

Task-Level Motion Planning for Multi-Manipulator System

*A Project Report Submitted
in Partial Fulfillment of the Requirements
for the Degree of*

Bachelor of Technology

by

Rajendra Singh
(111601017)

under the guidance of

Dr. Chandra Shekar



INDIAN INSTITUTE
OF TECHNOLOGY
PALAKKAD

DEPARTMENT OF COMPUTER SCIENCE AND ENGINEERING

CERTIFICATE

*This is to certify that the work contained in this thesis entitled “**Task-Level Motion Planning for Multi-Manipulator System**” is a bonafide work of **Rajendra Singh (Roll No. 111601017)**, carried out in the Department of Computer Science and Engineering, Indian Institute of Technology Palakkad under my supervision and that it has not been submitted elsewhere for a degree.*

Dr. Chandra Shekar

Assistant Professor

Department of Computer Science & Engineering

Indian Institute of Technology Palakkad

Acknowledgements

I would like to express my sincere gratitude to my mentor **Dr. Chandra Shekar** and **Mr. Girish Kumar PR**. I would also like to thank my project coordinator **Albert sunny** who gave me the golden opportunity to do this wonderful project at **Gadgeon Smart Systems Pvt Limited, Kochi**. Also, I would also like to thank my office colleague specially Abhinand and Indu for their critical doubts and questions, endless help and support throughout this project.

Contents

List of Figures	iv
1 Introduction	1
1.1 Problem Statement	1
1.2 Goal of Project	2
1.3 Organization of The Report	3
2 Prior Work	4
2.1 Introduction	4
2.2 Solving Inverse Kinematics(IK) using PSO	4
2.3 Moveit and Move_group Concept	6
2.4 Computer Vision for object detection	7
2.5 Uarm Shift Pro	8
2.6 Conclusion	10
3 MoveIt Task Constructor	11
3.1 Motivation	11
3.2 Introduction	11
3.3 Conclusion	13
4 Task-Level Motion Planning	14
4.1 MTC Task Description	14

4.2	MTC Primitive Stage Types	15
4.3	Basic Primitive Stages	17
4.4	Motion Planning Containers	18
4.4.1	Serial containers	18
4.4.2	Parallel containers	19
4.5	Task Scheduling	20
4.6	Task Execution	21
4.7	Motion Planning Introspection	23
4.8	Conclusion	23
5	Implementations	24
5.1	Buliding a structure using multi arm	25
5.2	Pouring Task	31
6	Conclusion and Future Work	38
	Bibliography	39

List of Figures

2.1	IK : Finding inverse kinematics solution for 6 dof robotics manipulator . . .	5
2.2	Moveit Manipulation Flowchart[1]	6
2.3	Move_group Concept[1]	7
2.4	Cylinder detection using PCL	8
2.5	UARM Setup Assistance	9
2.6	UARM JointState	9
4.1	Generator, Propagators and Connectors[2]	15
4.2	Various stages interfaces[2]	18
5.1	PickPlace Scene	25
5.2	PickPlace Stage for Panda arm 1	26
5.3	PickPlace Stage for Panda arm 2	27
5.4	Build Structure 1	28
5.5	Build Structure 2	29
5.6	Time taken by various solutions	30
5.7	Pouring Scene	31
5.8	Pouring Stage for Panda arm 1	32
5.9	Pouring Stage for Panda arm 2	33
5.10	Various stages involved in pouring task	37

Chapter 1

Introduction

This project is related to repair any space satellite using multiple robotic manipulator situated on another repair satellite. Currently, it is in feasibility phase and we are doing various simulation, experiment and tests to understand what is possible and what's not. My main work in this project is to coordinate 2 different arms and perform complex manipulation task like repairing various part of satellite. It involves solving kinematics and inverse kinematics for multi-manipulator system. One of the solutions for this is using a particle swarm optimization algorithm which I had used in the BTP phase one. Here, I'm using motion planning framework like Moveit, Move_task_constructor with ROS.

1.1 Problem Statement

Perform complex manipulation task like pick and place, building structures and pouring in multi-manipulator system. **More detailed subtask/problem are as:**

1. Simple Joint space planning(move_group)
2. Simple Cartesian space planning(move_group)
3. Pick Place Task (move_group)
4. Simple Joint space planning(MTC)

5. Simple Cartesian space planning(MTC)
6. Pick Place Task(MTC)
7. Multi arm simple Joint space planning
8. Multi arm simple Cartesian space planning
9. Multi arm Simple Pick Place Task(own work)
10. Multi arm Complex Pick Place Task(IIT)
11. Multi arm planning using Serial container
12. Multi arm planning using Parallel container
 - 12.1 Alternative
 - 12.2 Fallback
 - 12.3 Merger
13. Multiple task
14. Single arm pouring task
15. Complex Multi arm pouring
16. Complex Multi arm pouring task with stages intermixing
17. Complex task with orientation constraint imposed

1.2 Goal of Project

Goal for mid term submission was to do motion planning for task like pick-place and pouring. Going further, I'll using and improving recently released open source motion planning frame MTC. I will be analysis time and space complexity of this motion planning algorithms with simulated robots using ros, thus optimizing the same. I would be working in more complex and constraint environment for motion planning with four kinova jaco arms.

1.3 Organization of The Report

chapter 1 : We introduced the problem statement, discussed goal for this semester and organisation of this report.

chapter 2 : Here, I would take you through my prior experience with Robotics Manipulator i.e Uarm Shift Pro Robotics Arm for motion planning using move_group.

chapter 3 : Here, we'll introduce MTC and motivation behind using it.

chapter 4 : Here, We'll have in depth look at MTC planning, container, stages etc.

chapter 5 : Here, We'll implement motion planning to perform some task with the help of MTC. All of the codes used in these implementation can be found here on my GitHub repository[\[3\]](#).

chapter 6 : Here, We'll conclude my work and discuss future work.

Chapter 2

Prior Work

2.1 Introduction

During my summer internship(2019) and BTP phase one, I used robotic manipulator and motion planning frame work like Moveit to perform some simple tasks. Thus, this work becomes the basis of more complex manipulation task performed in this project.

2.2 Solving Inverse Kinematics(IK) using PSO

During my BTP phase, I had used particle swarm optimization(PSO) algorithm to solve the Inverse Kinematics problem in robotic manipulator. In general we use DH method to solve IK.[4] Inverse Kinematics is the inverse algorithm of Forward Kinematics. The Forward Kinematics algorithm takes a target position as the input, and calculates the pose required for the end effector to reach the target position. Whereas Inverse kinematics find the joint value required for arm to reaches the given coordinate. I have used PSO to solve the IK, and detailed code for the same can be found. [here](#).

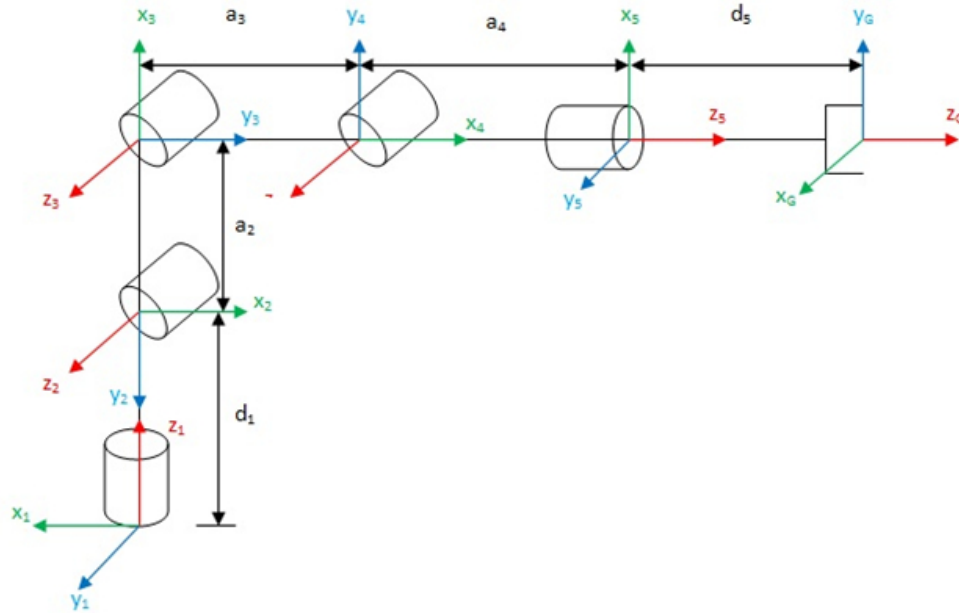


Figure 2.1 IK : Finding inverse kinematics solution for 6 dof robotics manipulator

Pseudo Code

```
# find forward kinematics pose of end effector
def get_end_tip_position(params):
    # Create the transformation matrices for the respective joints
    # Get the overall transformation matrix and return
# function to be optimized
def opt_func(X):
    n_particles = X.shape[0] # number of particles to be used
    #define the function to be optimised here
# Call an instance of PSO
optimizer = ps.single.GlobalBestPSO(...)
# Perform optimization
cost, joint_vars = optimizer.optimize(opt_func, iters=1000)
```

2.3 Moveit and Move_group Concept

Here we can see flowchart for any manipulation task utilising the various moveit capabilities.

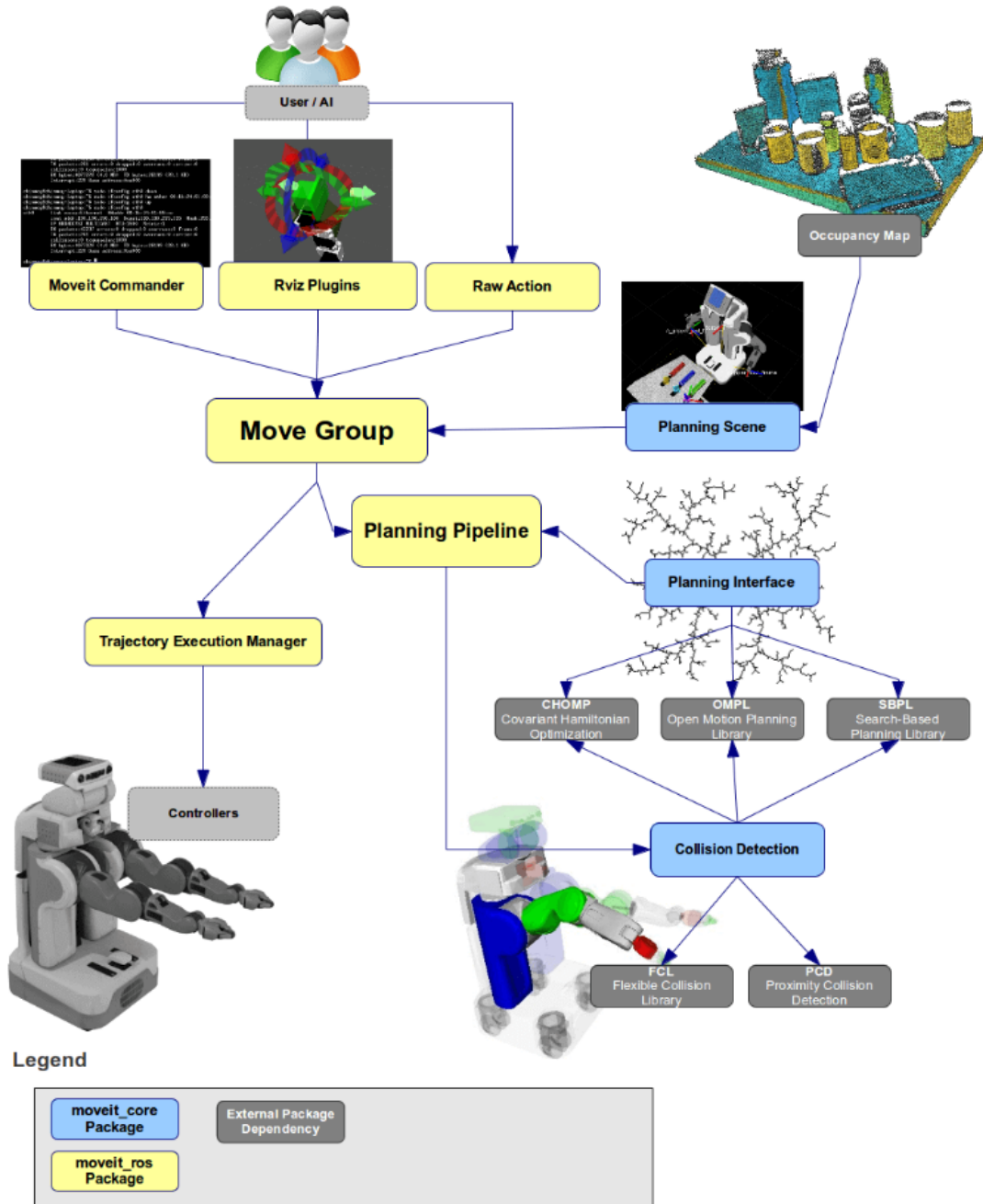


Figure 2.2 Moveit Manipulation Flowchart[1]

Below picture show the various topic that move_group publish and subscribes and its

interaction with various other node.

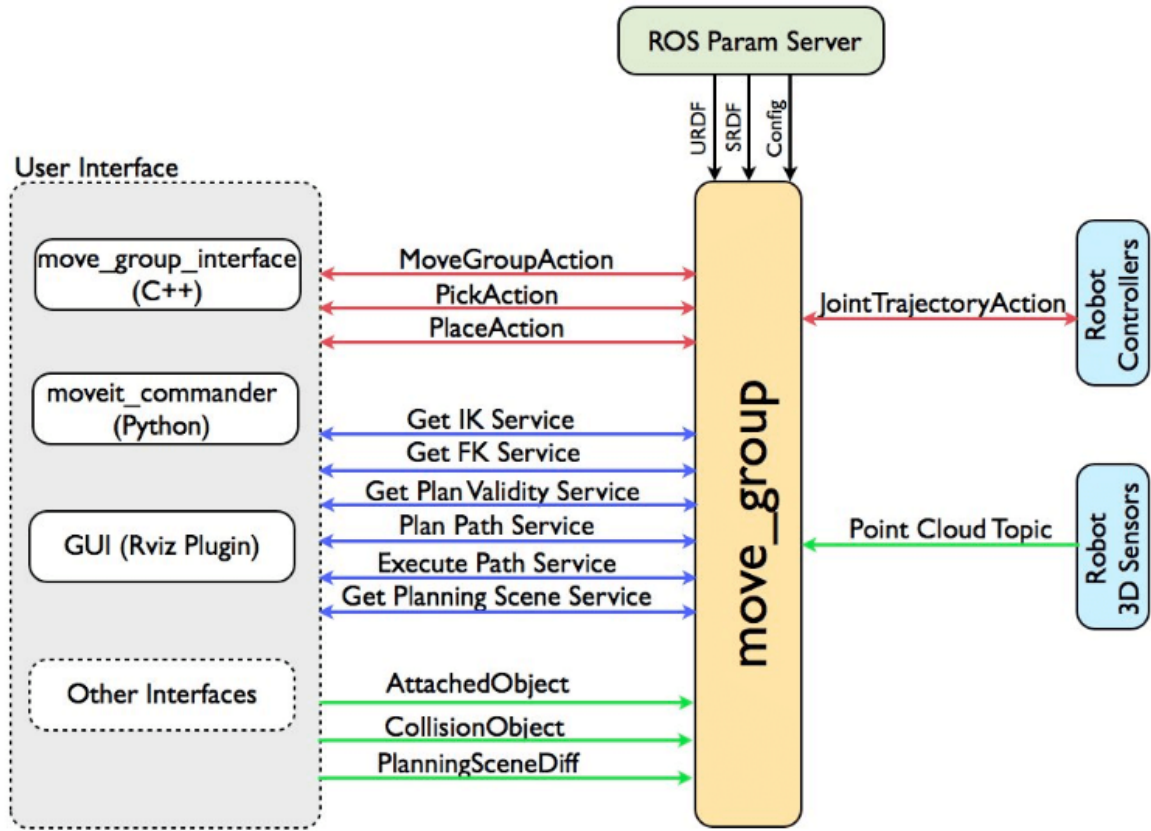


Figure 2.3 Move_group Concept^[1]

2.4 Computer Vision for object detection

I had used PCL(Point Cloud Library) to detect and extract Cylinder out of the point cloud in the following steps:

1. Converting pointcloud to pcl:PointXYZRGB
2. PassThroughFilter
3. Compute the point normals
4. Detect and eliminate the plane
5. Extracting plane normals

6. Extract the cylinder
7. Compute cylinder_params

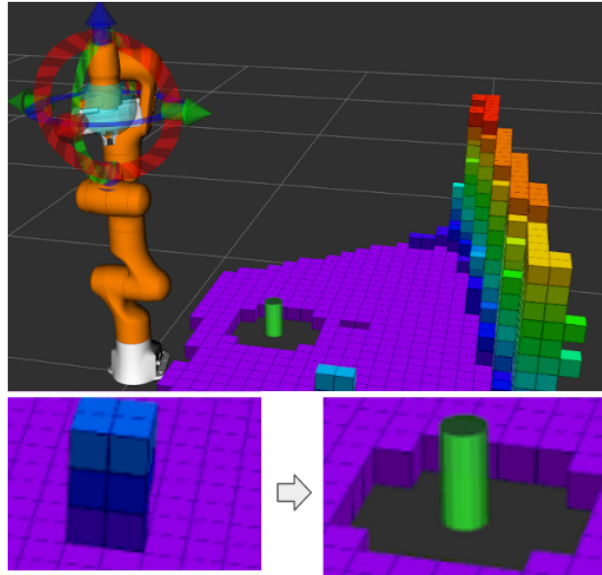


Figure 2.4 Cylinder detection using PCL

2.5 Uarm Shift Pro

I had used UARM with moveit, and since it was 4 dof there were lots of singularity in planning. Also error report was not good enough, which motivated me use MTC in this project.

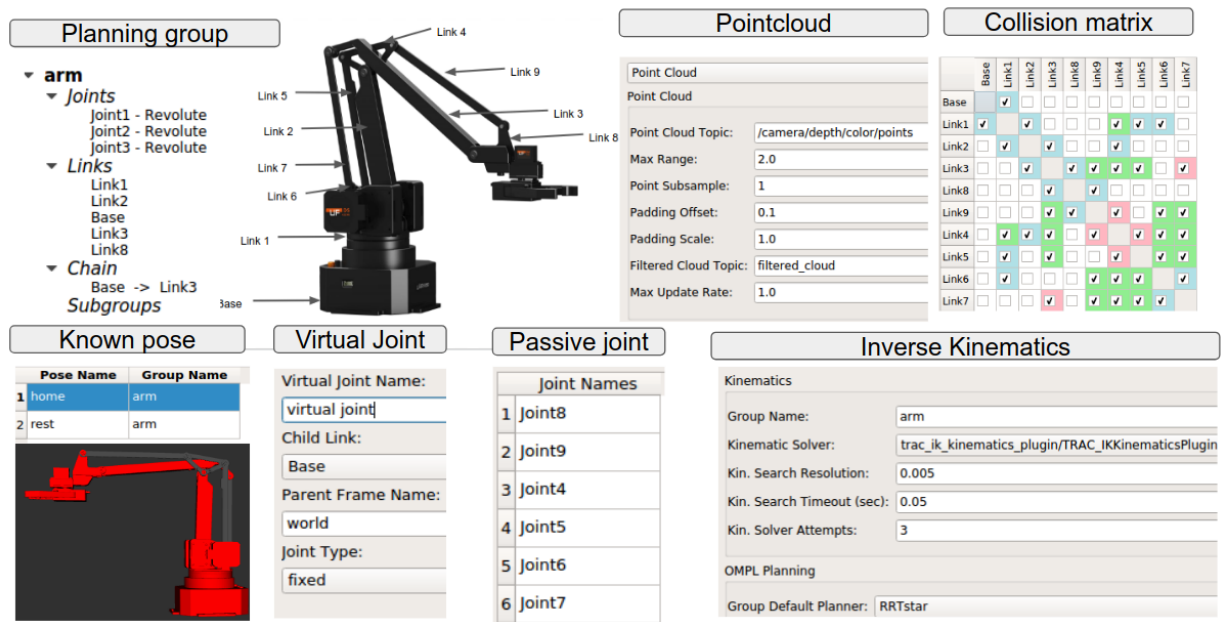


Figure 2.5 UARM Setup Assistance

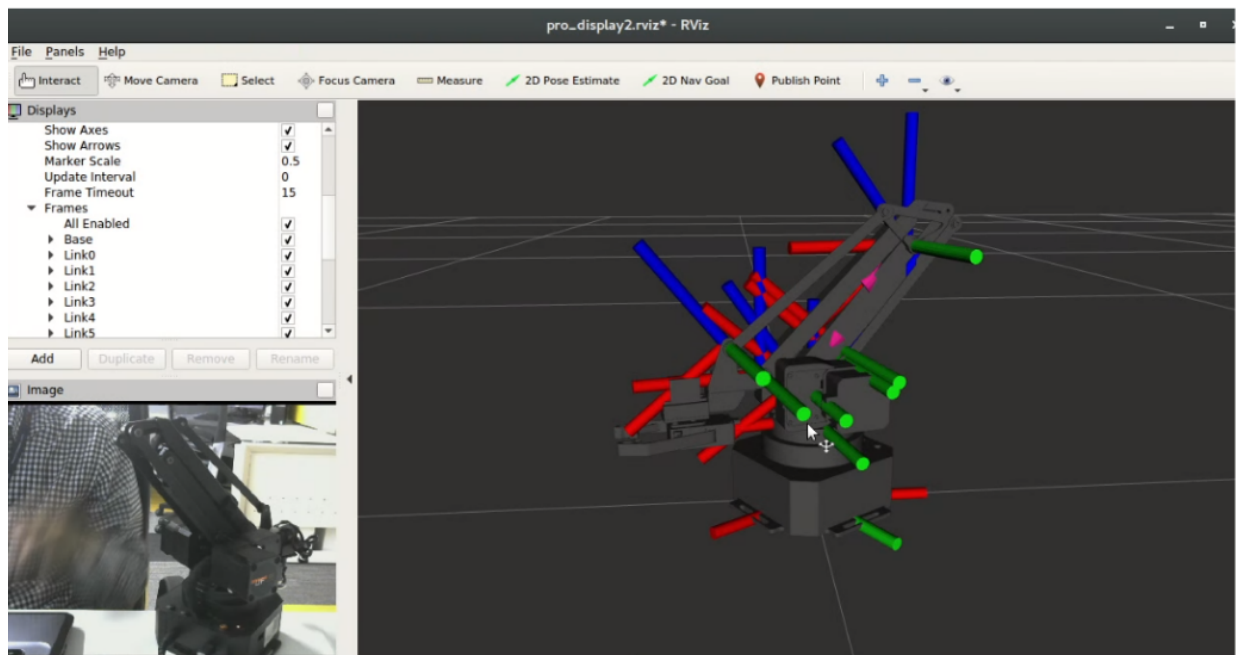


Figure 2.6 UARM JointState

2.6 Conclusion

We have seen that, for various use cases there are lots of limitation in using the Moveit move_group pipeline for motion planning, thus it motivated me use the MTC framework in the project. Also, We can see that moveit make it impossible to use lower level task planning and also produce bad error reporting. Introsection of stage in task planning is not possible, it became really hard to reason for the failure we get during the planning.

Chapter 3

MoveIt Task Constructor

3.1 Motivation

A lot of motion planning research in robotics focuses on efficient means to find trajectories between individual start and goal regions, but it remains challenging to specify and plan robotic manipulation actions which consist of multiple interdependent subtasks. MoveIt Task Constructor framework provides a flexible and transparent way to define and plan such actions, enhancing the capabilities of the popular robotic manipulation framework MoveIt!. Subproblems are solved in isolation in black-box planning stages and a common interface is used to pass solution hypotheses between stages. The framework enables the hierarchical organization of basic stages using containers, allowing for sequential as well as parallel compositions. The flexibility of the framework is illustrated in multiple scenarios performed on various robot platforms, including multi-arms.

3.2 Introduction

Motion planning for robot control traditionally considers the problem of finding a feasible trajectory between a start and a goal pose, where both are specified in either joint or Cartesian space. Standard robotic applications, however, are usually composed of multiple,

interdependent sub-stages with varying characteristics and sub-goals. In order to find trajectories that satisfy all constraints, all steps need to be planned in advance to yield feasible, collision-free, and possibly cost-optimized paths.

A typical example are pick-and-place tasks, that require (i) finding a set of feasible grasp and place poses, and (ii) planning a feasible path connecting the initial robot pose to a compatible candidate pose. This in turn involves approaching, lifting, and retracting – performing well-defined Cartesian motions during these critical phases. As there typically exist several grasp and place poses, any combination of them might be valid and should be considered for planning.

Such problems present various challenges: Individual planning stages are often strongly interrelated and cannot be considered independently from each other. For example, turning an object upside-down in a pick-and-place task renders a top grasp infeasible. Whereas some initial joint configuration might be adequate for the first part of a task, it could interfere with a second part due to inconvenient joint limits.

The present work describes the use of MTC framework to describe and plan composite tasks, where the high-level sequence of actions is fixed and known in advance, but the concrete realization needs to be adapted to the environmental context. With this, we aim to fill a gap between high-level symbolic task planning and low-level, manipulation planning, thus contributing to the field of Task and Motion Planning.

Within the framework, tasks are described as hierarchical tree structures providing both sequential and parallel combinations of subtasks. The leaves of a task tree represent primitive stages, which are solved by arbitrary motion planners integrated within MoveIt!, thus providing the full power and flexibility of MoveIt! to model the characteristics of specific subproblems. To account for interdependencies, stages propagate the world state of their sub-solutions within the task tree. Efficient schedulers are proposed to first focus search on critical parts and cheap-to-compute stages of the task and thus retrieve cost-economical solutions as early as possible. Continuing planning can improve the quality of

discovered solutions over time, taking into consideration all generated sub-solutions.

Additionally, the explicit factorization into well-defined stages and world states facilitates error analysis: individual parts of the task can be investigated in isolation and key aspects of individual stages can be visualized easily.

3.3 Conclusion

Here, we have seen how MTC enhance the moveit capability and improve the error reporting, introspection of task etc.

Chapter 4

Task-Level Motion Planning

Here I'll be discussing about how we can think each manipulation task in terms of in sub stages. This stages can be combined using various available containers.

4.1 MTC Task Description

Within this framework, tasks are composed in a hierarchical fashion from primitive planning stages that describe atomic motion planning problems that can be solved by existing motion planning frameworks like OpenRAVE [5], Klamp't [6] or MoveIt! [7]. These frameworks typically allow for motion planning from a single start to a goal configuration, which both are usually fully-specified in configuration space. Often they also permit to specify goal regions, both in configuration and Cartesian space, and appropriate state samplers are employed to yield discrete configurationspace states for planning.

Individual planning stages communicate their results via a common interface using a MoveIt! planning scene to describe the whole state of the environment relevant for motion planning. This comprises the shape and pose of all objects, the collision environment, all robot joint states, and information about objects attached to the robot. This geometric/kinematic state description can be augmented by additional semantic information in terms of typed, named properties, forming the final state representation. Each stage

then attempts to connect states from its start and end interfaces via one or more planned trajectories.

Container stages allow for hierarchical grouping of stages. Depending on the type of the container, solutions found by its children are converted to compound solutions and propagated up the task hierarchy.

4.2 MTC Primitive Stage Types

We distinguish primitive stages based on their interface type.

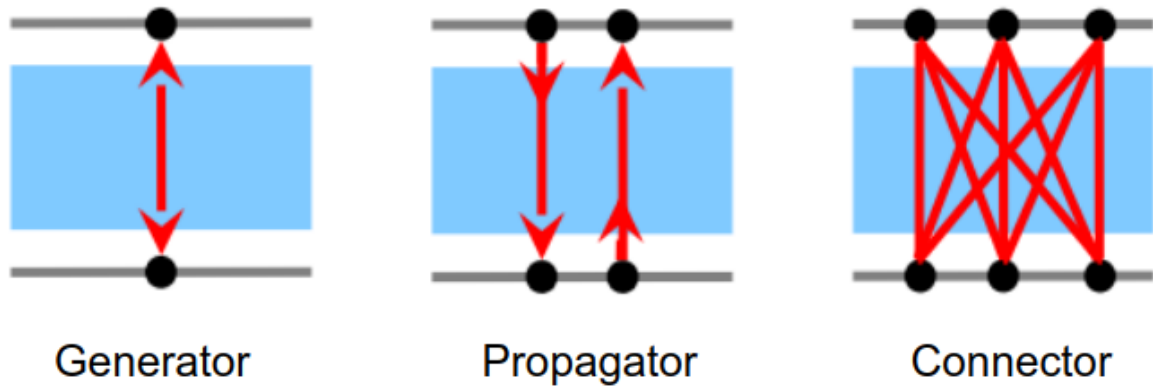


Figure 4.1 Generator, Propagators and Connectors[2]

The classical planning stage is the connecting stage, which takes a pair of start/end states and tries to connect them with a feasible solution trajectory. This type of planning stage often corresponds to transit motions that move the robot between different regions of interest. In this case, any combination of states from the start and end interfaces is considered for planning, realizing an exhaustive search. As such a planning stage will only affect a small set of active joints usually, a pair of start and end states need to match w.r.t. all other aspects of the state representation. Particularly, all other joints as well as the number, pose, and attachment status of collision objects need to match.

The second type, generator stages, populate their start and end interfaces from scratch, without any explicit input from adjacent stages. Usually they define key aspects of an action, for example defining the initial robot state or a fixed goal state, which subsequently can serve as input for adjacent stages. Another example are grasp generators, which provide pairs of pre- and final grasp poses, computing their corresponding robot poses based on inverse kinematics. In this case, generated start and end states usually differ and are connected by a non-trivial joint trajectory (provided by the grasp planner) to accomplish actual grasping.

The most common type of stages are propagators, which read an input state from either its start or end interface, plan to fulfill any predefined goal or action, and finally generate one (or more) new state(s) at the opposite interface together with a solution connecting both states.

Note that propagation can act in both directions, from start to end as well as from end to start. For this reason, it is important to distinguish the temporal from the logical flow. The temporal flow is always from a start to an end interface and defines the temporal evolution of a solution trajectory. However, the logical (program) flow defines the state information flow during planning and is determined by the propagation direction of individual stages. Backwards propagation allows for planning a relative motion to reach a given end state from a yet unknown start state. A common example is the Cartesian approach phase before grasping: Here the final grasp pose is given, and a linear approach motion to the pre-grasp pose needs to be found, whose extent is only coarsely specified within a range of several centimeters. Corresponding solutions are planned in reverse direction, from the end towards the start state. Finally, the solution is reversed to yield a trajectory properly evolving in time from start to end.

4.3 Basic Primitive Stages

The Task Constructor library provides a connecting stage and two basic propagating stages, which all are driven by individual planner instances. While stages specify a subtask, i.e. which robot states to connect, planners perform the actual work to find a feasible trajectory between these two states. Hence, planners can be reused in different stages. Two basic planning instances are provided: (i) MoveIt’s planning pipeline offering wrappers for OMPL [8], CHOMP [9], and STOMP [10]; and (ii) a Cartesian path generator based on straight-line Cartesian interpolation and validation.

The two propagating stages allow for (i) absolute and (ii) relative goal pose specification, either in joint or Cartesian space. While in the former case, the goal pose is specified in an absolute fashion w.r.t. a known reference frame, the latter case permits specifying relative motions of a specific endeffector link. In the general case, a twist motion (translation direction and rotation axis) is specified w.r.t. an arbitrary known reference frame and finally applied to the given endeffector link. This makes it possible for example to specify a linear approach or lifting motion relative to the object or a global reference frame.

Generator stages provided are: (i) the current state stage fetching the current planning scene state from MoveIt!’s `move_group` node, and (ii) the fixed state stage allowing to specify an arbitrary, predefined goal state.[11]

In some cases, the sequential information within the task pipeline is too restrictive to specify a task: Particularly, generator stages might depend on the outcome of another, nonneighboring stage, thus necessitating a short-cut connection within the task pipeline. For example, to place an object after usage at the original pick location, the corresponding place-pose generator needs access to the original pick pose.

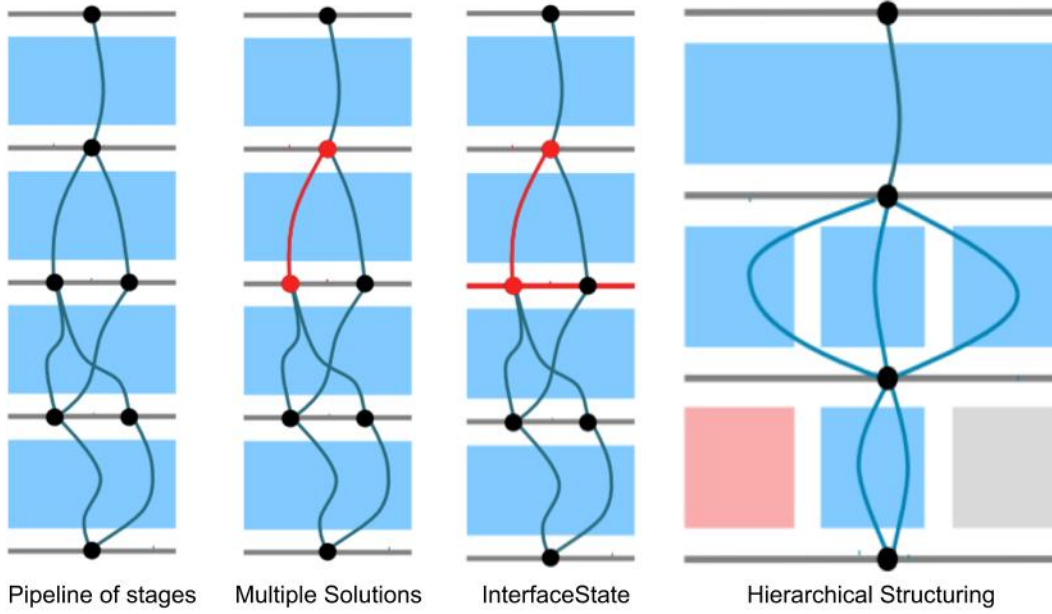


Figure 4.2 Various stages interfaces[2]

4.4 Motion Planning Containers

As mentioned before, container stages are used to hierarchically compose stages into a tree. Each container encapsulates and groups a set of children stages performing some semantically coherent subtask, e.g. grasping or placing. Children stages can easily inherit properties from their parent, thus reducing the configuration overhead. Two main types are distinguished: serial and parallel containers.

4.4.1 Serial containers

Serial containers organize their children into a linear sequence of subtasks which need to be performed in the specified order to accomplish the overall task of the container. Accordingly, a solution of a serial container connects a state from the start interface of the first child stage to the end interface of the last child via a fully-connected, multistage

trajectory path.

In a sequential pipeline, generators play a particularly important role: They generate seed states, which subsequently are extended (in both directions) via propagating stages to form longer partial solution paths. Finally, connecting stages are responsible to link individual partial solution paths to yield a fully-connected solution ranging from the very beginning to the very end of the pipeline.

Obviously, the interface types of stages constrain how they can be sequenced: A stage writing new states along one direction (forward / backward) should be followed / preceded by a stage that reads from the common interface and vice versa. Otherwise, the logical information flow would be broken. Containers provide automatic validation of the connectivity of their children prior to any planning and thus can reject wrongly configured task trees already at configuration time.

Note that in general there can be multiple paths connecting a single pair of start-end states and there can be multiple solutions corresponding to different pairs of start-end states. Hence, it becomes important to rank all found solutions according to a task-specific cost function.

4.4.2 Parallel containers

Parallel containers allow for planning of several alternative solutions, e.g. grasping with left or right arm. Each solution found by its children directly contributes to the common pool of solutions of the container. Different types of parallel containers are distinguished, depending on the planning strategy for children:

- (i) *Alternatives*: Consider all children in parallel. All generated solutions become solutions of the container.
- (ii) *Fallbacks*: Consider children sequentially, only proceeding to the next child if the previous one has vainly searched its solution space. Only solutions found by the first successful child constitute the solutions of the container.

(iii) *Independent Components*: consider all children in parallel. In contrast to (i), children generate solutions for disjoint sets of robot joints (e.g. arm and hand), which are subsequently merged into a single coherent trajectory performing all sub-solutions in parallel. Obviously, such a merge might fail and explicit constraint checks (including collision checking) are required for final validation. This divide-and-conquer approach is particularly useful, if the planning spaces of individual children are truly independent, as for example in approaching an object for bimanual grasping. In this case, the motion of both arms can be planned independently in lower-dimensional configuration spaces. To enforce independence, one may introduce additional constraints, e.g. a plane separating the Cartesian work spaces of both arms. This task-specific knowledge needs to be provided with the task specification.

4.5 Task Scheduling

The proposed framework exhaustively enumerates all possible solution paths connecting individual interface states, which obviously suffers from combinatorial explosion. Thus, scheduling heuristics are applied to focus the search on promising solution paths first.

To this end, solutions have an associated cost that is computed in a task-specific fashion by user-defined cost functions. Potential functions include, among others, length of trajectory, amount of Cartesian or joint motion, minimum or average clearance. Serial container stages accumulate the costs of all sub-solutions of a full path and only report the minimal-cost path for any pair of start-end states. In a similar fashion, parallel containers only report minimalcost solutions of their children. Each stage, and particularly the root stage of the task tree, can then rank their solutions according to this cost and stop planning when an acceptable overall solution is found.

Each stage ranks all its incoming interface states according to (i) the length and (ii) cost of the associated partial solution. The former criterion biases the search to depth-first (in contrast to breadth-first), which ensures finding full solutions as soon as possible. If a

partial solution fails to extend at either end, this failure is propagated to the other end, and the corresponding interface states are removed from the interfaces of the associated stages as there is no benefit in continuing work on that particular solution.

Additionally, containers handle the scheduling of their children stages. Again the serial container plays the most important role for this. Generators need to be scheduled first in order to generate seed states, which subsequently are extended via propagating stages, and finally connected to full solution paths. Obviously, execution of connecting stages should be postponed as long as possible, because their pairwise combination of start-end states leads to a combinatorial explosion of the search space.

On top of these heuristics, there is room for further optimization. For example, one could try to balance the expected computation time vs. the expected connection success (or reduction in overall trajectory cost) by ranking stages according to the ratio of these values. To yield estimates for them, one could consider heuristic measures (e.g. joint or Cartesian-space distance of states), or maintain statistics over previous stage executions. To yield higher diversity and randomization, actual ranking can be performed based on the Boltzmann distribution of the computed performance rank.

4.6 Task Execution

The main contribution of this work lies in modeling and planning manipulation tasks. Nonetheless, eventually a solution should be executed on the actual robot. Traditionally, planning research simply forwards the final solution trajectory to a low-level controller. To this end, the proposed framework provides utilities to access planned task solutions, such that the user can decide whether to execute, for example, (i) the first valid solution, (ii) the first solution below some cost threshold, or (iii) the best trajectory found within a given amount of time or after exhaustively searching the full solution space. Modifications to the world state performed as part of the task, e.g. attaching or releasing an object, are performed in the same fashion as trajectories are executed, thus ensuring a consistent world

representation throughout task execution.

Given the modularity of the task pipeline, several improvements are possible. Assuming feasible trajectories for the whole task will be found eventually, initial stages (or groups of stages) could commit early to a particular partial solution and forward it for execution before a full solution trajectory is found. As a consequence, this strategy can noticeably reduce the perceived planning time as the robot will start to move early. This is particularly useful when initial stages only yield a single canonical solution, but can also be used to significantly prune the search space, assuming full solutions will be available for most early sub-solutions.

To handle failures during task execution (e.g. due to dynamical changes in the environment, or because an early executed partial solution eventually turns out to be incompatible with later planning stages), a recovery strategy is essential. Again, the modular structure of the task pipeline can be exploited for intelligent recovery, dependent on the failed sub-stage. Potential strategies might replan from the reached stage, or partially revert sub-solutions to continue planning from a well-defined state.

It is also possible to specify different execution controllers (or parameterizations) for individual stages (or groups of stages) to account for different control needs. For example an approach stage might employ visual servoing to account for perception inaccuracies and a grasp stage should use a compliant motion strategy until contact is established and subsequently switch to force-controlled grasp stabilization. As long as the motion of these reactive, sensor-driven controllers remains within specified bounds to the planned trajectory, subsequent stages can connect seamlessly.

Finally, solution segments found by individual planning stages can be post-processed to yield a globally smooth solution trajectory. This requires local modifications at the transition between consecutive segments as they might have discontinuous velocity or acceleration profiles. To this end, acceleration-aware trajectory generation [12] can be applied to splice sub-trajectories smoothly within position bounds. The resulting trajectory segments might

only replace the original solutions, if they satisfy collision checks and other constraints.

4.7 Motion Planning Introspection

A key element for the success and acceptance of a software package is its transparency and ease of use. Although MoveIt comes with its own implementation of a manipulation pipeline, its major drawback is its intransparency: the provided pick and place stages are black boxes that do not allow for inspection of their inner workings.

Hence, important elements of the presented software package are pipeline validation, error reporting, and introspection. Stages can publish both successful and failed solution attempts and augment them with arbitrary visual markers or comments, thus providing useful hints for failure analysis. This information, together with the status of the overall planning progress of the pipeline (number of successful and failed solution attempts per stage) is regularly published.

In rviz, the user can monitor the status of the task pipeline and interactively navigate individual solutions of all stages, inspecting their associated markers and comments.

4.8 Conclusion

In this chapter, we have seen how any complex task can be broken down to simple stages. This way we get more control over the planning. These stages can be run serially or paralleling as per the requirements.

Chapter 5

Implementations

In the following, we describe two typical manipulation tasks and showcase involved planning stages. The first task considers picking and place task to create structure which look similar to word **IIT**. The second task demonstrates a pouring task, which involves picking up a glass, placing it on table, picking up a bottle, approaching a glass, performing the pouring, and placing the bottle back.

5.1 Buliding a structure using multi arm

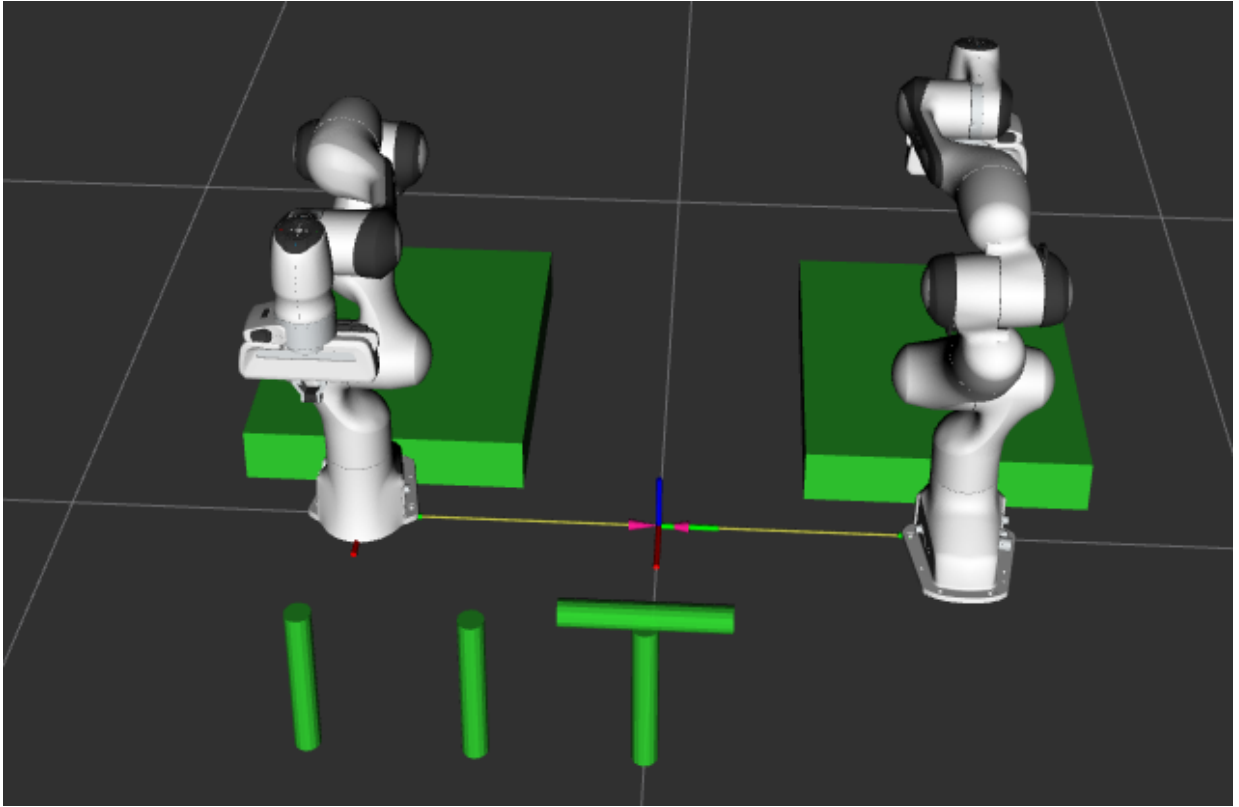


Figure 5.1 PickPlace Scene

Task Tree		
Name	✓	✗
▼ Motion Planning Tasks		
▼ pick_place_task	12	0
▶ ↕ applicability test	1	0
↓ move home	1	0
↓ open hand	1	0
↺ move to pick	66	0
▼ ↕ pick object	66	0
↑ approach object	84	31
▼ ↕ grasp pose IK	121	0
↕ generate grasp pose	25	0
↓ allow collision (hand,object)	116	0
↓ close hand	116	0
↓ attach object	116	0
↓ allow collision (object,support)	116	0
↓ lift object	68	48
↓ forbid collision (object,surface)	68	0
↺ move to place	53	0
▼ ↕ place object	58	0
↑ allow collision (object,support)	58	0
↑ lower object	63	52
▼ ↕ place pose IK	122	55
↕ generate place pose	2320	0
↓ detach object	116	0
↓ open hand	116	0
↓ forbid collision (hand,object)	116	0
↓ retreat after place	69	47
↓ close hand	69	0
↓ move home	58	0

Figure 5.2 PickPlace Stage for Panda arm 1

↓	move home2	58	0
↓	open hand2	58	0
⚡	move to pick2	110	0
▼ ↓	pick object2	98	0
↑	approach object2	110	3
▼ ↓	grasp pose IK2	576	0
↑	generate grasp pose2	1450	0
↓	allow collision (hand2,object2)2	114	0
↓	close hand2	114	0
↓	attach object2	114	0
↓	allow collision (object2,support)2	114	0
↓	lift object2	99	15
↓	forbid collision (object2,surface)2	99	0
⚡	move to place2	1	0
▼ ↓	place object2	2	0
↑	allow collision (object2,support)2	58	0
↑	lower object2	59	4
▼ ↓	place pose IK2	68	80
↑	generate place pose2	2280	0
↓	detach object2	64	0
↓	open hand2	4	60
↓	forbid collision (hand2,object2)2	4	0
↓	retreat after place2	3	1
↓	close hand2	3	0
↓	move home2	2	0

Figure 5.3 PickPlace Stage for Panda arm 2

As picking up an object is a common subtask for many manipulation tasks, a dedicated stage is provided for this. To apply this stage to a specific robot, only some key properties need to be configured, namely the end-effector to use, the name of the object to grasp, and the intended approach and retract directions. The actual grasping is planned by another generic stage, the grasp stage, which is provided as a configurable child stage to the pick

template.

Consequently, the pipeline comprises two alternative pick stages (left and right), configured to use the respective end-effector. The alternatives parallel container follows the current state generator, which fetches the current planning scene state from MoveIt!.

Planning for the pick stages starts with the grasp generator stage and proceeds in both directions: The approach stage realizes a Cartesian, straight-line approach motion, starting from a pre-grasp posture and is planned backwards to find a safe starting pose for grasping. On the opposite side, the lift stage starts from the grasped object state and realizes the Cartesian lifting motion in a forward fashion.

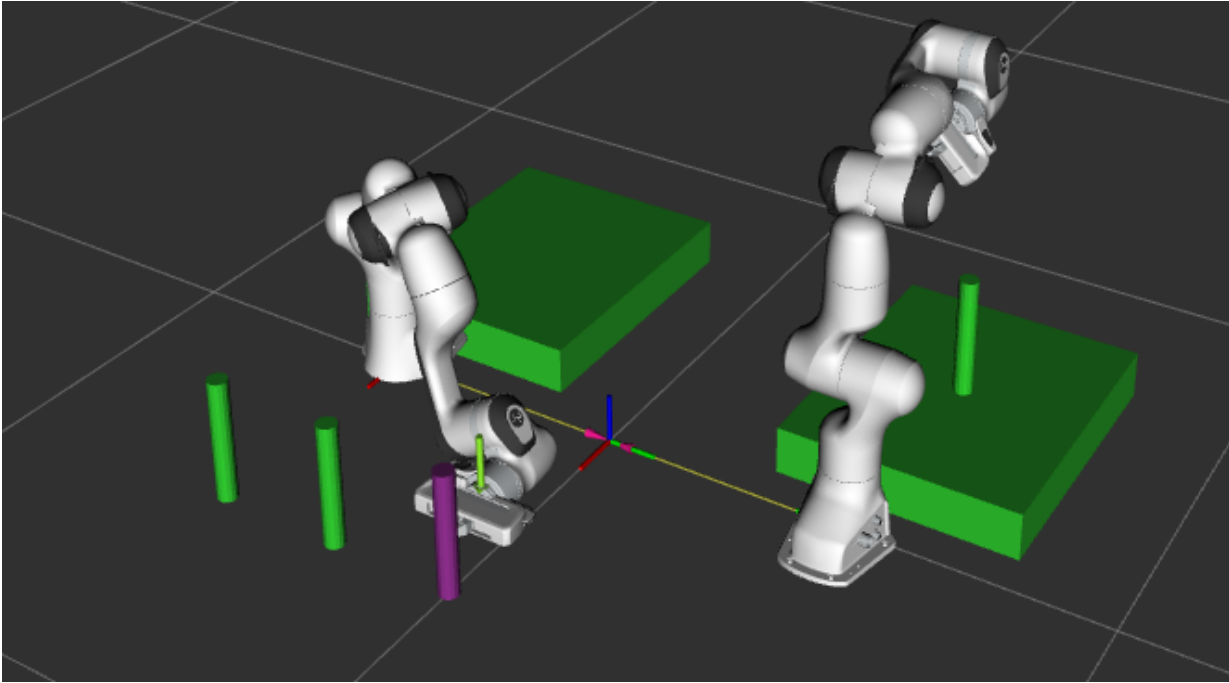


Figure 5.4 Build Structure 1

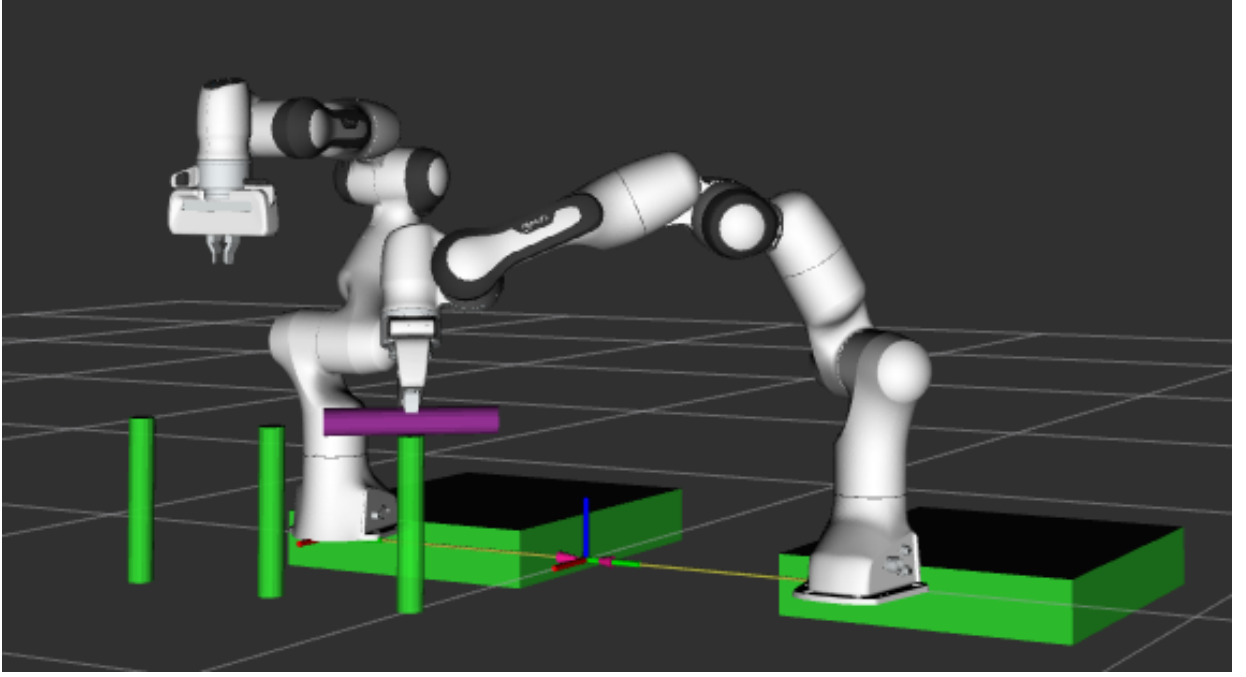


Figure 5.5 Build Structure 2

The grasp stage, in our simple scenarios, samples collision-free pre-grasp poses relative to the object at hand, computes the inverse kinematics to yield a joint-state pose suitable for use in the interface state, and finally performs grasping by closing the gripper. To this end, first collision detection between end-effector and object is turned off to allow the end-effector to contact or penetrate the object when actuating the grasp pose. For real-world execution, the close gripper stage obviously requires a force-controlled or compliant controller to avoid squashing the object. Finally, the object is attached to the end-effector link, such that further planning knows about the grasped-object state. These helper subtasks, which only modify the planning scene state, but do not actually perform any planning, are realized by utility stages, which permit to change allowed collisions as well as to attach and detach collision objects.

Sampling of pre-grasp poses, in our examples, considers a pre-defined open-gripper posture for the end-effector and proposes Cartesian poses of the end-effector relative to

object-specific grasp frames. We sample grasp frames by rotating the object frame about its z-axis in steps of $\pi/12$ radian, resulting in 25 ($12*2+1 = 25$) grasp frame samples. The end-effector is placed relative to these grasp frames by applying the inverse of a fixed tool-to-grasp transform. The resulting transform is used as the target for inverse kinematics. Before applying inverse kinematics sampling, the IK stage validates the feasibility of the targeted pose, i.e. whether placing the end-effector at the target is collisionfree. If not, IK sampling can be skipped and failure is reported immediately. While the first solution on all studied robots is found within a fraction of a second, the planning time for exhaustive search clearly varies between all studied robots and is dominated by the number of sampling-based planning attempts (in stage move to object), which in turn is determined by the number of solutions found by the grasp stage. By repeating this pick and place pipeline for second panda arm, we have created a structure which look similar to word **IIT**. With this we found 12 solution for task execution, and best solution take 78.8 seconds to execute the full task.

1	76.7909
7	77.1628
2	78.6891
8	79.061
3	80.079
4	80.4457
9	80.4509
5	80.5633
6	80.7123
10	80.8176
11	80.9352
12	81.0842

Figure 5.6 Time taken by various solutions

5.2 Pouring Task

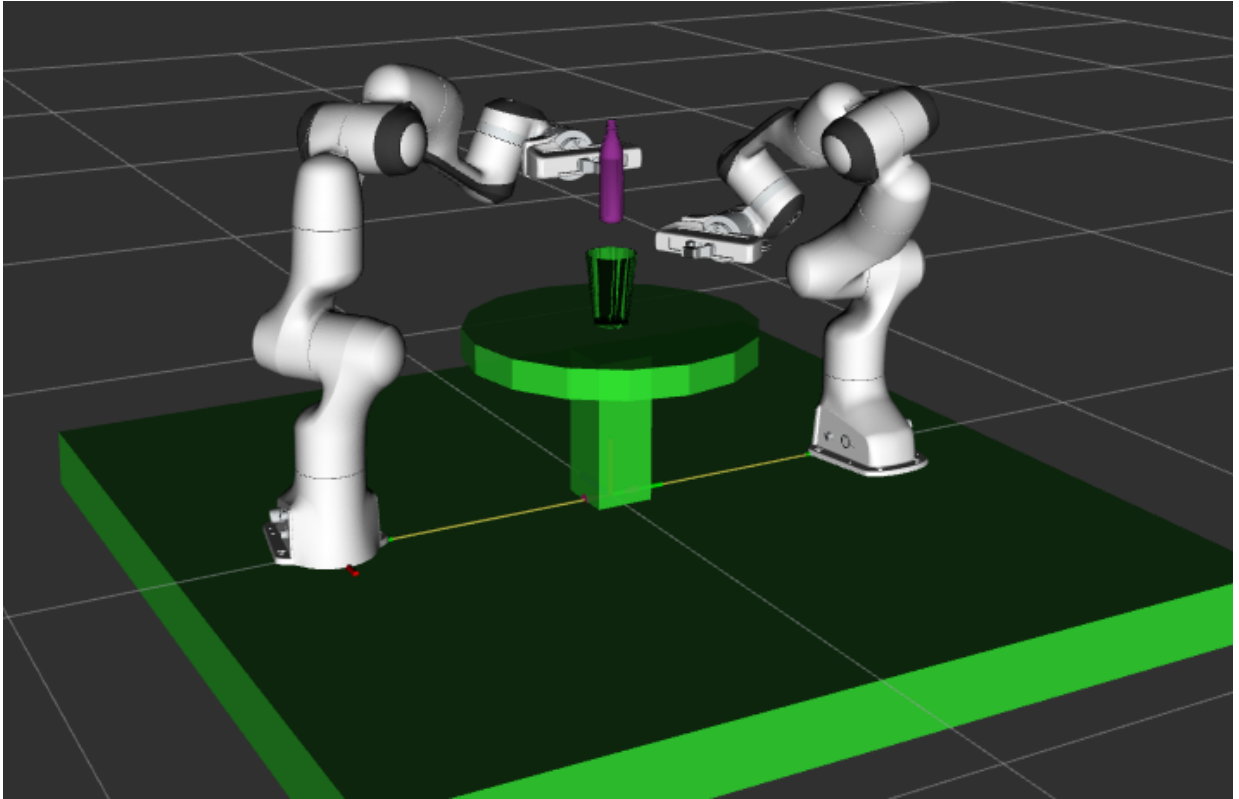


Figure 5.7 Pouring Scene

▼ Motion Planning Tasks		
▼ pick place task	8	0
▼ ↕ applicability test	1	0
↕ current state	1	0
↓ move home	1	0
↓ open hand	1	0
⚡ move to pick	17	0
▼ ↕ pick object	18	0
↑ approach object	21	26
▼ ↕ grasp pose IK	47	11
↕ generate grasp pose	25	0
↓ allow collision (hand,object)	47	0
↓ close hand	47	0
↓ attach object	47	0
↓ allow collision (object,support)	47	0
↓ lift object	19	28
↓ forbid collision (object,surface)	19	0
⚡ move to place	10	0
▼ ↕ place object	9	0
↑ allow collision (object,support)	9	0
↑ lower object	17	47
▼ ↕ place pose IK	64	45
↕ generate place pose	47	0
↓ detach object	64	0
↓ open hand	61	3
↓ forbid collision (hand,object)	61	0
↓ retreat after place	9	52
↓ close hand	9	0
↓ move home2	9	0

Figure 5.8 Pouring Stage for Panda arm 1

↓	move home2	6	0
↓	open hand2	6	0
⌘	move to pick2	2	0
▼	↕ pick object2	3	0
	↑ approach object2	3	5
▼	↕ grasp pose IK2	45	3
	↕ generate grasp pose2	150	0
	↓ allow collision (hand2,object2)2	9	0
	↓ close hand2	9	0
	↓ attach object2	9	0
	↓ allow collision (object2,support)2	9	0
	↓ lift object2	3	6
	↓ forbid collision (object2,surface)2	3	0
⌘	move to pre-pour pose2	8	0
▼	↕ pre-pour pose2	46	0
	↕ pose above glass2	9	0
	↓ pouring2	6	3
⌘	move to place2	3	0
▼	↕ place object2	3	0
	↑ allow collision (object2,support)2	3	0
	↑ lower object2	5	3
▼	↕ place pose IK2	18	0
	↕ generate place pose2	9	0
	↓ detach object2	9	0
	↓ open hand2	9	0
	↓ forbid collision (hand2,object2)2	9	0
	↓ retreat after place2	4	5
	↓ close hand2	4	0
↓	move home	3	0
↓	move home2	3	0

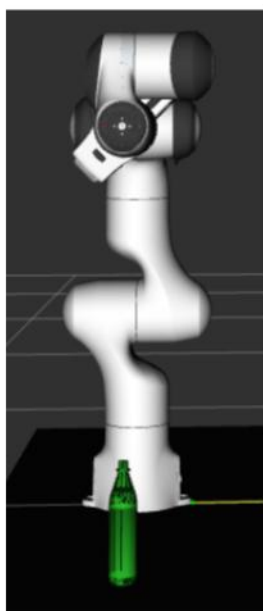
Figure 5.9 Pouring Stage for Panda arm 2

The second described application demonstrates the use of the task pipeline with custom modules, using the example of pouring into a glass. While the scenario requires a custom pouring stage, most other stages are realized with suitably parameterized standard stages to provide a robust context for this central component. The task reuses the previously described pick container to pick up the bottle. A similar container place provides a generic stage to compute place motion sequences, given a generator for feasible place poses.

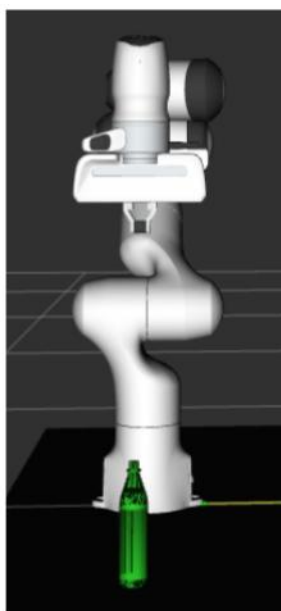
The pouring stage is implemented as tilting the tip of an attached object (the bottle) in a pouring motion over another object (the glass) for a specific period of time. The path is solved by a Cartesian planner along object-centric waypoints.

The four generator stages involved in this task are interrelated: the two last ones, bottle above glass and place location, depend on the grasp pose chosen in the pick stage. To this end, they monitor the solutions generated by the grasp stage and produce matching solutions.

Lastly, moving the bottle over the glass and moving it towards its place location are transit motions that have to account for an additional path constraint, namely keeping the bottle upright to avoid spilling of the liquid. This constraint is specified as part of the stage description and is passed on to the underlying trajectory planner. To accelerate planning with the constraint, we make use of configuration space approximations [13] implemented for OMPL-based solvers. In our experiments, using sequential planning, the task produces its first full solution after 91.38 seconds on average.



1. Current State



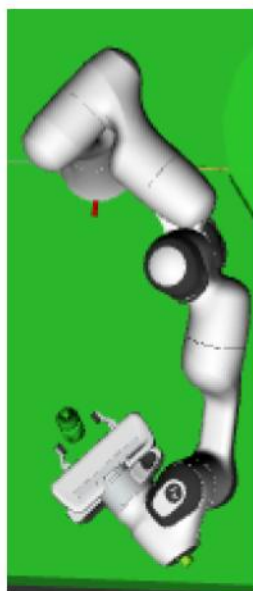
2. MoveTo Home



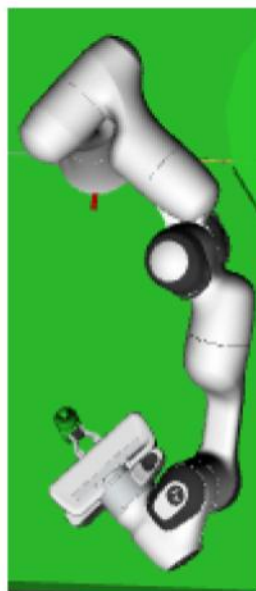
3. Open Hand



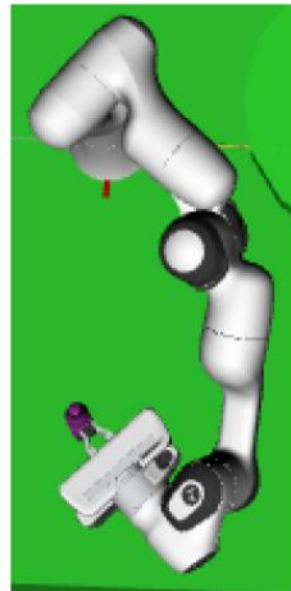
4. MoveTo Pick



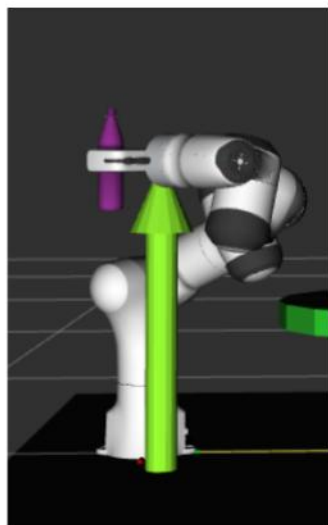
5. Approach



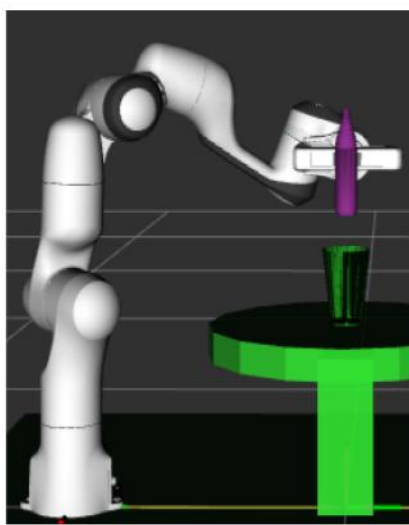
6. Grasp



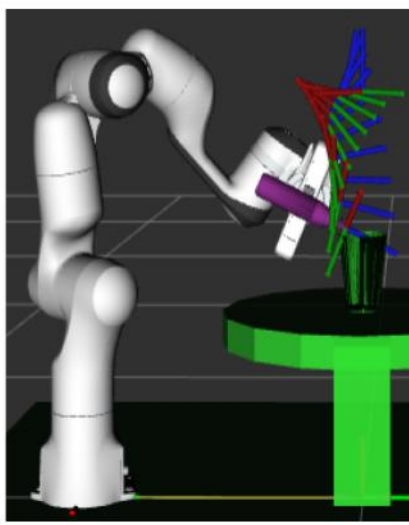
7. Attach



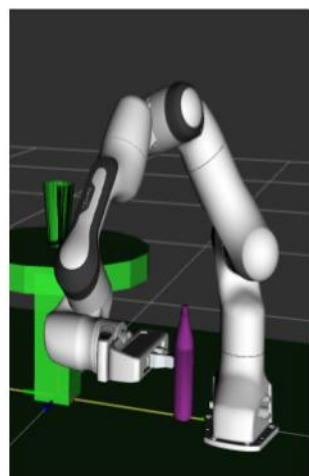
8. Lift



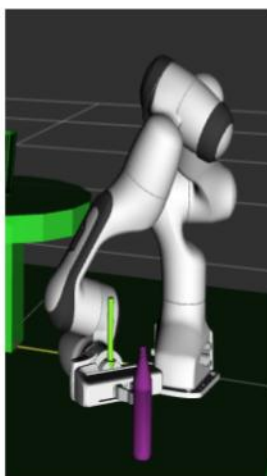
9. MoveTo Pre-Pour



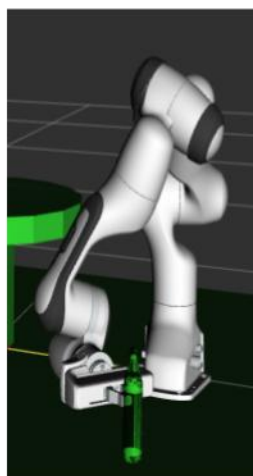
10. Pouring



11. MoveTo Place



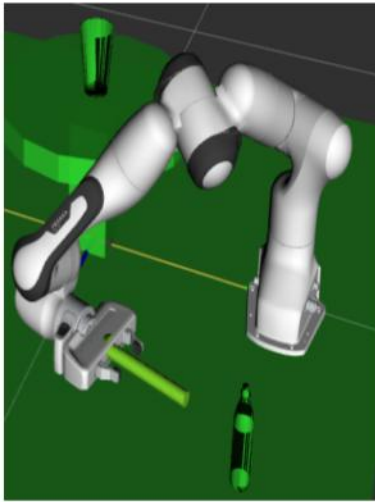
12. Lower



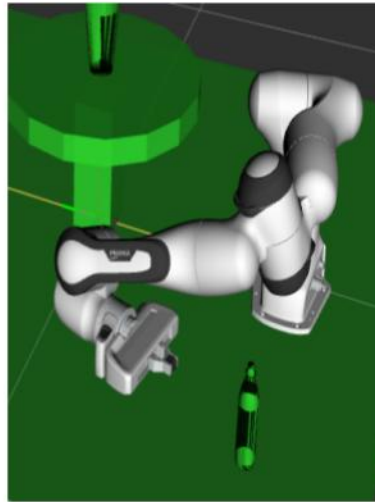
13. Detach



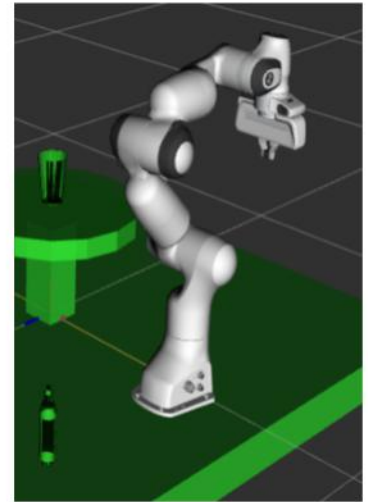
14. Open Hand



15. Retreat



16. Close Hand



17. MoveTo Home back

Figure 5.10 Various stages involved in pouring task

Chapter 6

Conclusion and Future Work

We discussed a modular and flexible planning system to fill the gap between high-level, symbolic task planning and low-level motion planning for robotic manipulation. Given a concrete task plan composed of individually characterized sub-stages, we can yield combined trajectories that achieve the whole task. Failures can be readily analyzed by visualization and isolation of problematic stages. The Task Constructor is meant to enhance the functionality of the MoveIt framework and replace its previous, severely limited pick-and-place pipeline. The open-source software library is under continuous development and various extensions were outlined directly within the corresponding sections.

As of now we have used of MTC to perform the multi arm task like building structure and complex pouring task. Going further, I'll be taking more of realistic task satellite repair. I will be working with four kinova jaco arms in more constrained environment.

Bibliography

- [1] “Move group concept.” [Online]. Available: <https://moveit.ros.org/documentation/concepts/>
- [2] “Mtc roscon presentation.” [Online]. Available: https://roscon.ros.org/2018/presentations/ROSCon2018_MoveitTaskPlanning.pdf
- [3] “Github repository for btp codes.” [Online]. Available: https://github.com/iamrajee/ws_moveit/tree/master/src/moveit_task_constructor/demo
- [4] “Denavit–hartenberg parameters.” [Online]. Available: https://en.wikipedia.org/wiki/Denavit%E2%80%93Hartenberg_parameters
- [5] R. Diankov, “Automated construction of robotic manipulation programs, ph.d. dissertation, carnegie mellon university, robotics institute, august 2010.” [Online]. Available: http://www.programmingvision.com/rosen_diankov_thesis.pdf
- [6] K. Hauser, “Robust contact generation for robot simulation with unstructured meshes, in robotics research. springer, 2016.”
- [7] S. C. D. Coleman, I. A. Sucas and N. Correll, “Reducing the barrier to entry of complex robotic software: a moveit! case study, journal of software engineering for robotics, may 2014.” [Online]. Available: <https://moveit.ros.org/>

- [8] M. M. I. A. Sucan and L. E. Kavraki, “The open motion planning library, *ieee robotics automation magazine*, december 2012.” [Online]. Available: <http://ompl.kavrakilab.org/>
- [9] J. A. B. N. Ratliff, M. Zucker and S. Srinivasa, “Chomp: Gradient optimization techniques for efficient motion planning, in *robotics and automation*, 2009. *icra’09. ieee international conference on. ieee*, 2009.”
- [10] E. T. P. P. M. Kalakrishnan, S. Chitta and S. Schaal, “Stomp: Stochastic trajectory optimization for motion planning, in *robotics and automation (icra)*, 2011 *ieee international conference on. ieee*, 2011.”
- [11] H. R. Michael Gorner, Robert Haschke and J. Zhang, “Moveit! task constructor for task-level motion planning.”
- [12] T. Kroger, “On-line trajectory generation in robotic systems: Basic concepts for instantaneous reactions to unforeseen (sensor) events. *springer*, 2010.”
- [13] I. A. Sucan and S. Chitta, “Motion planning with constraints using configuration space approximations, in *intelligent robots and systems (iros)*, 2012 *ieee/rsj international conference on. ieee*, 2012.”