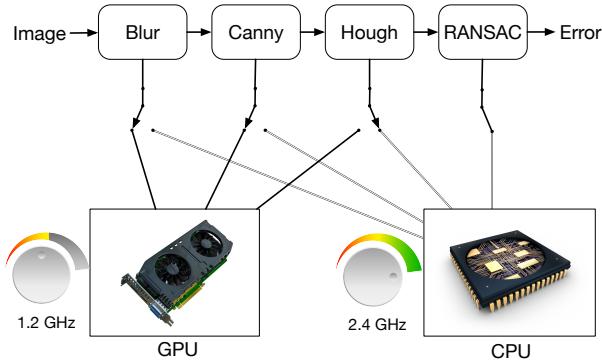


Fig. 2. The vanishing point algorithm with components running on either CPU or GPU at various frequencies, resulting in different power consumptions and execution times.

II. TWO STAGE APPROACH FOR HARDWARE OPTIMIZATIONS

A. Offline profiling of performance and power consumption of the perception algorithm

For the perception algorithm, the first stage of our method is profiling the performance (timing and, if available, quality) and power consumption of the computation. With the vanishing point algorithm, we can execute the Blur, the Edge detection and the Hough transform on either the CPU or the GPU (Fig. 2. RANSAC runs fast enough to not have a significant impact on the total execution time, so we do not consider running it on the GPU. Execution on the GPU results, in general, in a speed-up over the CPU but at the cost of higher power draw from the Jetson. Additionally, on the Jetson, we can control the performance of the CPU and GPU by changing the clock frequencies at which they operate. This gives us multi-dimensional knobs on the hardware level that we can control to trade-off computation speed and power consumption.

To do this profiling offline, we first navigate the robot manually in corridors and log video from the on-board camera at a high frame-rate (60Hz). We run Vanishing point algorithm on this video offline and profile it with different scheduling of the three components (Blur, Canny and Hough) on the CPU and GPU, and at different frequencies of both processors.

We wrote a custom C-code library to log power measurements from a Tektronix PWS4205 Programmable DC power supply at 100Hz. For this we communicate with the power supply over USB using the USB Test and Measurement Class (USB-TMC) communication protocol.

Since for an algorithm like Vanishing point there is no well-defined notion of ground truth, we do not have a measure of accuracy of the algorithm. Instead, Vanishing point's update rate (which is the inverse of the computation time) is used as a performance measure, since with faster updates the controller has less delay, resulting in better control performance.

1) Profiling: Experimental results: Figures 4 and 3 show the profiling results for the update rate of the Vanishing Point

algorithm for different CPU-GPU allocations of the 3 tasks and different frequencies of the CPU and the GPU. Note, the CPU can be clocked upto 2.32 GHz (on all 4 cores), while the GPU can be clocked upto 0.852 GHz. We select 6 operating frequencies evenly spaced from the minimum and maximum Jetson CPU and GPU frequencies for both the CPU and the GPU. In these figures, the 3 letter combinations encode the CPU-GPU allocation . For example, C G C means that the Blur was run on the CPU, Canny on the GPU and the Hough transform on the CPU.

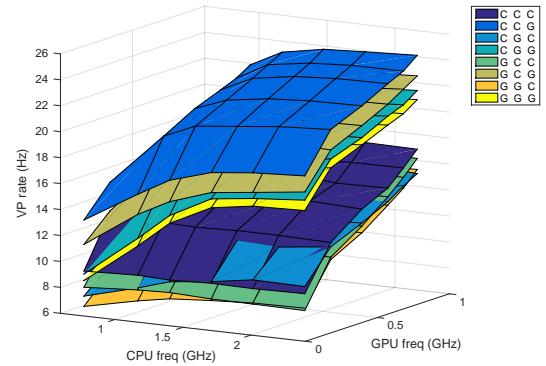


Fig. 3. Vanishing point algorithm update rate for different CPU-GPU assignments at varying frequencies (color in online version).

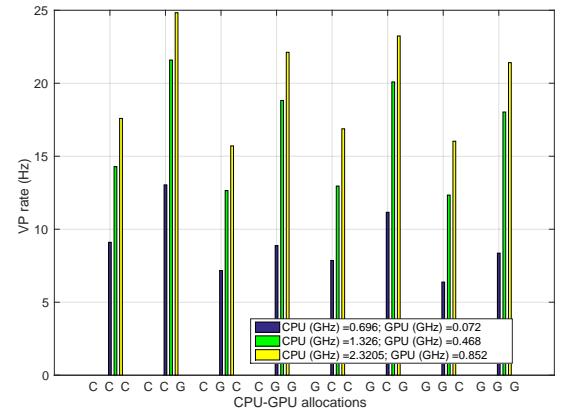


Fig. 4. Control update rate for different frequencies and a given CPU-GPU assignment. For clarity we only consider 3 CPU and GPU frequencies for this figure, ranging from the minimum to the maximum of frequencies of CPU and GPU. (Color in online version)

Figures 6 and 5 show the profiling of average power consumed during the computations for the vanishing point over all frames in the video used for the profiling.

B. Feedback driven online scheduling and hardware mode selection

From the profiling stage of the perception algorithm ??[section], we know that for a particular scheduling of the

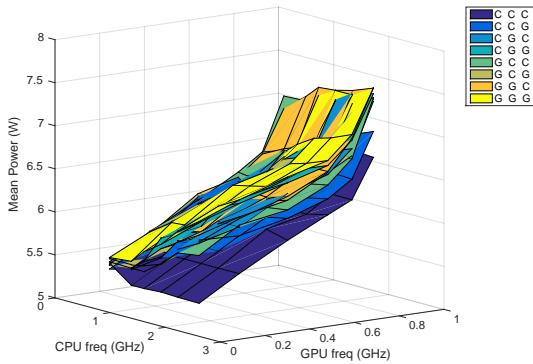


Fig. 5. Mean power consumed by the Jetson for different CPU-GPU assignments at varying frequencies. (Color in online version)

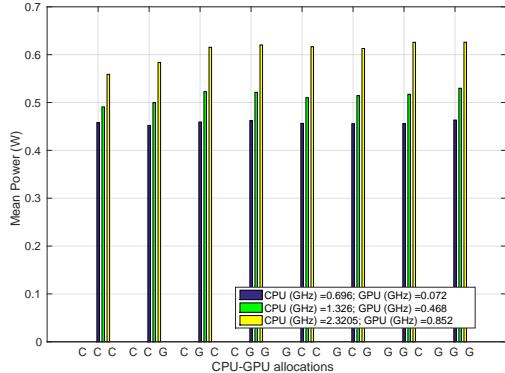


Fig. 6. Mean power consumed by the Jetson for different frequencies and a given CPU-GPU assignment. For clarity we only consider 3 CPU and GPU frequencies for this figure, ranging from the minimum and maximum of both the CPU and the GPU. (Color in online version)

components of the algorithm on the CPU or the GPU, we have varying throughput and power consumption profiles with changing CPU-GPU frequencies. With this profile, and the fact that less delay results in better closed loop control performance of a system, we can take a step towards formulating a scheduling (tasks on CPU or GPU) and hardware mode (CPU-GPU frequencies) selection problem to be solved at run-time. Consider maximizing at each time step t , a cost function of the form:

$$\max_{\sigma, F_c, F_g} \alpha(t) \bar{\mathbf{T}}(\sigma, F_c, F_g) + \frac{1 - \alpha(t)}{\mathbf{E}[\bar{\mathbf{P}}](\sigma, F_c, F_g)} \quad (1)$$

Here, σ denotes a schedule for tasks on the CPU or the GPU (see Fig. ??), F_c and F_g denote the CPU and GPU frequencies respectively. Remember, from the profiling in Sec. ??[section], that $\bar{\mathbf{T}}(\sigma, F_c, F_g)$ is the normalized throughput of the vanishing point algorithm under schedule σ and with the CPU and GPU at frequencies F_c and F_g respectively. Similarly, $\mathbf{E}[\bar{\mathbf{P}}](\sigma, F_c, F_g)$ is the normalized mean power consumed by the computation system at schedule σ and with

the CPU and GPU at frequencies F_c and F_g respectively. $\alpha(t) \in [0, 1]$ is a time-varying weight that decides how much to weight throughput versus performance at time step t . Note, higher $\alpha(t)$ is, more throughput is weighed. This varying $\alpha(t)$ results in different schedules and CPU-GPU frequencies for different times. It is worth noting that for a particular value of $\alpha(t)$, the optimal solution to Eq. 1 can be computed by composing the cost function from the profiled data and doing a search across parameters. In order to tie this to control performance, we can make $\alpha(t)$ a function of some feedback that reflects control performance, e.g. vanishing point abscissa or middle point abscissa or both. The function $\alpha(t)$ can now be composed such that as the vanishing point/middle point abscissas take on high values, $\alpha(t)$ also increases, resulting in a lower delay at the cost of more computation power. On the other hand, when the closed loop system is near or at steady state (vanishing point/middle point abscissas are small), we can trade-off computation delay (higher) in order to lower the computation power consumption.

III. SIMULATIONS FOR CLOSED LOOP CONTROL AND HARDWARE OPTIMIZATION

After profiling the performance and energy consumption of the Vanishing Point based perception algorithm, the next step is to leverage this information at run-time and close the loop with control based on the perception while being efficient with respect to computation energy.

A. Robot dynamics and control

In order to simulate the closed loop behaviour of the robot, we use a unicycle model for the dynamic and a non-linear feedback controller as explained in [2]. The unicycle dynamics are:

$$\begin{aligned} \dot{x} &= v \sin \theta \\ \dot{y} &= v \cos \theta \\ \dot{\theta} &= \omega \end{aligned} \quad (2a)$$

Here, v is the velocity of the robot, which we treat as a constant parameter for our setup. The co-ordinate frame is defined such that x is the distance of the robot from the middle of the corridor. Fig. ??[figureofunicycle] shows this. The goal of the closed loop controller is to navigate this robot along the middle of the corridor. Note, the controlled variable is ω , the desired angular velocity of the robot.

With the vanishing point based perception algorithm, the measurements from this system are the vanishing point and middle point abscissas as measured from processing the images from a front facing camera mounted on the robot. Using the geometry of the image frame as explained in [2], these measurements are

$$\begin{aligned} x_v &= k_1 \tan \theta \\ x_m &= k_2 \frac{x}{\cos \theta} + k_3 \tan \theta \end{aligned} \quad (3a)$$

Note, Eq. 3 shows that the vanishing point depends only on the orientation of the robot and the middle point depends on both orientation and position. The objective of our robot is to traverse a corridor while being as close to the middle of the corridor. In order to realize this, we need to bring both x_v and x_m to converge to zero. A non-linear controller based on the non-linear dynamics of the robot (Eq. 2 and the measurements of x_v and x_m to achieve this is (from [2])

$$\omega = \frac{k_1}{k_1 k_3 + x_m x_v} \left(-\frac{k_2 v}{k_1} x_v - k_p x_m \right) \quad (4)$$

Here, k_p is a positive proportional constant. To this controller, the time taken for computation of the vanishing point and middle point is a delay. In general, less delay means better control performance but as seen from the profiling of the vanishing point algorithm, this also means more computation power. Our goal is to achieve a trade-off where the control performance is acceptable (robot converges to the middle of the corridor) while the computation energy is minimized.

B. Online scheduling and mode selection

With the feedback in form of the vanishing point abscissa (x_v) and middle point abscissa (x_m), we can experiment with different functions to map the feedback to the weight $\alpha(t)$ in order to maximize the cost function of Eq. 1 and hence choose a schedule for the perception algorithm tasks and the CPU-GPU frequencies (see Sec. II-B). Since we know that higher values of x_v and x_m imply more work has to be done to align to the corridor and/or get to the center of the corridor, we can have functions for $\alpha(t)$ that are monotonically increasing with $x_v(t)$ and $x_m(t)$. Note, for our simulations we scale x_v and x_m to be between -1 and 1. For the simulations, we try out

$$\alpha(t) = f_1(x_v(t)) \text{ s.t., } \begin{cases} \alpha(t) = 0.001, & \text{if } x_v(t) \in [-d, d] \\ \alpha(t) = x_v(t) + d, & \text{if } x_v < -d \\ \alpha(t) = x_v(t) - d, & \text{if } x_v > d \end{cases} \quad (5)$$

This function depends only on the vanishing point abscissa x_v . The dead-zone magnitude, d is chosen to be 0.15 for our setup. Alternatively, we can try a similar function that depends only on the middle point abscissa.

$$\alpha(t) = f_2(x_m(t)) \text{ s.t., } \begin{cases} \alpha(t) = 0.001, & \text{if } x_m(t) \in [-d, d] \\ \alpha(t) = x_m(t) + d, & \text{if } x_m < -d \\ \alpha(t) = x_m(t) - d, & \text{if } x_m > d \end{cases} \quad (6)$$

IV. SIMULATION RESULTS WITH PROFILED DATA

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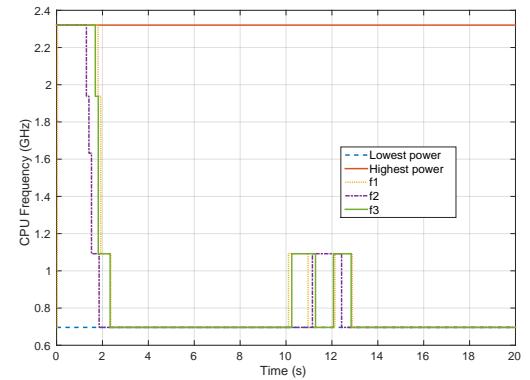


Fig. 7. CPU Frequency selected versus time.

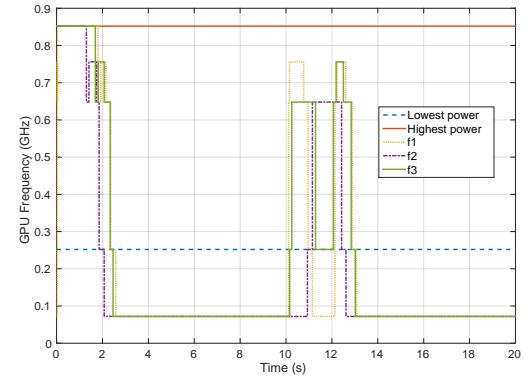


Fig. 8. GPU Frequency selected versus time.

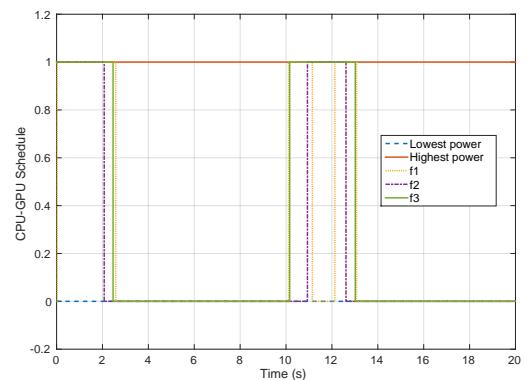


Fig. 9. Resource allocation schedule for the vanishing point algorithm.

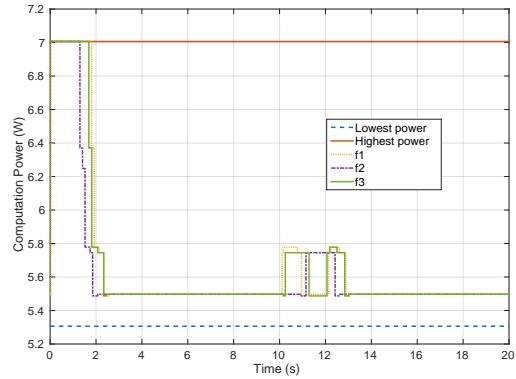


Fig. 10. Expected computation power for running the vanishing point on the Jetson.

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