Model-based robot localization using April Tags

Group #3, Construction Robotics, WS 2022/23

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Abstract-With advances in digitalization topics such as building information modeling (BIM) and structural health monitoring (SHM), the civil engineering industry provides possibilities for developing concepts for automation and robotic assistance. To combine robotics and BIM methods, the model-based localization of a robot is necessary. Localization - especially in indoor or subterranean construction sites – can become challenging because common techniques such as GPS are not accessible. Therefore, techniques working independently of global construction site conditions have to be developed. To address the problem of localizing a robot inside a BIM model and further on in a digital twin without depending on satellite connection, an indoor robot localization approach using AprilTags is developed. A mobile quadruped robot is equipped with a camera that is able to detect AprilTags in its environment. An algorithm calculates the relative position of the robot to the AprilTags and transforms the position into local coordinates. The calculated coordinates are transferred to a BIM model where the time-discrete location of the robot is visualized. After successfully localizing the robot inside a BIM model, a field test inside an office space is performed. The calculation of the local coordinates is successful under the condition, that two AprilTags with a fixed distance to each other are in the visual range of the robot's camera. Therefore, the developed localization technique is usable for model-based, indoor construction sites.

Index Terms-AprilTags, Localization, BIM

I. INTRODUCTION

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$$a + b = \gamma \tag{1}$$

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An excellent style manual for science writers is [8].

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Table	Table Column Head		
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Fig. 1. Example of a figure caption.

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ACKNOWLEDGMENT

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