

# Planning and Executing Humanoid Gaits in a World of Stairs

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# Introduction

Abstract. Humanoid Robot Locomotion Problem.

# Block Scheme

- `elevation_mapping`: autonomously build a map  $\mathcal{M}_z$
- RRT-based footstep planner: generate a footstep sequence  $\{f^j\}$  together with swing foot trajectories  $\{p_{\text{swg}}^*\}$
- variable-height CoM IS-MPC: realize a stable trajectory  $p_{\text{CoM}}^*$

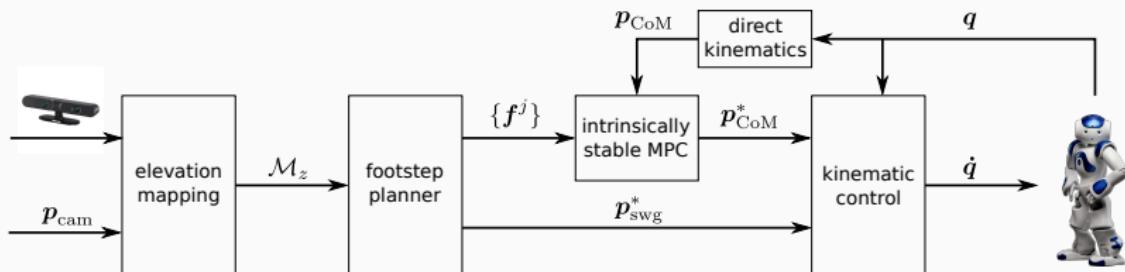


Figure 1: Block scheme of the approach.

# Variable Height CoM IS-MPC: 3D Motion Model

- LIP model not suitable for gait generation over uneven terrain
- constraint vertical motion such that

$$\frac{\ddot{z}_c + g}{z_c - z_z} = \omega^2$$

- CoM dynamics become

$$\ddot{x}_c = \omega^2(x_c - x_z)$$

$$\ddot{y}_c = \omega^2(y_c - y_z)$$

$$\ddot{z}_c = \omega^2(z_c - z_z) - g$$

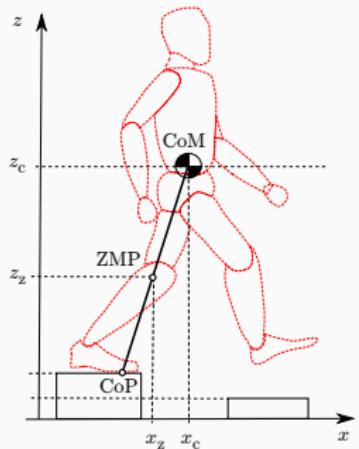


Figure 2: ZMP, CoP and COM are colinear.

# Variable Height CoM IS-MPC: MPC Formulation

- constrain ZMP into subregion of polyhedral cone (box)

$$R_{k+i}^T \begin{pmatrix} x_z^{k+i} - x_f^{k+i} \\ y_z^{k+i} - y_f^{k+i} \\ z_z^{k+i} - y_f^{k+i} \end{pmatrix} \leq \frac{1}{2} \begin{pmatrix} \tilde{d}_x^z \\ \tilde{d}_y^z \\ d_z^z \end{pmatrix}$$

- bound CoM wrt ZMP (LIP stability)

$$\frac{1}{\omega} \frac{1 - e^{-\delta\omega}}{1 - e^{-N\delta\omega}} \sum_{i=0}^{N-1} e^{-i\delta\omega} \dot{x}_z^{k+i} = x_c^k + \frac{\dot{x}_c^k}{\omega} - x_z^k \text{ internal to polyhedral cone.}$$

- solve QP problem using MPC scheme

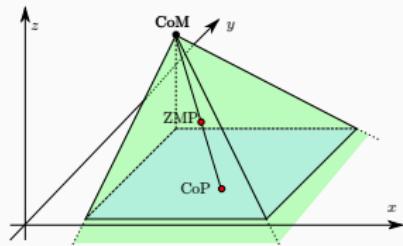


Figure 3: CoP internal to support polygon equivalent to ZMP internal to polyhedral cone.

# Variable Height CoM IS-MPC: Stair Climbing

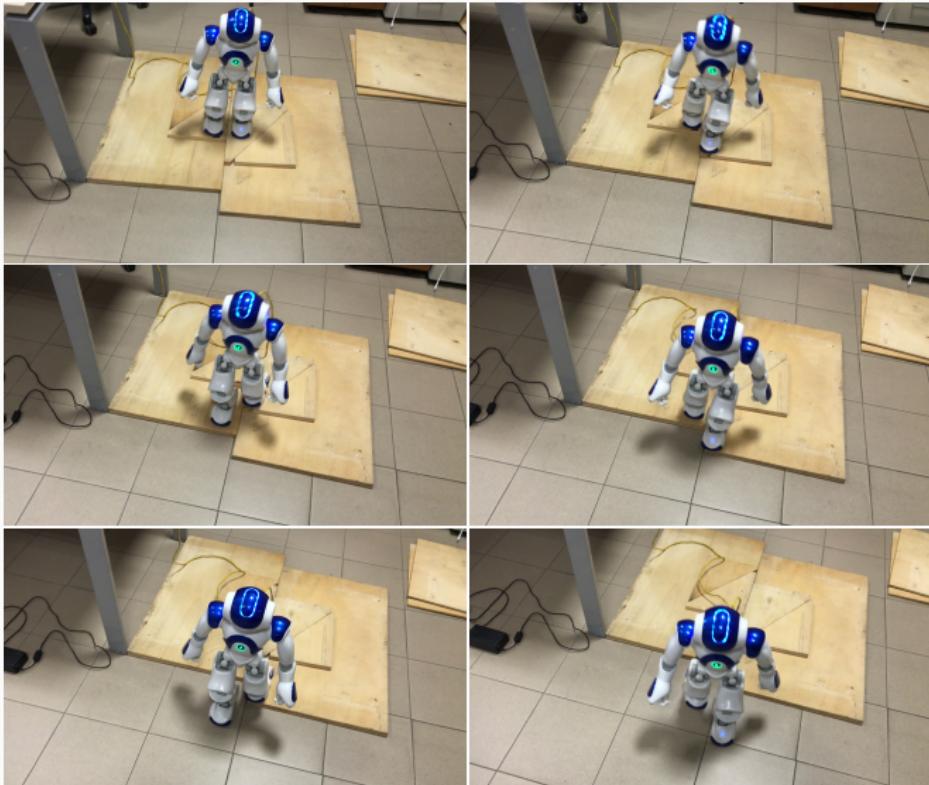


Figure 4: NAO going down the stairs.

# Variable Height CoM IS-MPC: Stair Climbing

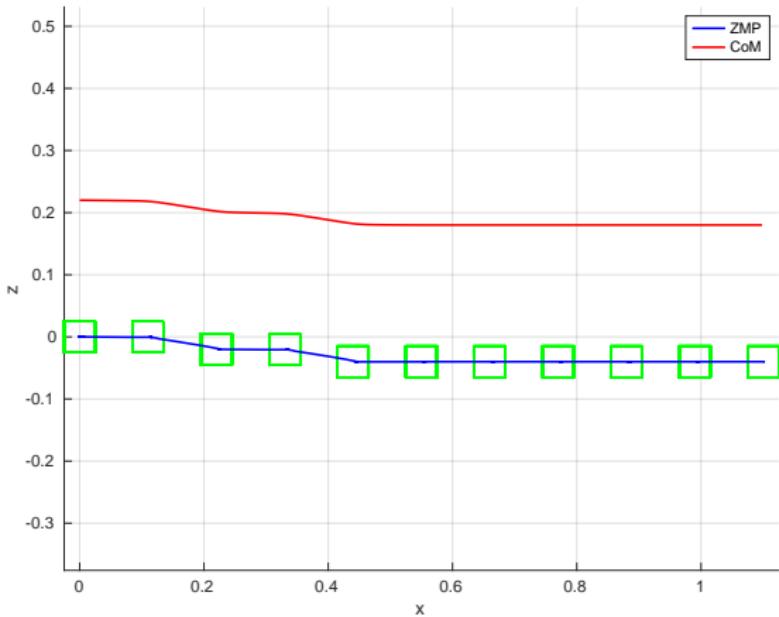


Figure 5: CoM/ZMP plot (z-axis).

# RRT-based Footstep Planning

- Rapidly-Exploring Random Tree

- R1 maximum footsteps height variation  $|z_f^j - z_f^{j-1}| \leq \Delta z_{\max}$

- R2 footstep is fully in contact with the ground

- R3 swing foot trajectory  $p_{\text{swg}}^j$  is collision free

- footstep planner iteration

1.  $p_{\text{rand}} \leftarrow \text{Rand}(\mathcal{M}_z)$

2.  $v_{\text{near}} \leftarrow \text{Nearest}(p_{\text{rand}}, \gamma, \mathcal{T})$

3.  $f_{\text{cand}} \leftarrow \text{Rand}(U)$

4. if  $f_{\text{cand}}$  feasible wrt R1-R2 then

5.  $p_{\text{swg}}^{\text{cand}} \leftarrow \text{BuildTrajectory}(\cdot)$

6.  $\mathcal{T}.\text{add}(v_{\text{new}}, v_{\text{near}})$  if  $p_{\text{swg}}^{\text{cand}}$  satisfies R3

# RRT-based Footstep Planning: Catalogue of Primitives

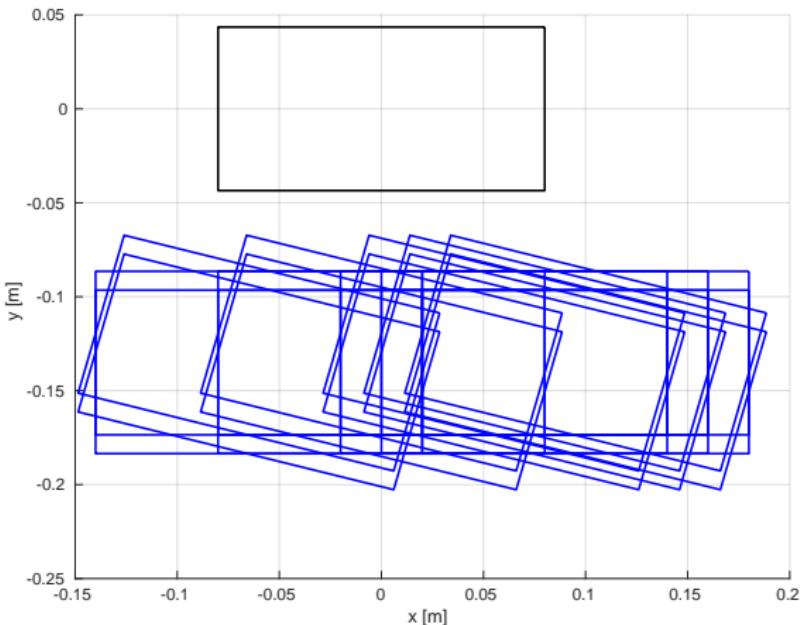


Figure 6: NAO's catalogue of primitives  $U$ .

# RRT-based Footstep Planning: Obstacle Avoidance

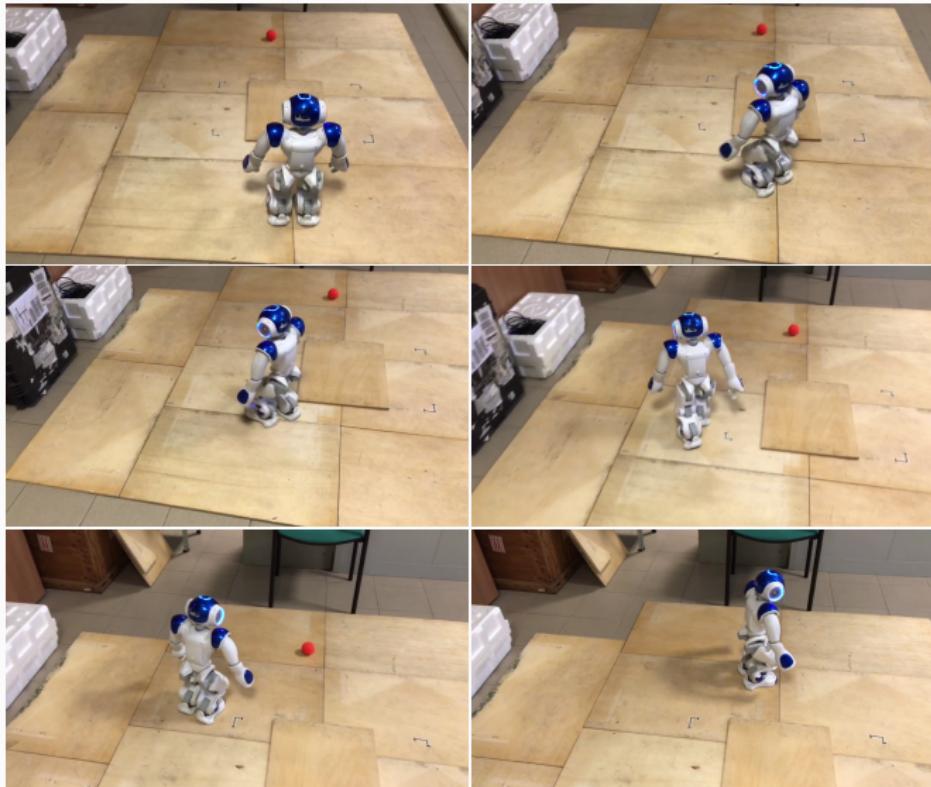


Figure 7: NAO avoiding an obstacle.

# RRT-based Footstep Planning: Obstacle Avoidance

tree size: 488 – solution size: 31 – runtime: 70 ms

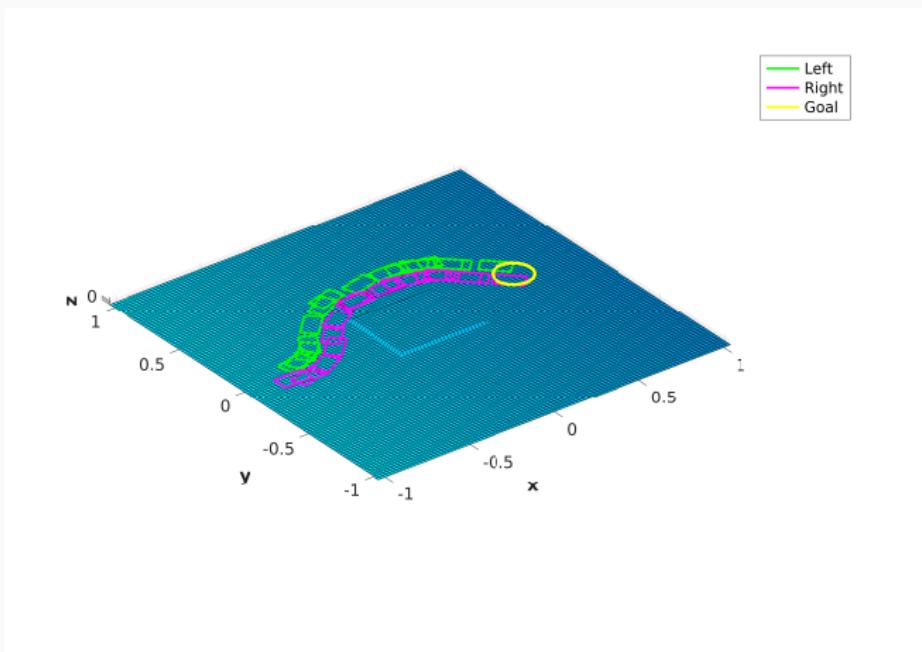


Figure 8: Footstep plan generated for the scenario “Obstacle Avoidance”.

# Elevation Map Generation

`elevation_mapping`, features, how it works (briefly). Settings: NAO + Xtion + *World of Stairs*.

Experiments: Generated Map + Stair Climbing in Unknown Environment.

Video

# Conclusion

Results. Future Works.

Q&A

## References

-  A. Zamparelli, N. Scianca, L. Lanari, and G. Oriolo, “Humanoid Gait Generation on Uneven Ground using Intrinsically Stable MPC,” *IFAC-PapersOnLine*, vol. 51, pp. 393–398, 01 2018.
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-  P. Fankhauser, M. Bloesch, and M. Hutter, “Probabilistic terrain mapping for mobile robots with uncertain localization,” *IEEE Robotics and Automation Letters (RA-L)*, vol. 3, no. 4, pp. 3019–3026, 2018.