

ARISTOTLE UNIVERSITY OF THESSALONIKI

SLAM for Autonomous Planetary Exploration using Global Map Matching

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Abstract

Write abstract here...

Contents

Abstract	iii
Contents	v
List of Figures	vii
List of Tables	ix
1 Introduction	1
1.1 Motivation	1
1.2 Problem Statement	1
1.2.1 Presumptions	1
1.3 Literature Review	2
1.3.1 SLAM	2
1.3.2 Planetary Absolute Localization	2
1.4 Thesis Objectives and Outline	2
1.4.1 Research Objectives	2
1.4.2 Outline	2
2 System Architecture	3
2.1 System Overview	3
2.2 Data Registration	3
2.2.1 Point Cloud Processing	4
2.2.2 Map Prediction and Update	4
2.3 Data Fusion	5
2.3.1 Sensor Fusion	5
2.3.2 Neighborhood Fusion	5
2.4 Pose Estimation	5
2.4.1 Initialization	6
2.4.2 Prediction	6
2.4.3 Update	6
2.4.4 Resampling	7
2.4.5 Estimation	7
2.5 Pose Correction	7
2.5.1 Global to Local Map Matching	8
2.5.2 Criteria Checking	9

	Elevation Features Checking	9
	Traversed Distance Checking	9
3	System Implementation	11
3.1	Library	11
3.1.1	Concurrency	11
3.1.2	Robotic Software Framework	11
3.1.3	Orbiter Data Preprocessing	11
3.2	System Architecture	12
3.3	Planetary Rover Testbed	12
4	Experimental Validation	13
4.1	Scope of Experiments	13
4.1.1	Environment	13
4.1.2	Metrics	13
4.2	Experiments on Pose Estimation	13
4.2.1	Relative Localization Results	13
4.3	Experiments on Global Map Matching	14
4.3.1	Absolute Localization Results	14
4.3.2	Map Resolution Viability	14
5	Conclusion	15
5.1	Thesis Summary	15
5.2	Contributions	15
5.3	Directions for Future Extensions	15
5.4	Applications	16

List of Figures

2.1	High Level Design Diagram	4
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List of Tables

List of Algorithms

Chapter 1

Introduction

1.1 Motivation

Mention the scope, its state, the current issues and what is needed to solve them

- Scope: planetary exploration (for scientific purposes)
- State: past and current missions, their purpose and outcome/state
- Issues: no constant communication, manual command sequence, unsafe/unpredictable conditions
- Needed: real-time and low-supervision system/platform

1.2 Problem Statement

Mention the environment and the robot's equipment and purpose

Mention that the problem is given X inputs to calculate Y outputs

- Environment: extreme planetary terrains with anomalies (rocks and craters) and high elevation variance
- Equipment: mechanical and sensor configuration
- Purpose: autonomous (low-supervision) navigation
- Inputs: odometry pose, sensor inputs, imu, global map
- Outputs: corrected pose, local elevation map

1.2.1 Presumptions

Explain what presumptions are made to the problem

- Initial global position is known
- Environment is static (not true for autonomous driving applications of algorithm)

- Environment is unknown (no high resolution a priori maps) (not true for autonomous driving applications of algorithm)
- Terrain is single layered (no bridges etc.)

1.3 Literature Review

1.3.1 SLAM

- What is SLAM
 - typical explanation in literature
 - categories
- How is SLAM implemented
 - volumetric/feature based approaches
 - grid-based fast slam
 - etc. etc. etc.

1.3.2 Planetary Absolute Localization

Mention how is absolute localization achieved in planetary applications

- Feature based approaches
- Skyline based approaches
- map based approaches

1.4 Thesis Objectives and Outline

1.4.1 Research Objectives

Mention what are the main objectives in terms of research

- Develop a novel technique for minimizing drift in global localization with global map matching and an execution strategy (criteria)
- Determine under what circumstances (i.e. resolution, local and global) can the orbital imagery be useful for SLAM
- Examine and quantify the gains (better localization, by providing a navigable map with the resolution and dense distribution restrictions that come with it) and losses (processing overhead)

1.4.2 Outline

Explain how this thesis is structured

Chapter 2

System Architecture

2.1 System Overview

In order for planetary robots to navigate autonomously in extreme and uncertain conditions where no GPS information is available, they need to perceive their surroundings with high precision and maintain this precision over time. A way of compensating for the lack of real-time GPS data, is to use an *a priori* global map that contains 3D information about the environment the robot is trying to navigate into. This map can be reconstructed using imagery taken from an orbiter and has a notably lower resolution compared to the robot's sensory data. To take advantage of this existing information, we have developed a system which is based around two layers of data processing.

In the first tier, the main objective is to capture the 3D structure of the environment using odometry, point cloud and IMU data from the robot's sensors. This is mainly achieved by adopting SLAM techniques to construct a local map and estimate the robot's current pose w.r.t. its initial pose. The latter, also called relative localization, is subject to drift in long-range traverses since all the input information is coming directly from the robot itself.

In the second tier, the objective is to achieve absolute localization by eliminating the accumulated position error of the previous stage. This is done by utilizing a matching technique to find the position of the robot's local map inside a global map.

The separation of the system to two layers comes from the need to process the data in separate moments, depending on the conditions of the environment as well as on the robot's processing capabilities. In Figure 2.1, the high-level design diagram of the system shows the 4 submodules that comprise the entire system. Their functionality will be explained in the following sections of this chapter.

2.2 Data Registration

Explain what is the purpose of this step

Explain the structure of the map and its properties

Explain the reference frame of the map with a figure

- Purpose: to register new sensor data in the local map

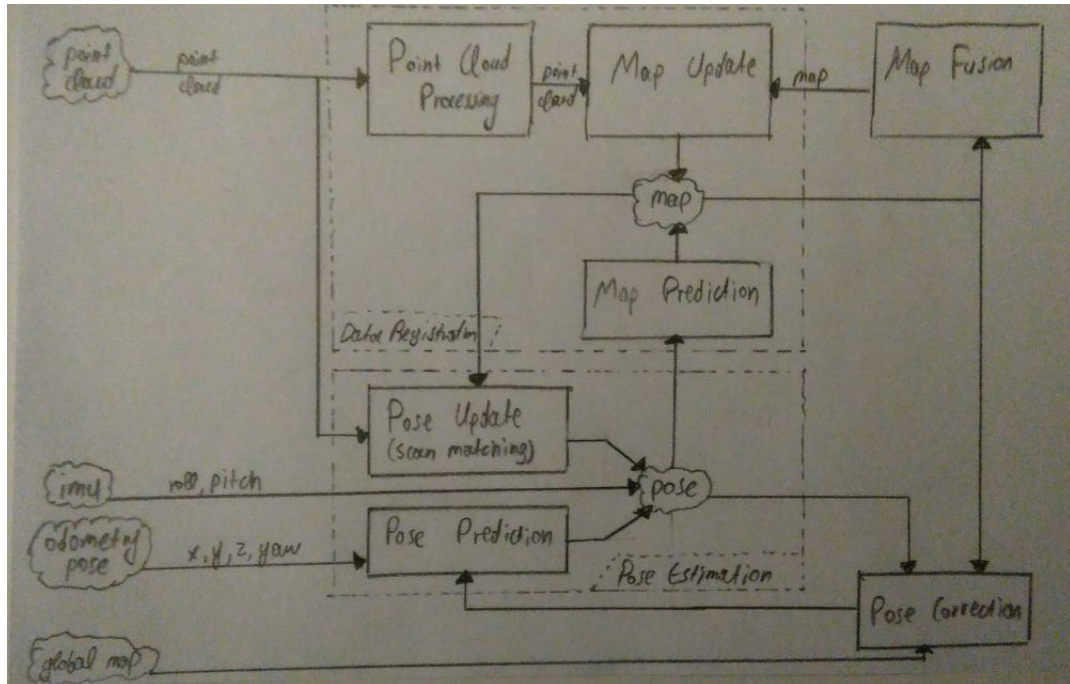


FIGURE 2.1: The high-level design diagram showing the submodules that comprise the system as well as the data flow.

- Map Structure: 4 layers (height gaussian + translation variances)
- Map Properties: resolution, length, min/max elevation, 2D position

2.2.1 Point Cloud Processing

Explain the processing steps of the input point cloud and why they are needed

1. Downsample with voxel grid to have less data (precision trade-off)
2. Apply TF to bring the points from the sensor frame to the robot frame
3. Crop to map size to discard out-of-bounds information
4. Calculate height variance of each point using the sensor's model to create a 1D gaussian

Add equations of the sensor model used to calculate the variances

Add figure of point cloud pre and post processing

2.2.2 Map Prediction and Update

Explain prediction and update steps

1. Prediction
 - (a) Apply delta pose translation (x and y) from particle filter to map

- (b) Update translation variances of each cell using translation model
- (c) Keep height gaussian of each cell unchanged

2. Update

- (a) Fuse each point of cloud to corresponding map cell by fusing gaussians
- (b) Keep translation variances (x and y) of each cell unchanged

Add gaussian fusion equations

Add figures of input point cloud and its projection in the map

2.3 Data Fusion

Explain what is the purpose of this step

- to get better sensor coverage by fusing multiple sensors
- increase map quality using the translation uncertainties

2.3.1 Sensor Fusion

Explain how sensor fusion is implemented

Mention that calibration errors in sensors as well as inaccuracies in the sensor transformations can cause the sensor fusion to over-smooth obstacles/features causing false negatives

Add figures of point clouds from different sensors and the resulting map from fusion

2.3.2 Neighborhood Fusion

Explain what is neighborhood fusion and the steps

For each cell of map:

1. Compute a weight for every neighbor cell according to distance/variance
2. Update mean/variance of cell using a weight-based fusion rule

Add equation for the weight calculation and the fusion rule

If visible, add figures showing the variance layers in the map, and the result of the fusion (prior and posterior mean elevation layers)

2.4 Pose Estimation

Explain what is the purpose of this step Explain the particle filter used Explain how IMU measurements are fused to get the final pose

- Purpose: to get a better estimate of the pose using the local map

- Particle Filter: continuous, estimates 3 states (x , y , yaw) etc.

Add figure showing the particle distribution around the robot

2.4.1 Initialization

Explain the step

1. Sample all particles at initial pose

Add gaussian sampling equation

2.4.2 Prediction

Explain the steps

1. Add gaussian noise to delta pose transformation from visual odometry
2. Apply transformation to each particle

Add prediction equations (trivial)

2.4.3 Update

Explain the steps

1. Crop local map to sensor's dimensions
2. Create point cloud from local map
3. Crop raw (input) cloud to map size
4. Downsample raw and map point clouds (for faster convergence of point cloud alignment)
5. For each particle
 - (a) Create particle point cloud by transforming map point cloud to particle's pose
 - (b) Measure particle and raw point cloud alignment using mean square error
 - (c) Assign inverse error as particle's weight

Add equations of point cloud alignment method for the weight update

2.4.4 Resampling

Explain the technique used, the steps and the strategy

- Technique: multinomial resampling
- Steps
 1. Normalize particle weights to form cumulative distribution
 2. Sample uniformly each particle from cumulative distribution
 3. Strategy: resample every X filter updates, depending on the robot's speed and the particle scattering (noise)

Add equations for forming and sampling from the cumulative distribution

2.4.5 Estimation

Explain the steps

1. Estimate pose from particle cloud:
 - (a) Ignore particles with weights below a specific threshold
 - (b) Pick top X particles
 - (c) Calculate new estimate by performing a weighted average of particles
 - (d) Calculate pose variance from the distribution of the particle cloud
2. Fuse IMU/Odometry states:
 - (a) Get roll and pitch measurements directly from the IMU
 - (b) Get z estimation directly from visual odometry
 - (c) Fuse IMU (laser gyroscope) yaw measurement with the PF's yaw estimate by means of 1D gaussian fusion

Add equations for calculating the mean and the variance values of the estimate

Mention that the robot's absolute z estimate is not of importance and why is that

2.5 Pose Correction

Explain what is the purpose of this step

Explain the execution strategy of this step

Mention known limitations of this approach

- Purpose: to minimize absolute localization drift using the global map
- Strategy:

- Generic: map needs to have features & robot must have covered certain amount of cells in the global map
- Planetary specific: correct pose by the end of the day (for energy efficiency reasons)
- Limitations:
 - When there are no features, the local to global map matching will fail
 - For safety purposes, the rover tries to generate a global path (using the global map) with as few features (i.e. rocks/craters) as possible

2.5.1 Global to Local Map Matching

Explain the steps

Explain why a template matching method is used instead of a feature-based one

1. Downsample local map to match global map's resolution
2. Calculate gradient (magnitude of the edge) of local and global map's elevation values
3. Replace unknown cell values with zero (does not affect matching)
4. Warp the local map to specific yaw angles to find a yaw correction
5. For each yaw angle: match local map to global map using template matching with normalized correlation coefficients Select or discard best match if score is above X (e.g. 95%)
6. Convert the matched position from image coordinates to map coordinates
7. Add gaussian noise to delta transformation (x & y) from matching
8. Apply transformation to each particle of particle filter

Add figures of:

- comparing Sobel edges with Scharr/Laplacian to justify the method
- source global/local maps in the scene (3D)
- source global/local maps in 2D
- downsampled local map
- gradients of global/local maps
- result image of matching with rectangles indicating the match & the ground truth match

Add equations of:

- nearest neighbor method for downsampling the local map
- gradient calculations (sobel kernel etc.)
- template matching method (normalized correlation coefficients)
- selection technique of best position from result image

2.5.2 Criteria Checking

Elevation Features Checking

Explain the steps and the threshold parameter selection

1. Create slope map from local elevation map by calculating the elevation gradient
2. Remove values in slope map below a specific threshold
3. Add remaining values to get absolute slope of map
4. Compare to threshold

Add equation for calculating the gradient and thresholding the map (image)

Add figures of final slope maps that succeed/fail the criterion

Traversed Distance Checking

Explain the step and the threshold parameter selection

1. Calculate traversed distance since last pose correction step
2. Compare to threshold

Add equation for the distance calculation (very trivial)

Add figures of robot traverses that succeed/fail the criterion

Chapter 3

System Implementation

3.1 Library

Mention GA SLAM library and tools used to create it etc.

3.1.1 Concurrency

Explain the algorithm's processing limitations and the circumstances under which it can run

Explain how concurrency can help and how it's implemented

Add timing diagram explaining the issues and how they are solved

3.1.2 Robotic Software Framework

Explain briefly ROCK, its tools, workflow and advantages/disadvantages

Explain briefly ROS etc.

Mention that the standalone library has interface to both frameworks

3.1.3 Orbiter Data Preprocessing

Explain that orbital imagery is emulated using drone imagery

Explain quickly how a 3D point cloud is reconstructed from the orbital imagery

Mention NASA's HiRISE (High Resolution Imaging Science Experiment)

Explain the steps for creating a global map from orbital point cloud:

1. Voxelize point cloud to the desired resolution
2. Crop the point cloud in the order of magnitude as local map's size
3. Smooth the point cloud using a SOR filter
4. Transform point cloud to robot's pose (using the initial absolute position)

Add figures of orbiter point cloud (raw & processed) and the orbiter map

Add figures from NASA's HiRISE depicting actual Mars point clouds

3.2 System Architecture

Explain how the algorithm can be integrated in a system and what components are needed (stereo, odometry etc.)

Add component diagram showing the architecture and how the different components are integrated

3.3 Planetary Rover Testbed

Explain lab's main rovers (HDPR & Exoter) and their mechanical/sensor configuration

Add figure depicting and explaining the rover(s)

Chapter 4

Experimental Validation

4.1 Scope of Experiments

Mention why mapping experiments are out of the scope

Explain briefly the purpose of the following experiments

Explain the type of the experiments

- Purpose: validate the algorithm and its robustness in various terrains and configurations
- Type: SIL tests (precollected data)

4.1.1 Environment

Explain the environment of the collected data (location, traversed paths etc.)

Add figures showing the said environment/traverses

4.1.2 Metrics

Mention the metrics used

- MSE of pose graph
- mean variance of pose graph,
- (execution times)
- etc.

4.2 Experiments on Pose Estimation

4.2.1 Relative Localization Results

Explain what the experiment is (test the accuracy of the particle filter)

Explain what is the expected accuracy of the estimation (1 cell size of local map)

Add bird's eye view of XY plot comparing:

- ground truth 2D position
- (Odometry)
- PF estimate

Add plot showing the error vs the number of particles used

Add plot showing the mean variance of the estimate vs the number of particles used

Add table showing the execution time vs the number of particles used

Add plot showing the error vs the resampling frequency

Discuss the above results and what are the advantages/drawbacks while tuning each parameter

4.3 Experiments on Global Map Matching

4.3.1 Absolute Localization Results

Explain what the experiment is (test the drift correction on long range traverses)

Explain what is the expected accuracy of the correction (1 cell size of global map)

Add bird's eye view of XY plot comparing:

- ground truth 2D position
- (Odometry)
- PF estimate without global correction
- PF estimate with global correction

Repeat test in environment with different distribution of features

(Repeat test in environment without features to show the limitation of the approach)

Add table with the matching accuracy of the different experiments

Discuss the threshold value that should be chosen on such environments

4.3.2 Map Resolution Viability

Explain what the experiment is (test under what resolutions can we expect a drift correction)

Add figure showing local & global maps with different resolution

Add table comparing global vs local map resolutions using the correction error (actual offset - matched location)

Discuss the global and local map resolution of the current Mars missions and how these will change in the future (e.g. NASA is planning to have 0.25m orbiter map resolution by 2020)

Chapter 5

Conclusion

5.1 Thesis Summary

Mention briefly what was discussed in this thesis and what the experiments proved

5.2 Contributions

Mention the research and the development contribution of this thesis

- Research contributions (same as objectives of Introduction)
- Development contributions (system features):
 - Suitable for rough terrain navigation by utilizing 2.5D (elevation) maps
 - Global pose correction using map matching of local (robot-centric) and global (orbiter) elevation maps
 - Sensor-agnostic data registration using point clouds (support for lidar, stereo camera, ToF camera etc.)
 - Automatic sensor fusion when multiple inputs are provided (without prior configuration)
 - Adaptive design to fit the needs of different robots and applications

5.3 Directions for Future Extensions

Mention future work and possible extensions to the algorithm

- Use a discretized particle filter to gain advantage of the grid nature of the map
- Use global map for complete (all initial cells) or partial (new unknown cells at the map's edge) of the local map
- Use the motion model in addition to using the particle cloud distribution to determine the estimated pose's uncertainty
- Use a method (e.g. SOR) to minimize outliers in input point cloud

- Apply a threshold to points in projected point cloud that fall in the same map cell
- Implement a strategy for selecting a match in template matching when matches with similar score are a. close to each other b. far from each other

5.4 Applications

Talk about other possible applications except for the planetary one

- Autonomous driving vehicles in urban environment using a priori 3D reconstructed maps (i.e. Google Maps) - although GPS data helps in avoiding the drift of dead reckoning, global map can still be used for local map initialization
- Autonomous driving in rough non-urban areas where no predefined paths exist and GPS usage is limited
- Lunar teleoperated robot with SLAM for augmenting the operator's perception - processing is done on the station (i.e. ISS) since stereo images are sent anyway