

Planning and Executing Humanoid Gaits in a World of Stairs

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Master Degree in Artificial Intelligence and Robotics

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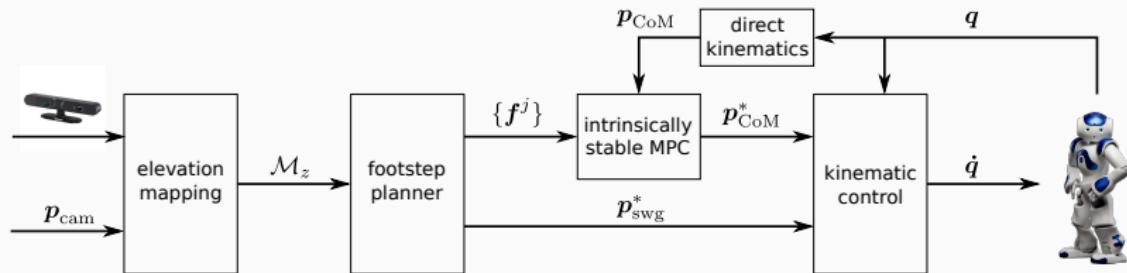
Sapienza University of Rome

Introduction

- goal: humanoid robot locomotion in a *World of Stairs*
- assumption: humanoid is equipped with a depth sensor
- assumption: humanoid knows its location



Proposed Approach



- **elevation map building**: autonomously build a map \mathcal{M}_z
- **footstep planner**: generates a footstep sequence $\{f^j\}$ on \mathcal{M}_z together with swing foot trajectories $\{p_{swg}^*\}$
- **variable-height IS-MPC**: computes a stable gait along the planned footsteps $\{f^j\}$

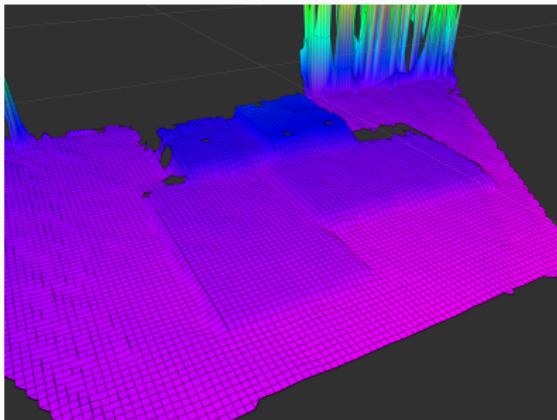
Elevation Map Building: Framework

`elevation_mapping` [Fankhauser et al., 2018]

- robot-centric grid-based map: \mathcal{M}_z
- height estimate $\mathcal{N}(\hat{h}_i, \sigma_{h_i}^2)$ for each cell i
- Kalman filter given new height and motion measurements
- map fusion: $(\hat{h}_i, h_{i,\min}, h_{i,\max})$ such that $h_i \in [h_{i,\min}, h_{i,\max}]$ with 95% confidence
- dynamic environments using visibility check based on ray tracing

Elevation Map Building: Results

- ASUS Xtion Pro (**depth sensor**)
- working range: 0.5–3.5 m



Footstep Planner

- requirements

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_{swg}^j is collision free

- RRT-based 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_{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

- U is the set of footstep primitives

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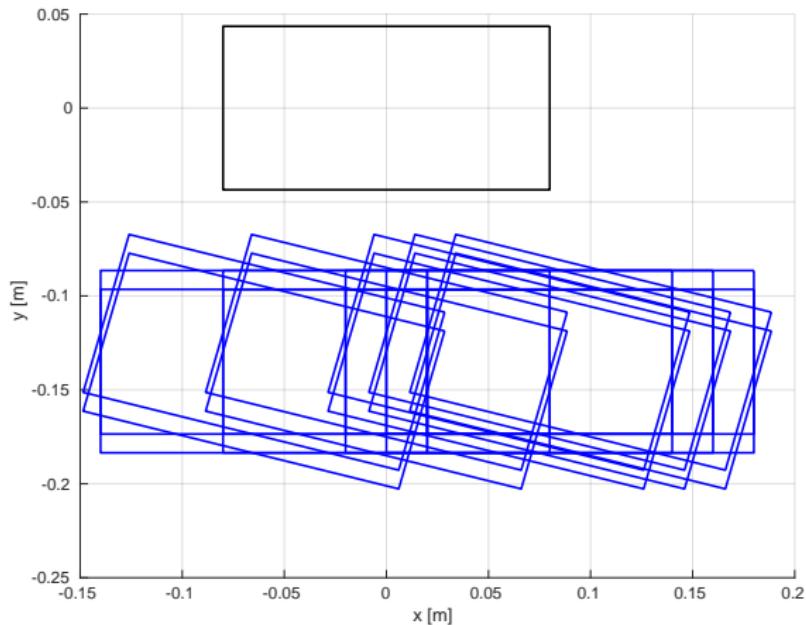
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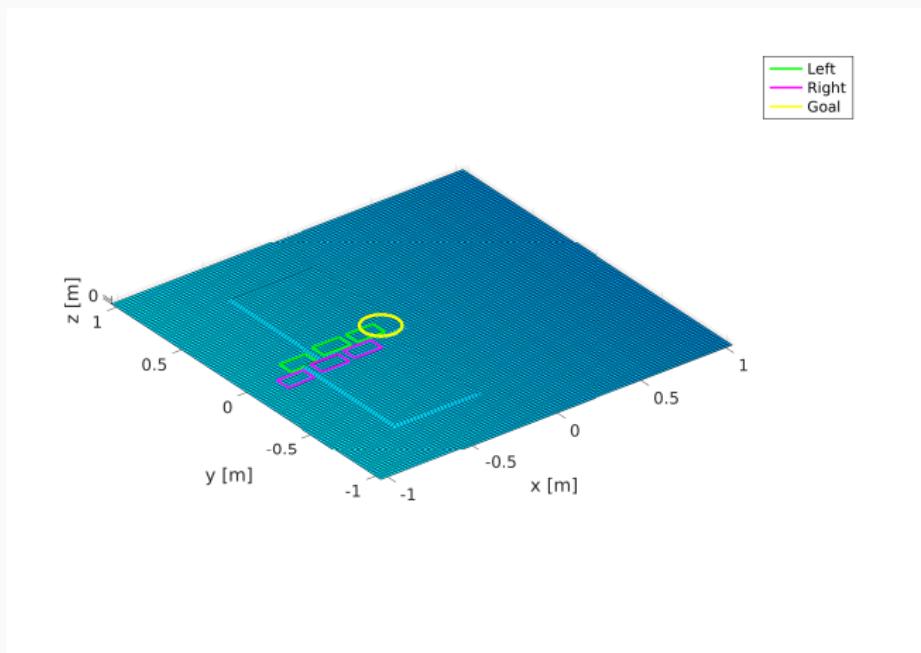
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Footstep Planner: Primitives Catalogue U



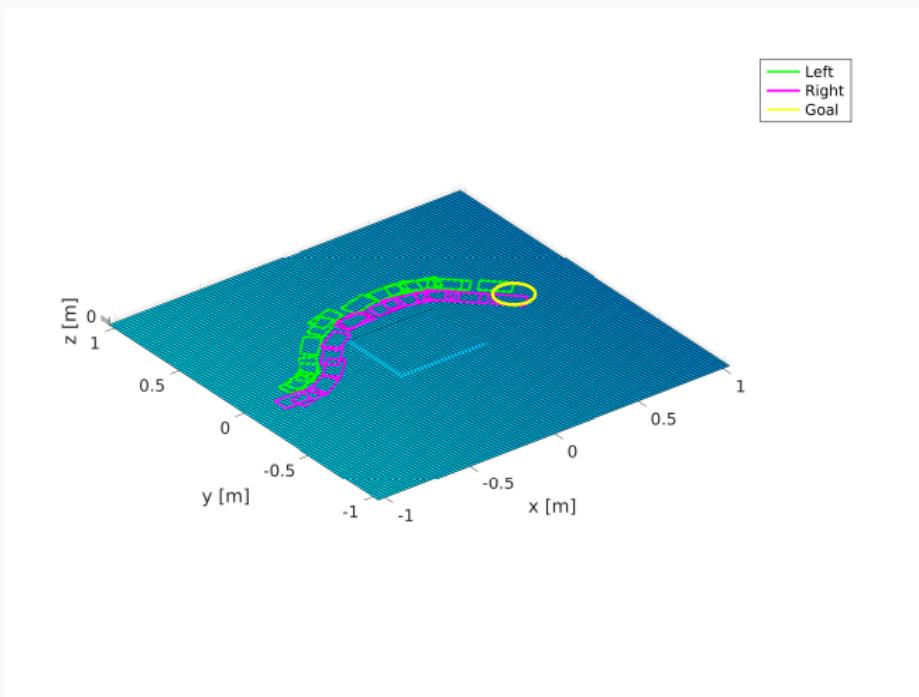
Footstep Planner: Results (stair climbing)

tree size: 10 – solution size: 6 – runtime: 0.8 ms



Footstep Planner: Results (obstacle avoidance)

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



Variable Height IS-MPC: 3D Motion Model

- LIP model not suitable for gait generation over uneven terrain due to constant height assumption
- linearity can be maintained by constraining vertical motion such that

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

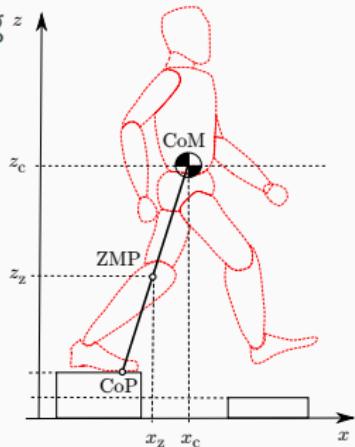
- CoM dynamics become

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

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

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

- x_c, y_c, z_c : CoM coordinates
- x_z, y_z, z_z : ZMP coordinates

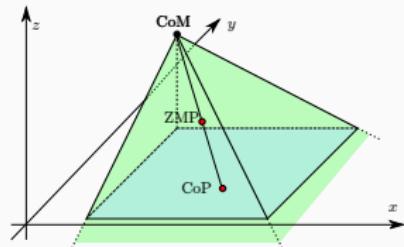


Variable Height IS-MPC: MPC Formulation

- 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)



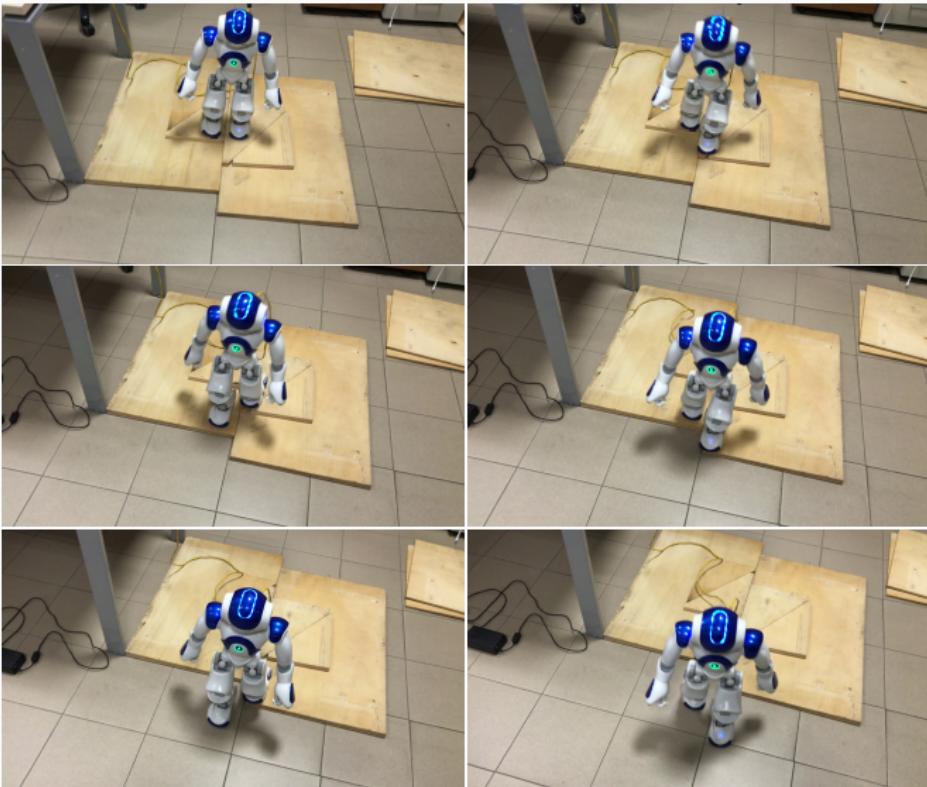
$$\frac{1}{\omega} \frac{1 - e^{-\delta\omega}}{1 - e^{-N\delta\omega}} \sum_{i=0}^{N-1} e^{-i\delta\omega} \dot{x}_z^{k+i} = x_c^k + \frac{\dot{x}_c^k}{\omega} - x_z^k$$

- solve QP problem using MPC scheme

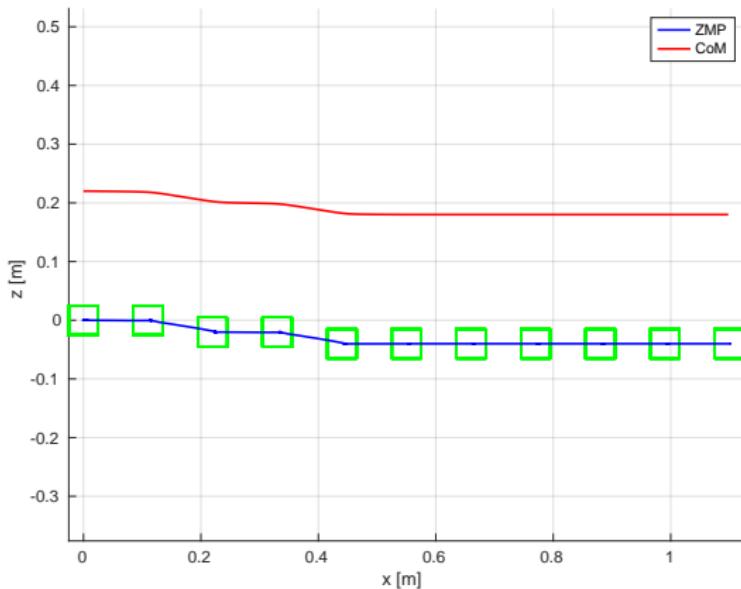
$$\min_{\dot{x}_z^k, \dot{y}_z^k, \dot{z}_z^k} \|\dot{x}_z^k\|_2^2 + \|\dot{y}_z^k\|_2^2 + \|\dot{z}_z^k\|_2^2 + \beta(\|\Delta x_f^{k+1}\|_2^2 + \|\Delta y_f^{k+1}\|_2^2 + \|\Delta z_f^{k+1}\|_2^2)$$

s.t. ZMP and stability constraints

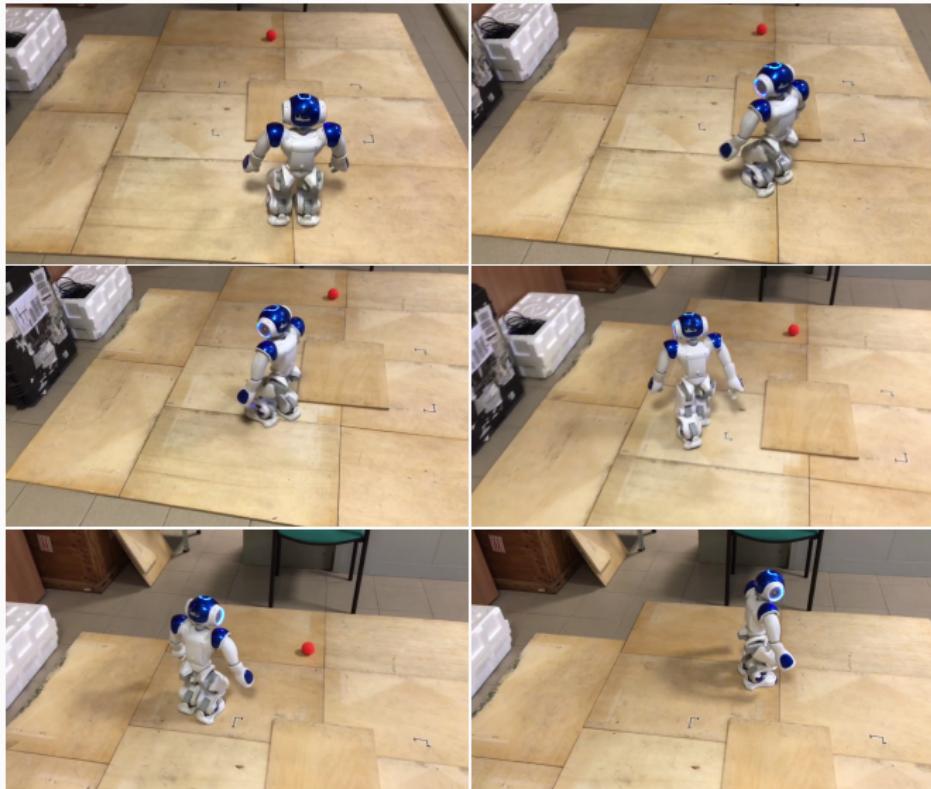
Variable Height CoM IS-MPC: Stair Climbing



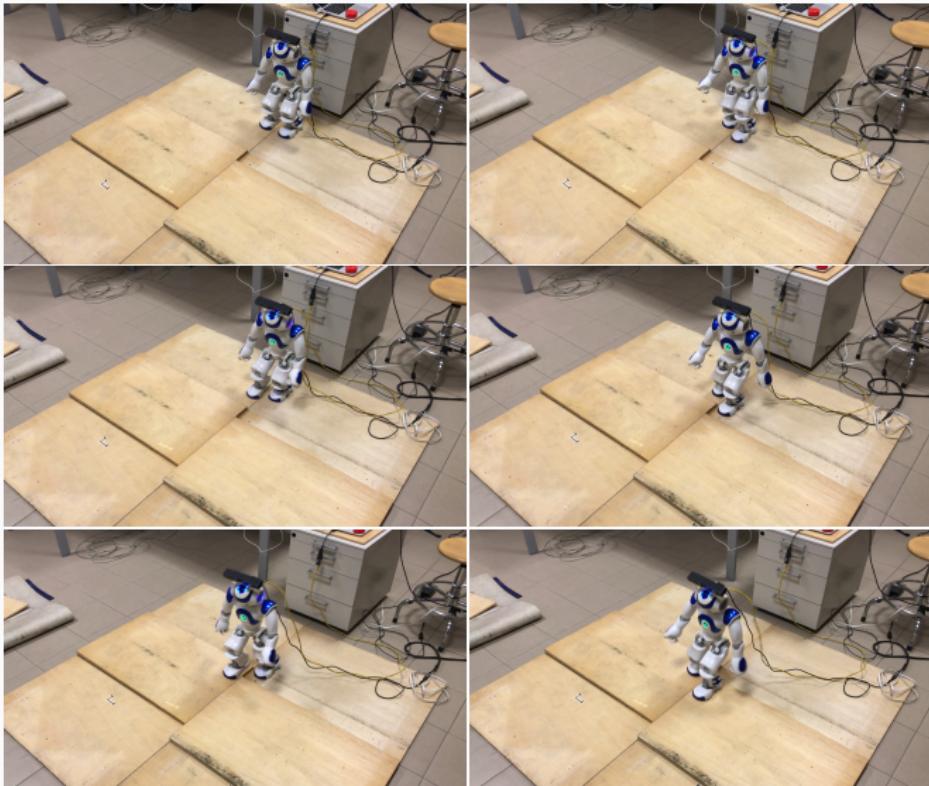
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RRT-based Footstep Planning: Obstacle Avoidance

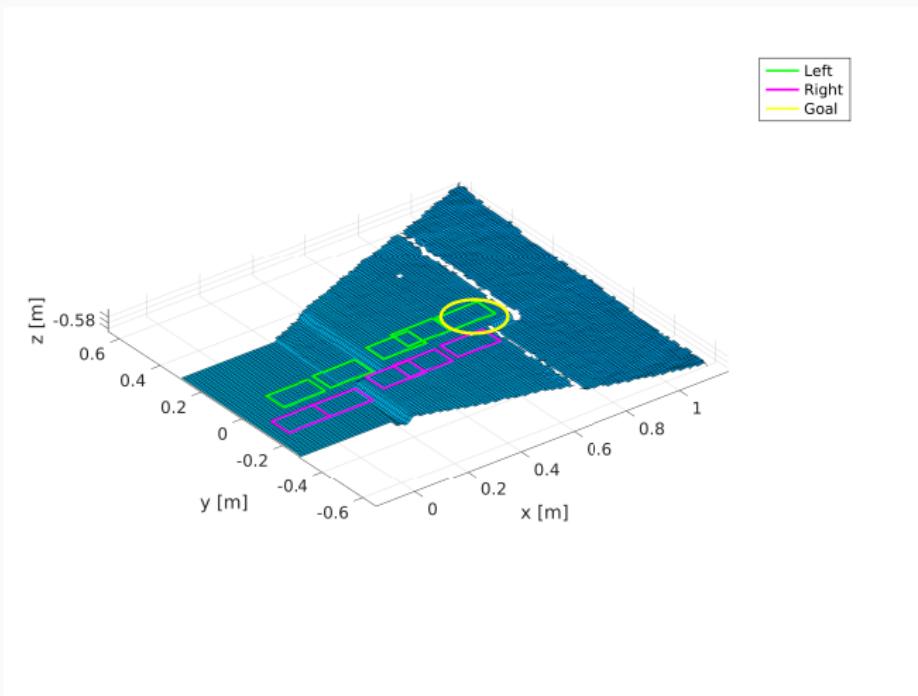


Stair Climbing in Unknown Environment



Stair Climbing in Unknown Environment: Footstep Plan

tree size: 454 – solution size: 10 – runtime: 331 ms



Conclusion: Results and Future Works

- NAO is able to autonomously climb the stairs in an unknown *World of Stairs* environment
- future works
 - localization module and continuous mapping
 - replanning phase
 - dynamic and rough environments

Q&A

References

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