

# Assignment 3

## Probabilistic Pose Estimation based on Topological Map

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In this assignment it was attempted to create a topological map of 3 different rooms using an omni camera (as was used in the previous assignment). Two different ways of topological mapping were attempted; using wall extraction and by using colored blobs. In the first case landmarks were determined by finding sequences of wall parts and corridors, and in the second case the orientation of the colored blobs were used to determine the position of the legorobot. These sequences, called fingerprints, could in theory be used to distinguish between the three different rooms, as long as the fingerprints differ enough.

### 1 The dataset

The dataset consists of multiple pictures of every room, each with a different orientation of the robot within the room. This will create different possible fingerprints for both the wall based topological mapping as well as the blob based mapping. By rotating the sequences of these fingerprints it should be clear that two fingerprints are so much alike they refer to the same room, while reducing the noise in the fingerprints. Figure ?? shows one of the images from the dataset.

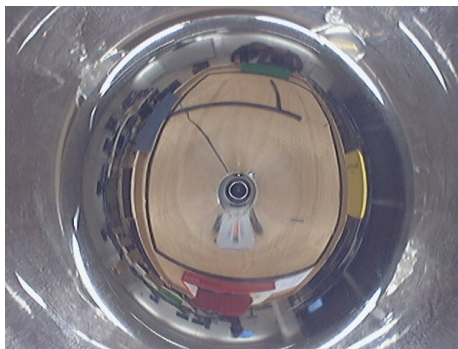


Figure 1: A picture from the dataset. Represented is room 3.

## 2 Using wall extraction for localisation

In the previous assignment we were able to successfully find data points that represented walls of our lego construction. This same method is now used in this assignment (see figure 2). The next step towards creating the final fingerprints is to first map these points to line segments, as seen in 3

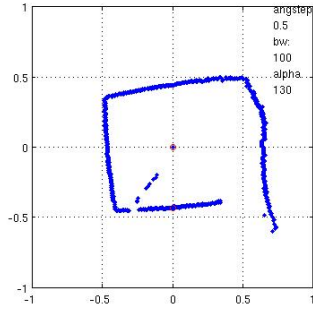


Figure 2: A picture of all extracted wall-points from room 3

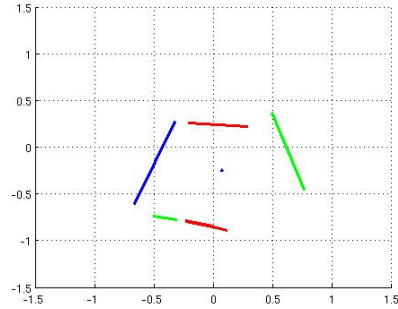


Figure 3: A picture of all extracted lines from room 3

With these line segments we are now able to create a fingerprint. Depending on the size of the **angstep** (the same variable from the previous exercise) . The **angstep** determines the angle between every laser step, and in this case also the step for each sequence in the fingerprint.

## 3 Using color blobs for localisation

Colors need to be detected by determining the right threshold in HSL values for all four of the colors. Because all blobs are not exactly one color but fall in a range of hues (due to shadow forming and light direction) all colors have a maximum and minimum hue that is used. The original image gets thresholded on these values and after that the biggest blob is extracted by using the matlab function **bwlabel**.

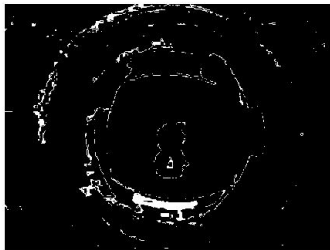


Figure 4: `imunwrap.m` Image after initial thresholding

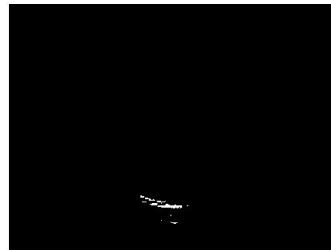


Figure 5: `imunwrap.m` Image with final blob detected

The provided script only works with two colors at one time to create the fingerprint, so we devide the colors used for every room. This makes the problem of identifying a room a lot more straightforward, as now one of the two colors can always be chosen uniquely. This is not all that unrealistic as color blobs could be the color of walls in the room or other keyfeatures. The script `ComputePatStringBlobs.m` gives the option to return the fingerprint with only a value 3 for every blob without discriminating between the colors. For room 3 we use colors red and yellow. For room 2 we use colors green and yellow and for room 1 we use colors blue and green. The set of fingerprints can be seen in ...

## 4 Comparing fingerprints using Levenshtein distance

Now that ways have been determined to establish the fingerprints, these fingerprints now need to be compared some way or the other. Because these fingerprints are nothing more than a row of characters that determine if given some radius step there is a, the Levenshtein distance can be used for this. The Levenshtein distance is a way to measure the **distance** between two sequences by determining how many deletions, replacements and insertions have to be made to end up with two the same sequences. In our use of the fingerprints only the replacement operation will be important as we use one and the same **angstep** for every fingerprint extraction.

If we want to measure the difference between two fingerprints we first need to rotate both strings so that we know for sure the orientation of the robot plays no part in the final distance calculation (for example if we want to compare a fingerprint of room 1 with another for room 1, it may not look the same in case the robot looks the other direction and thus the sequence is the same but each element is at another place). The way we chose to neglect this rotation is by putting the first element of one of the fingerprints after the last one until we end up with this character at the beginning again, at every step calculating how big the Levenshtein difference is. When it is at a minimum we know that we have compensated for the rotation of the robot.

In `find_distance.m` the strings are rotated and returned the absolute minimal Levenshtein distance (using the code provided in `LevenshteinDistance.m`) that could be found.

Now that the fingerprints have been made rotation invariant, we need to make a dataset for each room with same orientations, which can be done while running `GetLinePattern.m` and `GetBlobPattern.m` respectively. These files create a `.mat` file with encoded fingerprints.

## 5 Experiments

A script was written to match a fingerprint against each fingerprint in the labeled set of data and measure the performance of the prediction. With 3 different locations and 11 different tested fingerprints, there is a success-rate of 63%, which is okay. The set of fingerprints used for testing are the same as used for the labeled data, so it isn't the most scientifically valid test ever. It does

however demonstrate that the algorithm used works, and performs significantly better than random guessing would.

## 6 Results