Interactive Map Labeling for Service Robots

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Abstract— **Maps that include semantic information such as labeled structures, objects, or landmarks can be useful to service robotic systems. For example, we might want our service robot to be able to accept commands such as "fetch the mug from the kitchen table". To perform such a task, the robot should know the location and extent of the structure referred to by "kitchen table". We will describe a mapping system capable of creating maps of a type suitable to enable this type of task, and an interactive system for providing labels via a tablet UI and gestures.**

I. INTRODUCTION

Maps that include semantic information such as labeled structures, objects, or landmarks are more effective for interaction with humans and the semantic information may be essential context for motion control and navigation. For example, we might want our service robot to be able to accept commands such as "fetch the mug from the kitchen table". To perform such a task, the robot should know the location and extent of the structure referred to by "kitchen table". As another example, we might want the robot to be able to follow directions through an indoor environment, which might include commands such as "go down the hallway". To do this, it is useful to have a map that includes a representation of the location and extent of the hallway. In this way, we must establish "common ground" [3] for communication, by grounding these labels to landmarks in the robot's map.

A simple approach to adding labels to robot maps would be to attach labels to specific coordinates in the map. For example, we might attach a label "kitchen table" to coordinate $(2.4, 7.12, 0.0)$ in our map. Such an approach fails to capture the layout of the structure designated by the label, which might be important to tasks such as searching an object on the table. In addition, point based references may be ambiguous for a region or volume in a map, such as a hallway or room. For this reason, we will take an approach that allows us to represent both location and extent of landmarks to these labels.

Our approach is to employ a feature-based mapping system that uses planar surfaces detected in point cloud data as landmarks. Planar surfaces are used for SLAM by using their surface normals and the range to the plane, and the landmarks are bounded by their convex hulls. Maps composed of such features can accurately represent the locations and extents of landmarks such as walls, tables, shelves, and counters.

Many important landmarks may be represented as single planar structures that have unique labels, such as "coffee table" or "front door". Other labels might correspond to regions of a map bounded by multiple planar landmarks, such

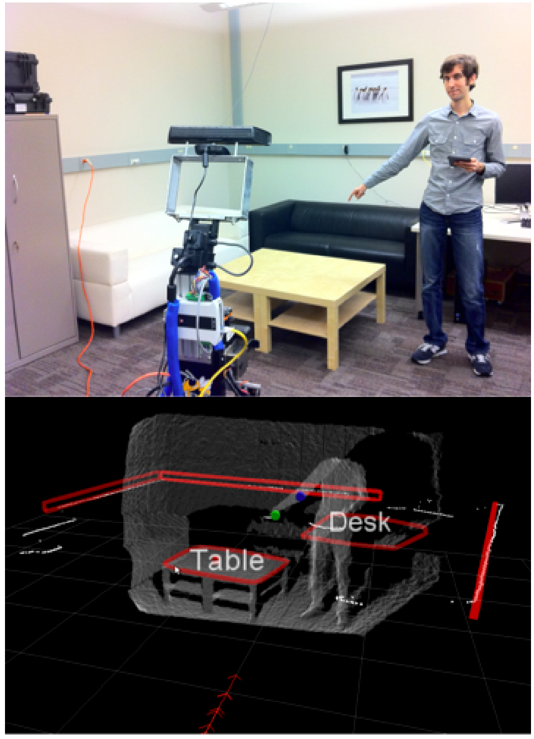

Fig. 1. Top: A photo of a user pointing at a nearby table, after entering the desired label on a handheld tablet UI. Bottom: A visualization of the robot's map and sensor data. Red outlines represent the convex hulls of mapped planar features. The detected gesture can be seen via the green sphere at the user's hand, the blue sphere at the user's elbow, and the red sphere (near the "a" in Table) indicating where the pointing gesture intersects a mapped plane.

as the walls of a room or hallway. If a user labels multiple planar landmarks with the same label, such as the four walls of a room, or two walls of a hallway, it specifies a region of space corresponding to this label by finding the convex hull of the extent of all planar features with that label. In this way, we can label both specific important landmarks such as tables or shelves, or regions such as rooms, hallways, or cubicles.

To label this type of map, we have developed an interactive system that uses a combination of a tablet based user interface and pointing gestures. Using this tablet interface, users can command the robot to follow them through a mapped environment, as well as entering labels for nearby features. Labels are entered using an on-screen keyboard, pressing the "label" button, and then performing a pointing gesture at the feature that should be annotated with this label. Pointing gestures are recognized using a Microsoft Kinect and OpenNI. The mapped landmark indicated by the pointing

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gesture is then annotated with the entered label. An example of the labeling process, as well as a map generated by our system is shown in Figure 1.

A brief survey of related work will be given in Section II, followed by a detailed description of our approach in Section III. Results are presented in Section IV, followed by a conclusion in Section V.

II. Related Work

There are several areas of research related to ours. The most closely related approach to our own is that of Human Augmented Mapping (HAM), introduced by Topp and Christensen in [23] and [22]. The Human Augmented Mapping approach is to have a human assist the robot in the mapping process, and add semantic information to the map. The proposed scenario is to have a human guide a robot on a tour of an indoor environment, adding relevant labels to the map throughout the tour. The HAM approach involves labeling two types of entities: regions, and locations. Regions are meant to represent areas such as rooms or hallways, and serve as containers for locations. Locations are meant to represent specific important places in the environment, such as a position at which a robot should perform a task. This approach was applied to the Cosy Explorer system, described in [27], which includes a semantic mapping system that multi-layered maps, including a metric feature based map, a topological map, as well as detected objects. While the goal of our approach is similar, we use a significantly different map representation, method of labeling, and interaction.

Another related body of work is that of semantic mapping, which aims to create maps that include various types of semantic information to allow the robot to have a richer representation of the environment. Many approaches have been taken, some of the key works include the Spatial Semantic Hierarchy (SSH) of Kuipers [11], the semantic mapping work of Martínez-Mozos and Rottmann [13] [17], as well as the place categorization of Pronobis *et. al* [16].

There are several works related to our mapping approach. Our mapper takes a smoothing and mapping approach based on the work of Dellaert [4], which we use with our own planar landmark mapping technique. Others have also proposed different solutions to using planar features for mapping, including Weingarten [25], Pathak *et.al.* [15], and Rusu *et. al.* [19].

The problem of following a person with a mobile robot has found a lot of interest in the literature. One of the methods to track people is to detect legs in laser scans [1], [21]. One other common method is to use face or blob detection and fuse it with laser-based methods [9]. More recently, depth cameras have been used to detect and follow people. Loper [12] presents a system that follows a person and recognizes speech commands as wells as non-verbal gestures. In this work, specifically designed arm gestures were used to start/stop following and give lower level motion commands to the robot. There also has been some work to recognize natural gestures, such as the gesture of pointing to a direction. Nickel [14] estimated the pointing direction by detecting the head and hand in a stereo image. Steifelhagen [20] used a similar approach to detect pointing gestures and used it in the context of Human-Robot Interaction. Fong [7] describes a robot that can be controlled by both arm gestures and a handheld device. Dias [6] have used a multi-modal interface combining speech and gesture in a tablet computer for a multi robot - multi user setting. Using touch screen devices as the main User Interface(UI) is common for robots [8].

III. Approach

Our technique allows maps composed of planar surfaces to be interactively labeled. First, a metric feature-based map of the environment is collected, which can then be labeled. Users interact with the robot via a handheld tablet interface, shown in Figure 4. Users can command the robot to follow them through the environment, and can provide labels for nearby features. The same functionality could be achieved using a speech dialog system, but such interfaces tend to have a high error rate [5] and ultimately we decided to use a the tablet as a more robust way of communicating with the robot.

The expected usage scenario is similar to that of the Human Augmented Mapping approach, where a user can command the robot to follow them on a tour of an environment, and stop to annotate important landmarks and regions. The gesture recognition system allows users to precisely indicate specific landmarks to be annotated, avoiding ambiguities. The person following system enables the user to bring the robot to any relevant location, close to the landmarks that the user wishes to label.

In this section, we will describe our approach in detail, and provide details on our system that implements this approach. Our system makes use of the ROS software infrastructure for interprocess communication and message passing. A system diagram is shown in Figure 2, which demonstrates the overall structure of our system.

A. Mapping System

Our feature-based mapping system makes use of the Georgia Tech Smoothing and Mapping library (GTSAM) of Dellaert [4]. GTSAM solves the smoothing and mapping problem using factor graphs that relate landmark poses to robot poses. The factors are nonlinear measurements produced by measuring various features. New factor types can be defined and used by specifying a measurement function along with its derivatives with respect to the robot pose and the landmark pose. The resulting factor graph can be used to optimize the positions of the landmarks as well as the robot poses. Note that we are solving the *full SLAM* problem, recovering not just the current robot pose, but the full trajectory along with the landmark poses.

Our mapping system makes use of the GTSAM optimization and inference tools, and defines a variety of feature types that can be used for SLAM and semantic mapping. We have defined features which correspond to discrete entities in the world, such as planar surfaces or door signs, which

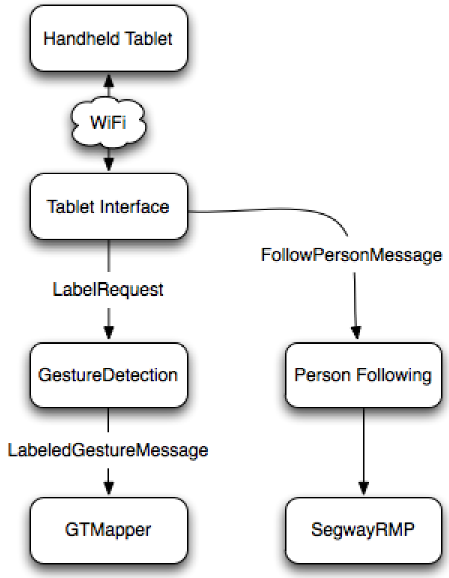

Fig. 2. A system diagram of our approach.

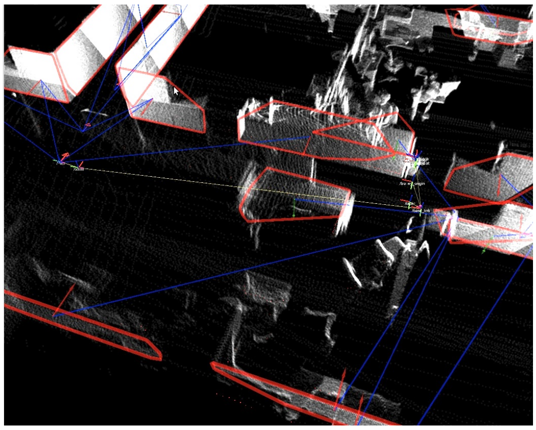

Fig. 3. An example of a map generated by our system. The map shown is of an office environment. The map includes palanr surfaces such as walls, tables, and desks, as shown by the planar surfaces outlined by the red convex hulls. Surface normals are also displayed in red, on the centroids of the landmarks' hulls. The robot's trajectory is shown as a sequence of red arrows, and blue lines between trajectory poses and landmarks indicate the landmarks measured from that pose. The pointclouds used to construct the map have been registered in the map frame, and are displayed in white, for visualization purposes only – full point clouds are normally not needed.

can optionally be labeled. A detailed description of earlier work on this system using 2D line measurements as features is presented in [24]. In this work, we will use only consider one type of landmark: planar features detected in point cloud data, which are represented by their surface normal and range, and bounded by a convex hull. These landmarks can be measured either via sensors that detect point cloud data, or 2D measurements can be made on them using a 2D laser scanner. Planar measurements only measured by 2D sensors are assumed to be vertical.

3D laser scanners or RGB-D sensors such as the Microsoft Kinect can be used to collect suitable data. Planes are then extracted from the point cloud by an iterative RANdom SAmple Consensus (RANSAC) method, which allows us to find all planes meeting constraints for size and number of inliers. A clustering step is also performed on extracted planes in order to separate multiple coplanar surfaces, such as two tables with the same height, but at different locations. We make use of the Point Cloud Library (PCL) [18] for much of our point cloud processing.

Planes can be represented by the well known equation: $ax + by + cz + d = 0$. Our mapper then represents the planes as: $p = [n, hull]$ where: $n = [a, b, c, d]$ and $hull$ is a point cloud of the vertices of the plane's convex hull. As the robot platform moves through the environment and measures planes multiple times, the mapped planes' hulls will be extended with each new portion seen, allowing the use of large planes such as walls where the full extent is typically not observed in any single measurement.

An example demonstrating the map representation is shown in Figure 3.

B. Gesture Recognition

We use pointing gestures as a natural interface between the robot and the user. The pointing direction is used to find out which planar surface the user is pointing to. To detect people in the environment, we have used a Microsoft Kinect RGB-D sensor with OpenNI natural interaction framework for skeleton tracking. OpenNI necessitates the person to make a calibration pose to start skeleton tracking. This limitation actually serves to our purposes since we allow only one user to be in control and the person who does the calibration pose is chosen to be the user. Pointing gesture detection is initiated when a LabelRequest message is received, which contains the label entered by the user. The gesture is then searched for T seconds. Let's denote ${}_s e$ and ${}_s h$ as the elbow and hand position of one arm in the sensor's coordinate frame. Two conditions has to be satisfied to trigger a pointing gesture:

1) $\frac{{}_s e_z - {}_s h_z}{|{}_s e - {}_s h|} > sin(\phi_g)$
2) ${}_s e$ and ${}_s h$ stays almost constant for some duration Δt_g.

First condition requires the forearm not to be on the side of the body and second ensures that the gesture is consistent for some time period. We have used $T = 30s$, $\phi_g = -45\,°$ and $\Delta t_g = 0.5s$. Whenever the pointing gesture is triggered, a LabeledGestureMessage, and received by the mapper. The mapper then applies the coordinate transformations ${}_m e = ({}_m T_s){}_s e$ and ${}_m h = ({}_m T_s){}_s h$, which allows us to find all the planes that intersects the ray emanating from ${}_m e$ towards ${}_m h$ in the map frame. When testing if the ray intersects with a given plane, we also enforce that the intersection point lies within the convex hull of this landmark. If the ray intersects with multiple planar landmarks, the closest one to the user's hand is selected.

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C. Person Following

Person tracking is achieved by detecting legs in the laser data acquired from a laser scanner placed parallel to floor at ankle height. First, laser data is segmented. Two adjacent distance measurements are considered to be in the same segment if the euclidian distance between them is below a threshold. Then the segments are scored according to their likelihood to be a leg. In a laser scan, legs can appear in different patterns [21]. We track only one *Single Leg(SL)* pattern. Three geometric features of a segment are calculated for leg detection: Segment Width, Circularity and Inscribed Angle Variance(IAV)[26]. We captured several laser frames while both the robot and the person are mobile and manually labelled about 1.7×10^4 *SL* patterns. For the training set, two people's legs are recorded with different clothing (i.e. shorts, baggy pants, trousers). Mean and variances of leg features are calculated and are used as constants for leg detection.

For a segment, the leg features are calculated and the weighted mahalanobis distance to the mean leg features is calculated. If the mahalanobis distance is below a threshold, the segment is elected to be a leg. While the leg is being tracked; a fourth parameter, the proximity of the segment center to the estimated position of the leg, is also considered. The leg is tracked with a Kalman Filter in the odometry frame using a constant velocity model. When no segment is below the leg distance threshold, the tracker expects the leg to reappear in the same location for some time, before declaring the person is lost. This allows to handle no-detection frames and temporary occlusions(i.e. another person passes between the tracked person and robot). The mean and variances of leg features are adaptively updated using the last 20 frames, so that the tracker adjusts to the leg shape/clothing of the person after the initial detection. After the high level command of following received, the person to follow is selected by detecting a significant movement by a leg segment in a rectangular region in front of the robot.

The leg position is considered as the position of the person and a goal location is determined so that the robot is 0.8m away from the person and oriented towards him/her. The goal position is re-calculated at every time a laser scan observation is made and is provided to a local navigation planner. We have used the Robot Operating System (ROS) navigation stack to achieve the person following behavior.

D. Tablet UI

A tablet-based interface was developed to enable interaction between the user and the robot. This was chosen over a speech recognition interface, as we believe it will be more accurate and less error prone than the available speech recognition systems. The interface has been implemented on a Samsung Galaxy Tablet running the Android OS. The tablet is equipped with 802.11 WiFi, and can communicate with a ROS node running on our robot via a TCP socket.

The interface contains a series of buttons which can be used via the tablet's touch screen. A screenshot of the tablet's UI is shown in Figure 4. This interface can be used to command the robot to follow the user, stop following the user, annotate landmarks with labels, and navigate to labeled landmarks. Labels are entered via the tablet's on-screen keyboard, and sent to the robot.

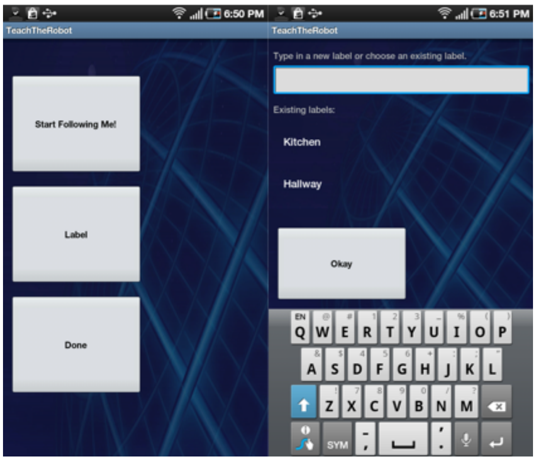

Fig. 4. Screenshots of our tablet user interface. Left: A screenshot of the interface that allows the user to command the robot to follow, or stop following them, or enter a label. Right: A screenshot of the interface for labeling landmarks. Previous labels are available for the user's convenience when labeling multiple surfaces with the same label (e.g. the four walls of a room). New labels can be entered via the onscreen keyboard. Upon pressing the "Okay" button, the user points at the landmark that should be annotated with the desired label.

E. Navigating to labeled structures

After labeling various landmarks in the map, we want the robot to be able to navigate back to these labeled landmarks. While investigating specific service robot tasks is beyond the scope of this paper, most of these tasks will involve navigating to the labeled landmark. We have implemented a function to calculate a goal location corresponding to a label.

We consider two cases when calculating a goal point for a given label. The requested label may correspond to one landmark, or multiple landmarks. In the case that it is one landmark, it corresponds to a plane somewhere in the environment, but if many landmarks share the label, it corresponds to a volume.

Let us first consider the case where there is only one plane with a given label. In this case, we assume that the robot should navigate to the closest edge of the plane, so we select the closest vertex on the landmark's convex hull to the robot's current position. This point is projected down to the ground plane, as our robot navigates on the floor. We calculate a line between this point and the robot's current pose, and navigate to a point on this line 1 meter away from the point, and facing this point. This results in the robot navigating to near the desired landmark, and facing it. This method is suitable for both horizontal planes such as tables, or vertical planes such as doors.

In the case that we have multiple planar landmarks annotated with the same label, this label corresponds to a region of space. In this case, we calculate the centroid of the hull points corresponding to all planes with this label, and project

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it down to the ground plane. The goal orientation is chosen to be perpendicular to one of the labeled planes' normals. This is suitable for hallways, as we would be oriented in the direction of travel, or rooms.

IV. RESULTS

The system has been evaluated on a robot platform in our lab and office environment. The environment was mapped ahead of time by teleoperating the robot through the environment. The interactive labeling system was then tested on the robot using this map.

A. Robot Platform

The robot platform used in this work is the *Jeeves* robot from the Georgia Institute of Technology's Cognitive Robotics Lab, shown in Figure 6 and 8. Jeeves is comprised of a Segway RMP-200 mobile base, and is equipped with a variety of sensors. A SICK LMS-291 laser scanner is used for navigation and obstacle avoidance. A Microsoft Kinect RGB-D sensor is mounted on a Directed Perception DP-47-70 pan-tilt unit, allowing us to capture point cloud data, which we require for mapping. The platform is also equipped with a parallel jaw gripper mounted on a 1-DOF linear actuator, which allows basic manipulation tasks when combined with the Segway's additional degrees of freedom.

B. Labeling System

We used our system in an office environment for two types of scenarios. First, labeling single important landmarks, such as the coffee table and desk , seen in Figure 1. Once a metric map was collected, the user used the tablet-based UI to command the robot to follow them through the environment to important landmarks. The tablet UI was used to type the relevant labels for the landmarks, and gestures were used to indicate which landmark should be annotated with this label.

We also tested labeling of regions by labeling multiple surfaces with the same label. For example, a hallway can be seen in Figure 7.

The tablet and gesture interface allows users to easily label landmarks throughout the environment.

C. Navigating to labeled landmarks and regions

Navigation to labeled landmarks has also been tested by using the tablet-based user interface. An example goal location corresponding to the labeled table is shown in Figure 5. As was described in Section III-E, the goal location is calculated by first selecting the nearest point on the landmark's convex hull to the robot, as is shown as the white sphere in Figure 5. A pose 1m from this point in the direction of the robot, and facing the labeled landmark has been selected as the goal location. The robot then navigates to this point, as can be seen in Figure 6.

Navigation to a labeled region has also been tested. An example of this is shown in Figure 7, which includes a goal point that has been calculated for the label "hallway". A photo of the robot after navigating to this point is shown in Figure 8.

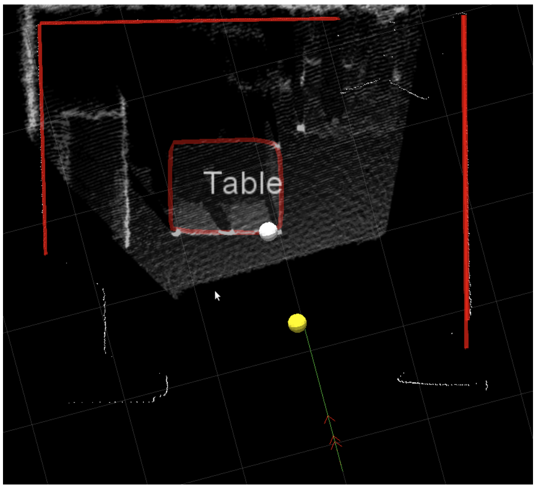

Fig. 5. A goal point corresponding to a labeled table is shown in yellow.

Fig. 6. A photo of the robot after navigating to the goal point corresponding to the table.

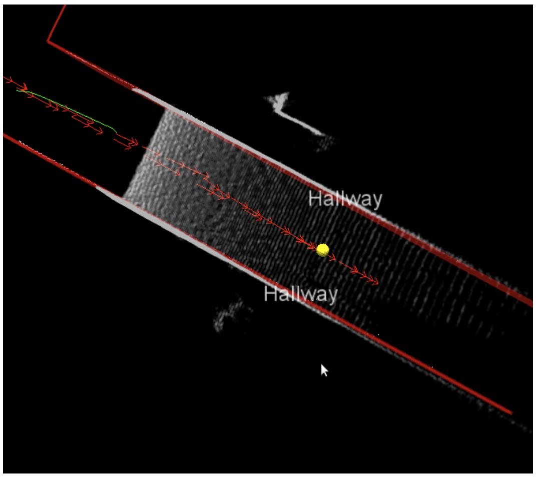

Fig. 7. A goal point corresponding to a labeled hallway is shown in yellow.

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Fig. 8. A photo of the robot after navigating to the goal point corresponding to the hallway.

V. Discussion and Conclusion

We have proposed an approach for labeling feature based maps, and demonstrated a system implementing this approach. We described a map representation that supports labeled landmarks, such as tables, counters or shelves, as well as regions, such as rooms or hallways. We also described a user interface that allows users to annotate such maps, by entering labels on a tablet based UI, and gesturing at the landmark that should be annotated with the entered label. Landmarks throughout the environment can be labeled in a "home tour" scenario by making use of our person following system. This approach was validated by implementing and using it on our robot in our lab and office environment. Annotated maps were produced, and used to command the robot to go back to labeled landmarks and regions.

As future work, we would like to investigate the usage of the labeled maps produced by our system for service robotic tasks such as fetch and carry, object search, or other mobile manipulation tasks. Other applications might include informing active visual search such as [2], or facilitating directions following tasks such as [10]. Additionally, we would like to evaluate the ease-of-use of our system with non-expert users.

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