

Decentralized architecture for robust  
semi-autonomous logistics and  
construction robots

# Motivation

- Logistics robots are increasingly adopted in warehouse settings to improve efficiency, decrease downtime of various industry supply lines
- Robotics for construction are presently being evaluated in many forms, especially to aid in lifting heavy equipment/supplies
- Safe and collaborative robot control architectures can be used to increase productivity in both of these settings
- Decentralizing the control architecture can increase safety and robustness to signal drops, robot equipment malfunction, and other unforeseen failures

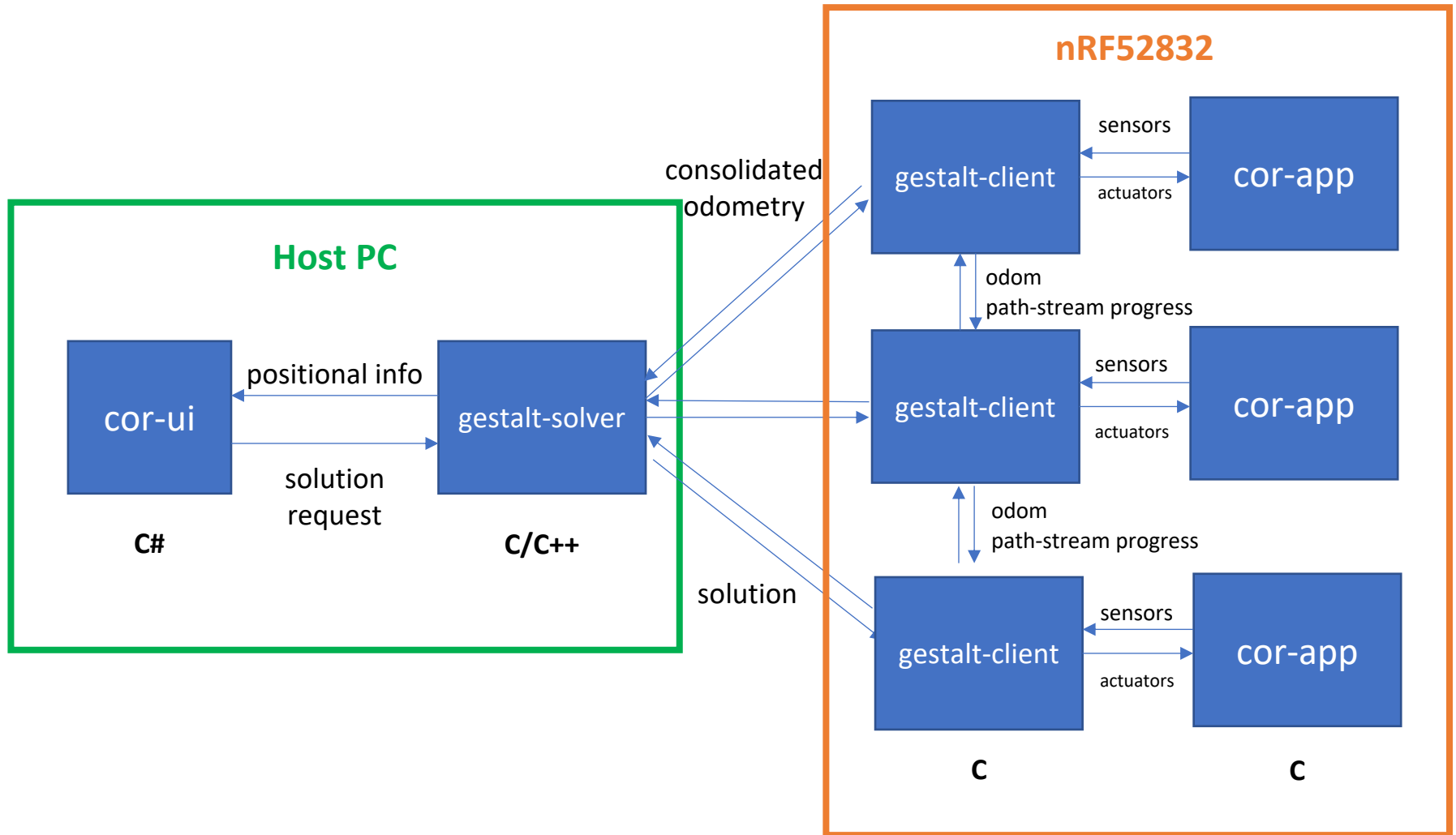
# Goal

- This project will demonstrate a decentralized robot control architecture by which a user-controlled interface prescribes an objective to a semi-autonomous robotics network. This network is then able to arrange props collaboratively in arbitrary patterns safely without further guidance from the operator and is robust to losses within the network.

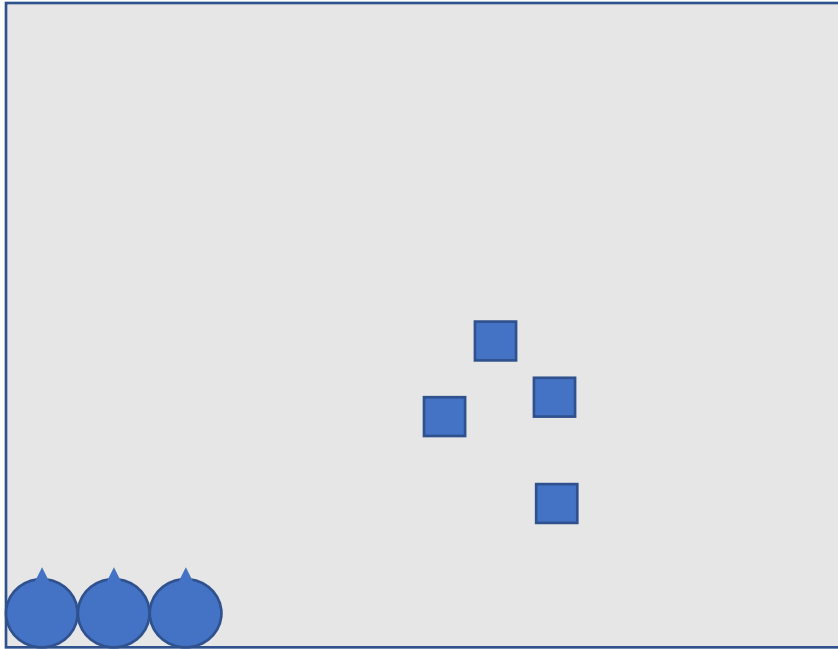
# Project Approach

- The project involves a demonstration of 2+ robots operating in collaboration within an isolated environment to arrange props in arbitrary patterns as assigned by an operator.
- At tasking-time, a solver will calculate a stream of paths for the robots to follow, and this path is then downloaded to all robots in the network.
- During execution-time, the operator is disconnected from the network, and the path-stream will be correlated with live sensor data on each robot to move toward the solution state. Furthermore, during this phase, state space measurements and path-stream progress will be communicated between all operating robots, enabling higher spatial certainty and decreasing chances of collision.
- To demonstrate loss-tolerance, all robots will receive redundant path-streams such that network members may be removed at any time and the same outcome will be achieved.

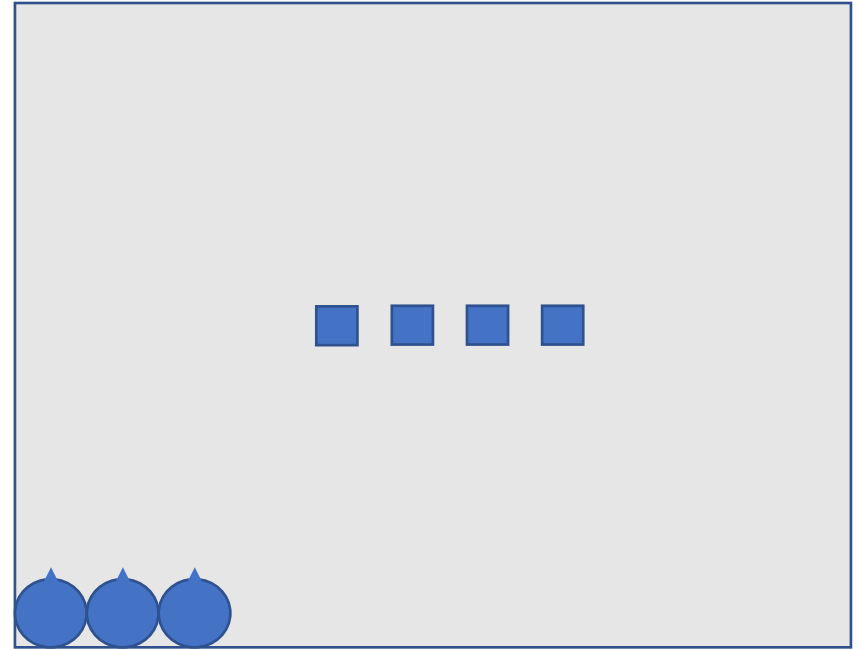
# Coarse-Grain Hierarchy



# Proof of Concept

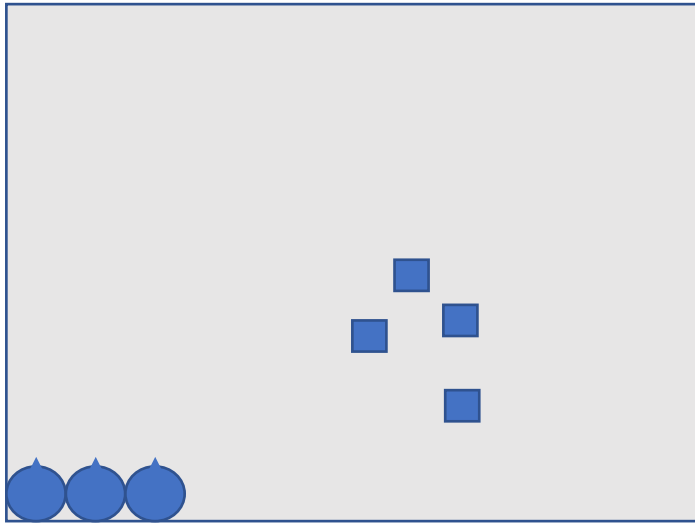


Starting condition

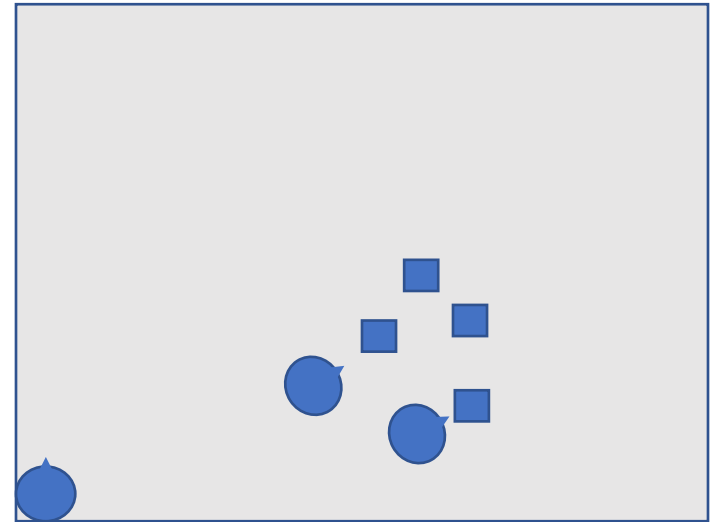


User-prescribed target

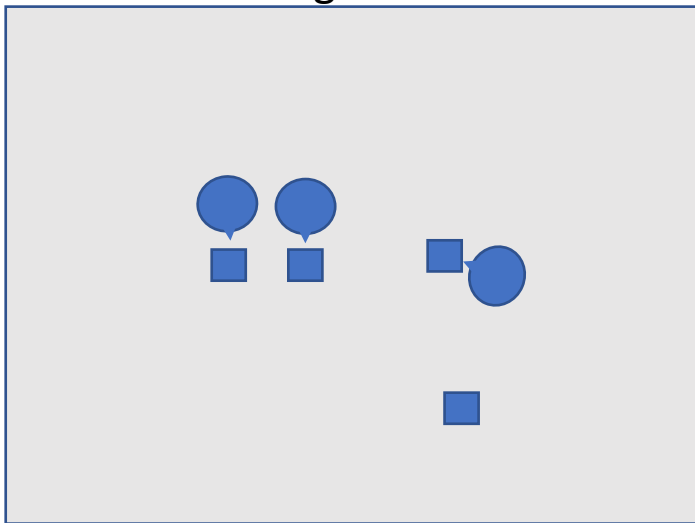
# Proof of Concept - Solver



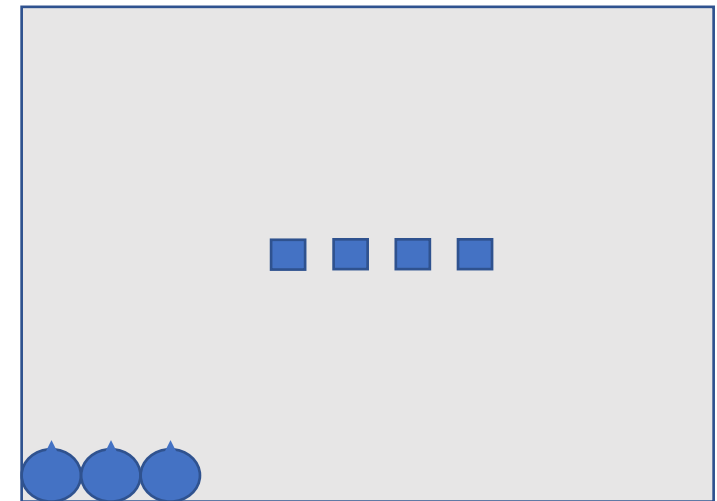
Starting condition



Step 1

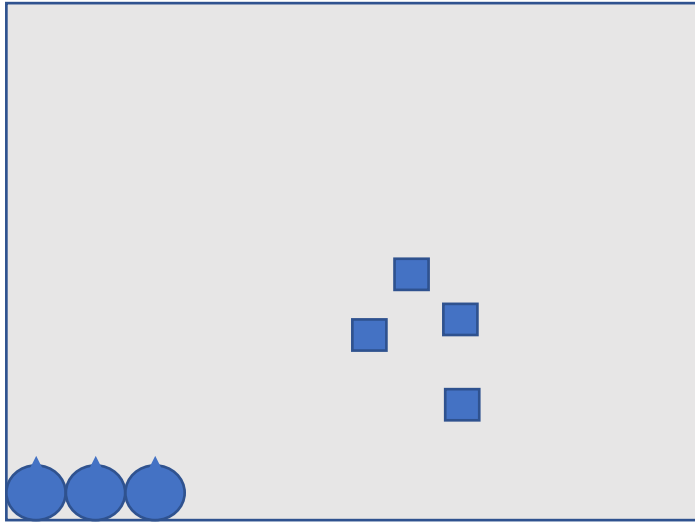


Step i

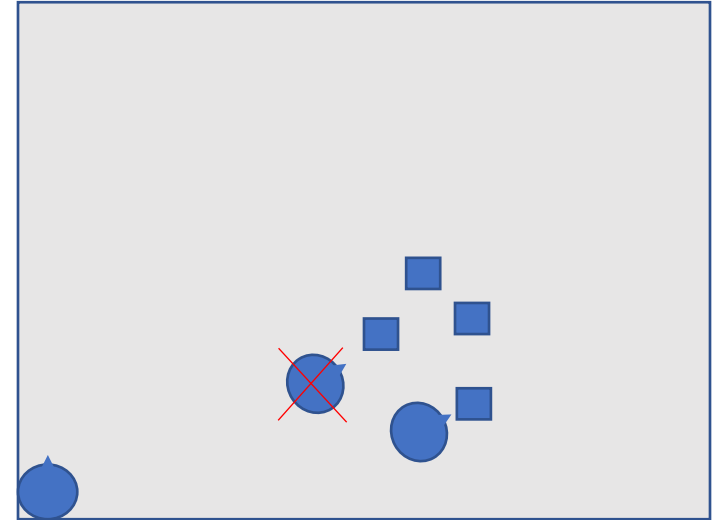


Step N

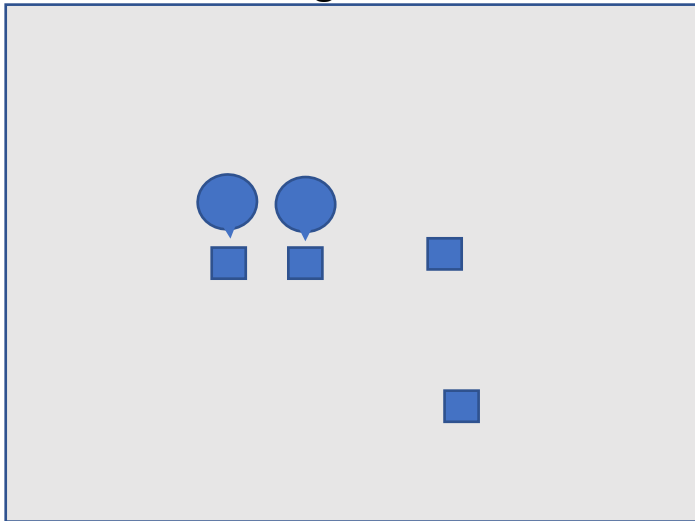
# Proof of Concept – Loss-Tolerant Solver



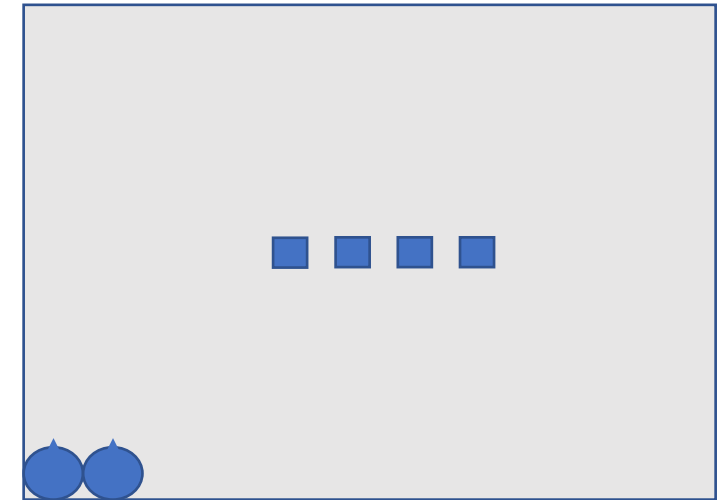
Starting condition



Step 1



Step i

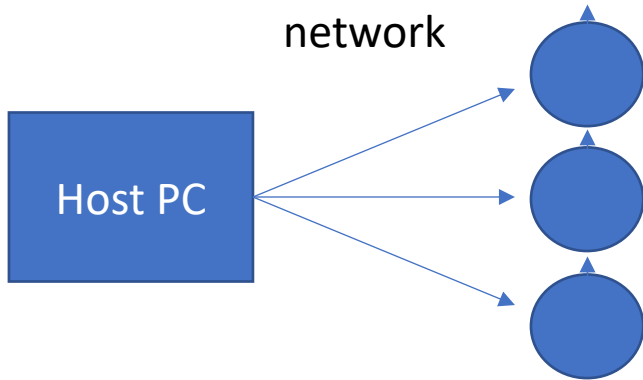


Step N



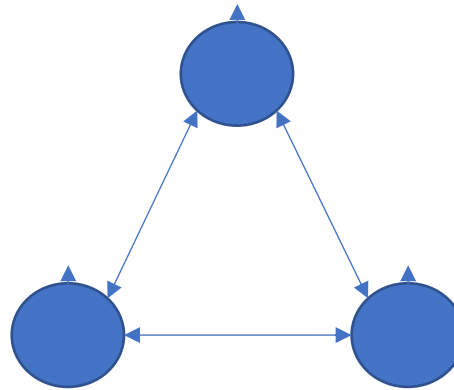
# Architecture

Solution path-streams  
are uploaded to robot  
network



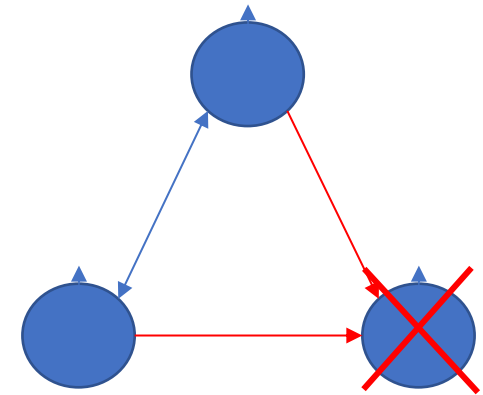
Architecture at tasking

Path-stream progress  
and odometry are  
exchanged



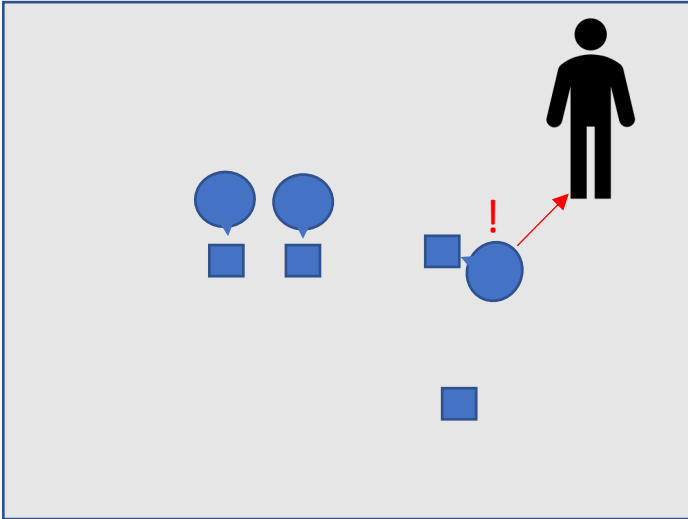
Architecture at execution

Remaining path-streams  
are consolidated and  
distributed between  
robots



Architecture at loss-time

# Safety



## **STOP**

If any single member of the network senses an unrecognized object within the operational space, all members will be stopped

## **RESUME**

All members of the network must confirm that the unrecognized object has exited the space before the entire network may resume

# Equipment

- 3x Robot platform – Kobuki
- SoC
  - nRF52832
- Sensors
  - Accelerometer from Buckler
  - Gyro from Buckler
  - [2D top-mounted LiDAR](#) \$100
  - Bluetooth from nRF
- Actuators
  - One-dimensional linear actuator to grip cubes
- Host PC
  - Any OS running Unity