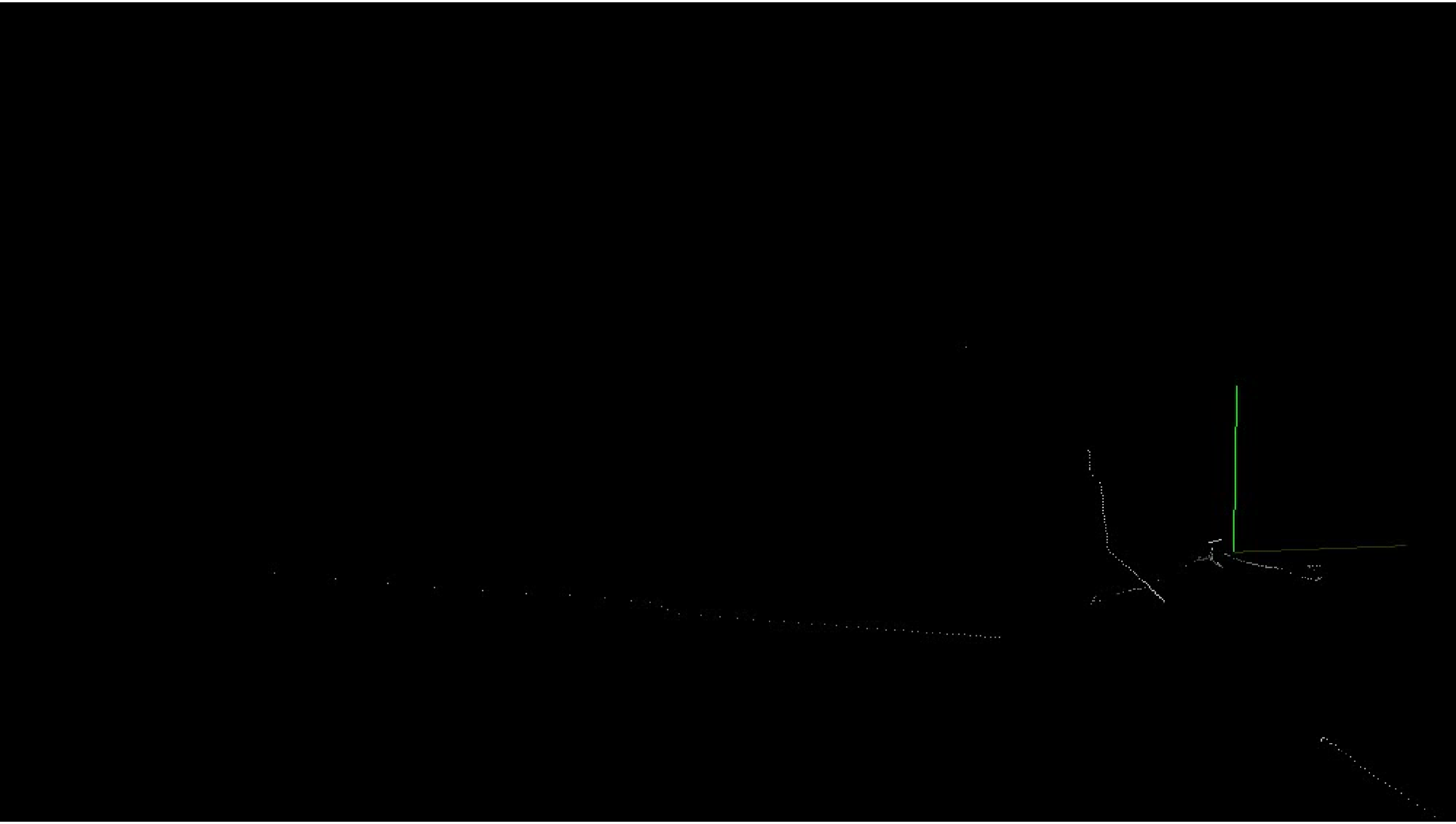
Visual Navigation for Flying Robots

Welcome

Dr. Jürgen Sturm

Advertisement: Machine Learning for Computer Vision



Advertisement: Machine Learning for Computer Vision

- Lecture by Dr. Rudolph Triebel
- Starts Friday 26th April 9-11 am, weekly
- Exercise classes every other week
- Room 02.09.023
- Topics: Probabilistic Graphical Models, Conditional Random Fields, Kernel Methods, Gaussian Processes, Boosting, Random Forests, Clustering...
- Requirements: basic math (algebra, stochastic)
- More information: http://vision.in.tum.de/teaching/ss2013/ml_ss13

Visual Navigation for Flying Robots

Welcome

Dr. Jürgen Sturm

Organization

- Tue 10:15-11:45
  - Lectures, discussions
  - Lecturer: Jürgen Sturm
- Thu 14:00-15:30
  - Lab course, homework & programming exercises
  - Teaching assistant: Jakob Engel and Christian Kerl

Who Are We?

- Computer Vision group:
  1 Professor, 3 Postdocs, 11 PhD students
- Research topics:
  Motion estimation, 3D reconstruction, image segmentation, convex optimization, shape analysis
- My research goal:
  Apply solutions from computer vision to real-world problems in robotics.

Who Are You?

Goal of this Course

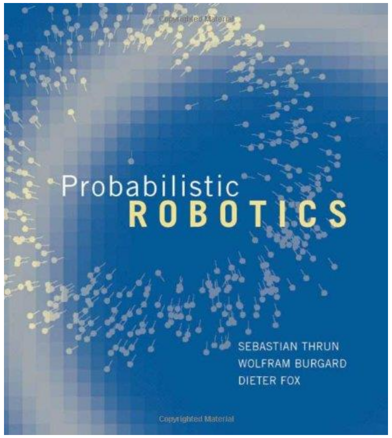
- Provide an overview on problems/approaches for autonomous quadrocopters
- Strong focus on vision as the main sensor
- Areas covered: Mobile Robotics and Computer Vision
- Hands-on experience in lab course

Course Website

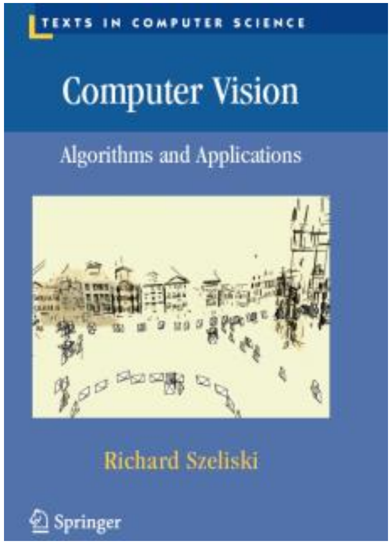
- Course Website: http://vision.in.tum.de/teaching/ss2013/visnav2013
  - Announcements
  - Schedule
  - Slides
  - Recordings
  - Exercises
- We need your feedback to improve this course!
- Let us know when you have ideas for improvement, find mistakes, …

Course Material

- Probabilistic Robotics. Sebastian Thrun, Wolfram Burgard and Dieter Fox. MIT Press, 2005.



- Computer Vision: Algorithms and Applications. Richard Szeliski. Springer, 2010. http://szeliski.org/Book/



Lecture Plan

1. Introduction
2. Robots, sensor and motion models
3. State estimation and control
4. Guest talks
5. Feature detection and matching
6. Motion estimation
7. Simultaneous localization and mapping
8. Stereo correspondence
9. 3D reconstruction
10. Navigation and path planning
11. Exploration
12. Evaluation and Benchmarking

Basics on mobile robotics

Camera-based localization and mapping

Advanced topics

Lab Course

- Jakob Engel and Christian Kerl
- Thu 14:00 – 15:30
- Room 02.05.014
- Alternation of exercises and robot lab:
  - Exercises: every two weeks, discussion of homework, **participation is required**
  - Robot lab: in weeks without exercises, help with quadrocopter programming, participation recommended

Exercises

- Exercise sheets contain both theoretical and programming problems
- 3 exercise sheets + 1 mini-project
- Deadline: before lecture (Tue 10:15)
- Hand in by email (visnav2013@vision.in.tum.de)

Group Assignment and Schedule

- 5 Parrot Ardrones
- 30 students in the course, 3 students per group → 10 groups
- Either use lab computers or bring own laptop (recommended)
- List for groups and robot schedule
- You have to sign up for a team before May 2nd (team list in lab room)
- After May 2nd, remaining places will be given to students on waiting list

Lab Course

- Starts this Thursday (room 02.05.014)
- Introduction to ROS and the Ardrone
- If you bring your own laptop:
  - Pre-install ROS
  - http://www.ros.org/wiki/ROS/Installation
- If not:
  - Jakob and Christian will provide you with user accounts for the lab machines

VISNAV2013: Team Assignment

Team Name					
Student Name					
Student Name					
Student Name					

Team Name					
Student Name					
Student Name					
Student Name					

VISNAV2013: Robot Schedule

- Each team gets one time slot with programming support
- The robots/PCs are also available during the rest of the week (but without programming support)

Thursday	Ardrone 1	Ardrone 2	Ardrone 3	Ardrone 4	Ardrone 5
2pm – 4pm					
4pm – 6pm					

Safety Warning

- Quadrocopters are dangerous objects
- Read the instructions carefully before you start
- Always use the protective hull
- If somebody gets injured, report to us so that we can improve safety guidelines
- If something gets damaged, report it to us so that we can fix it
- **NEVER TOUCH THE PROPELLORS**
- **DO NOT TRY TO CATCH THE QUADROCOPTER WHEN IT FAILS – LET IT FALL/CRASH!**

Agenda for Today

- History of mobile robotics
- Brief intro on quadrocopters
- Paradigms in robotics
- Architectures and middleware

General background

- Autonomous, automaton
  - self-willed (Greek, auto+matos)
- Robot
  - Karel Capek in 1923 play R.U.R. (Rossum’s Universal Robots)
  - labor (Czech or Polish, robota)
  - workman (Czech or Polish, robotnik)

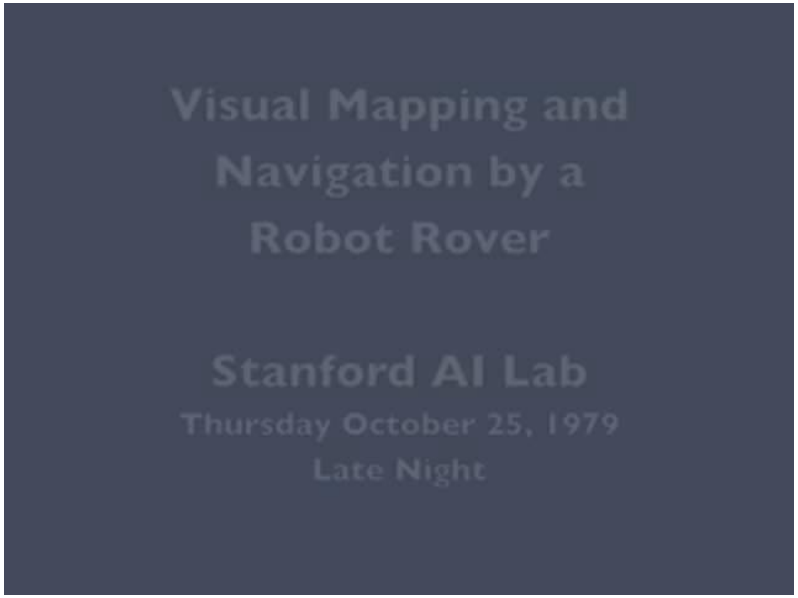
History

In 1966, Marvin Minsky at MIT asked his undergraduate student Gerald Jay Sussman to

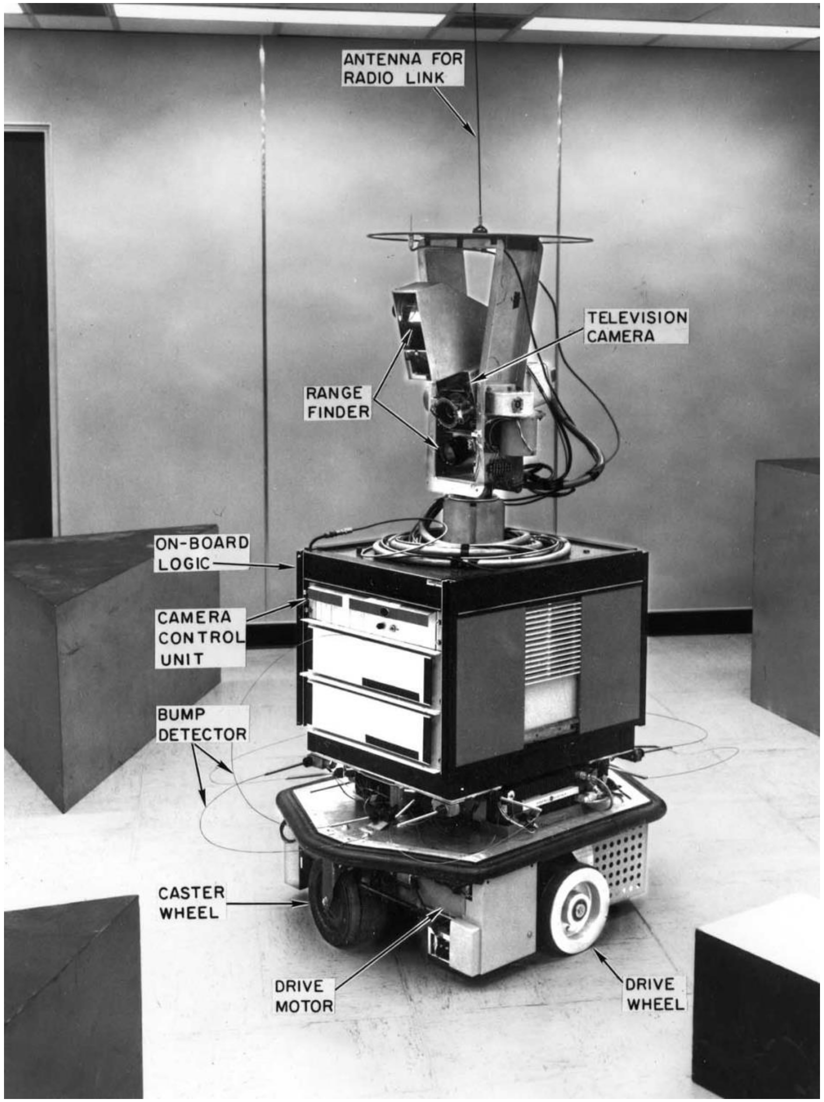
"spend the summer linking a camera to a computer and getting the computer to describe what it saw".

We now know that the problem is slightly more difficult than that. (Szeliski 2009, Computer Vision)

Stanford Cart (1961-80)



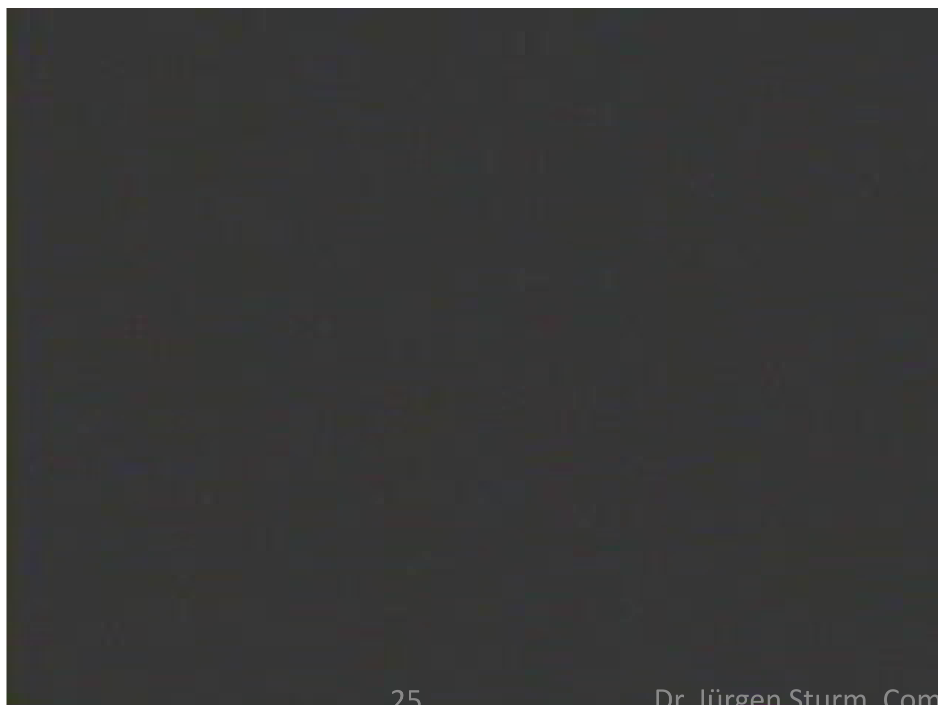
Shakey the Robot (1966-1972)



Shakey the Robot (1966-1972)

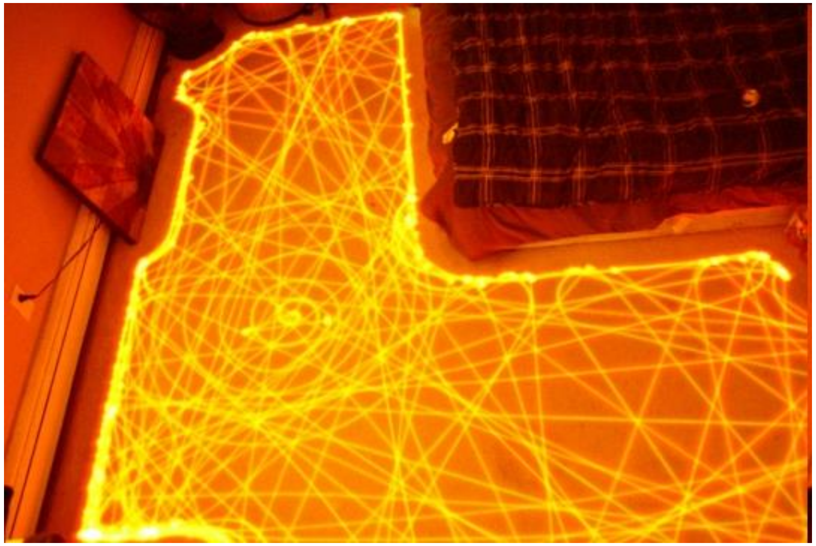
Rhino and Minerva (1998-99)

- Museum tour guide robots
- University of Bonn and CMU
- Deutsches Museum, Smithsonian Museum



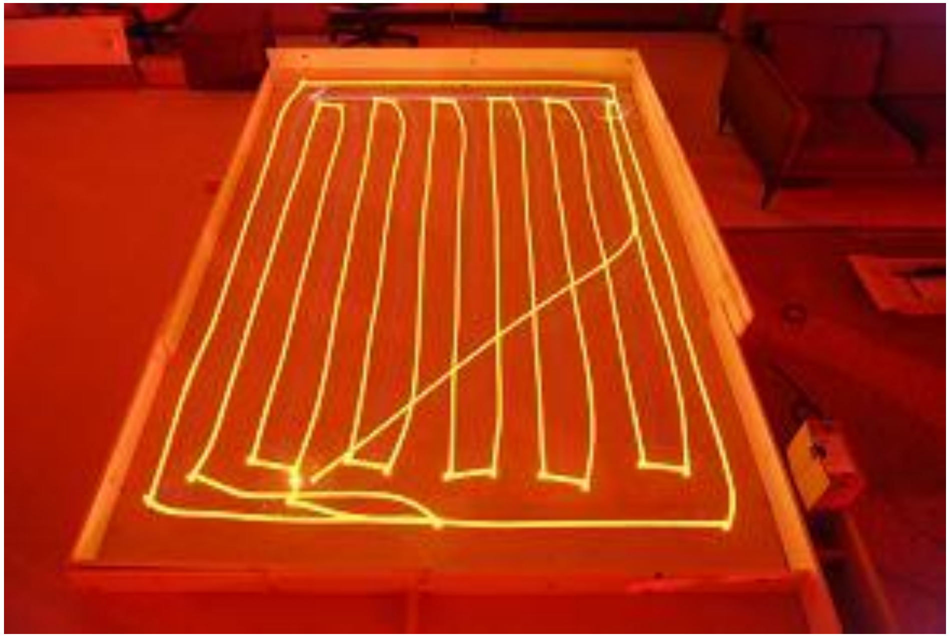
Roomba (2002)

- Sensor: one contact sensor
- Control: random movements
- Over 5 million units sold



Neato XV-11 (2010)

- Sensors:
  - 1D range sensor for mapping and localization
  - Improved coverage



Darpa Grand Challenge (2005)

Kiva Robotics (2007)

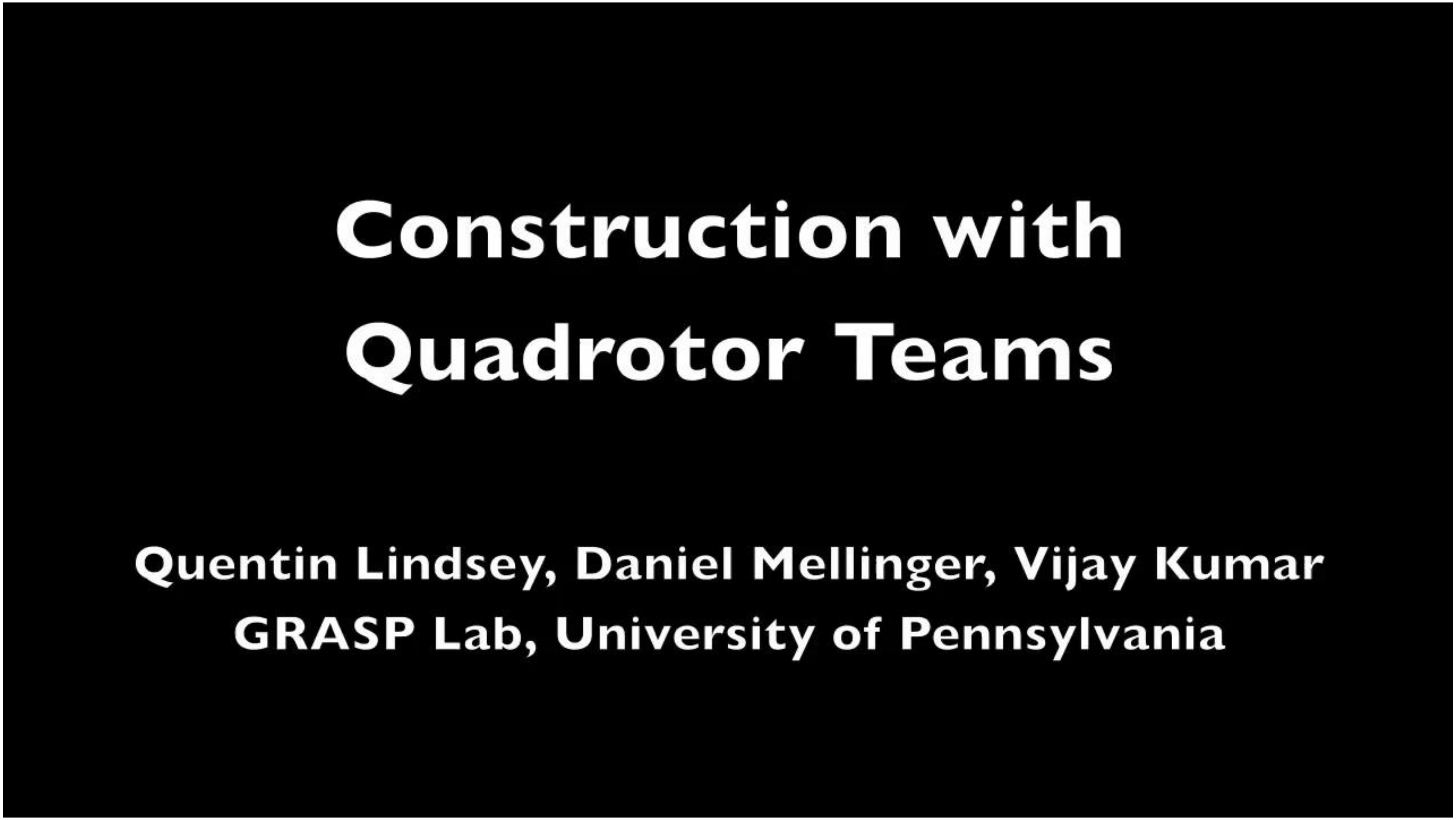
- Pick, pack and ship automation

Fork Lift Robots (2010)

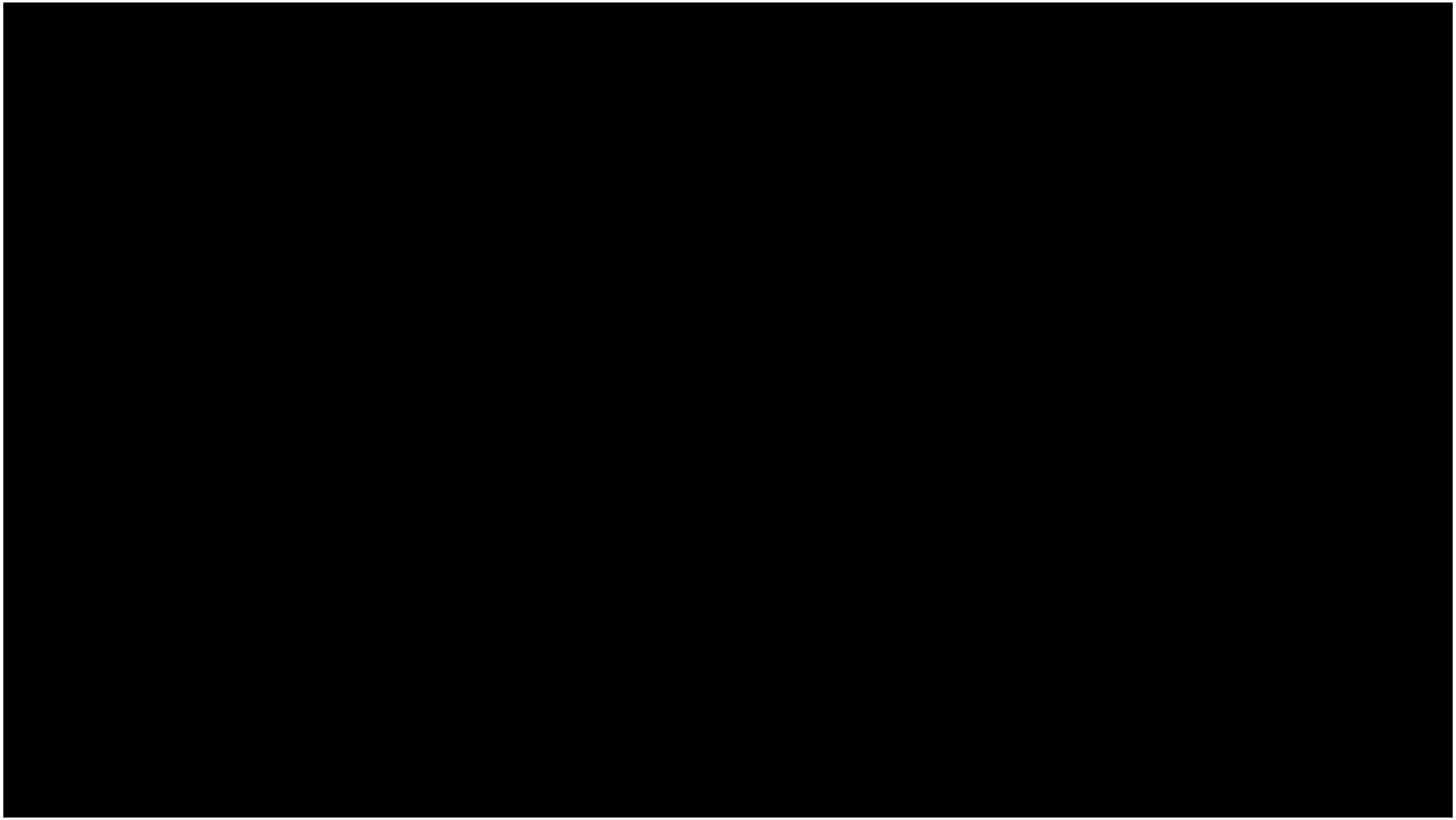
Quadrocopters (2001-)

Aggressive Maneuvers (2010)

Autonomous Construction (2011)

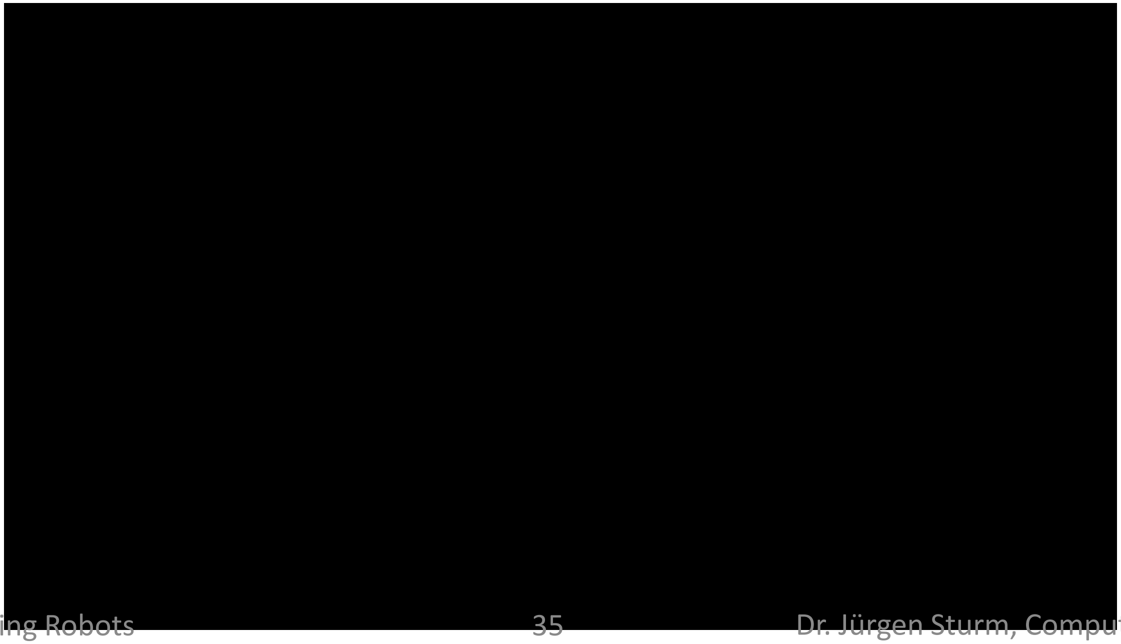


Mapping with a Quadrocopter (2011)



Our Own Recent Work (2011-)

- Visual odometry (Frank Steinbrücker, Christian Kerl)
- Camera-based navigation (Jakob Engel)
- 3D Reconstruction (Erik Bylow)



Current Trends in Robotics

Robots are entering novel domains

- Industrial automation
- Domestic service robots
- Medical, surgery
- Entertainment, toys
- Autonomous cars
- **Aerial monitoring/inspection/construction**

Flying Robots

- Recently increased interest in flying robots
  - Shift focus to different problems (control is much more difficult for flying robots, path planning is simpler, …)
- Especially quadrocopters because
  - Can keep position
  - Reliable and compact
  - Low maintenance costs
- Trend towards miniaturization

Application Domains of Flying Robots

- Stunts for action movies, photography, sportscasts
- Search and rescue missions
- Aerial photogrammetry
- Documentation
- Aerial inspection of bridges, buildings, …
- Construction tasks
- Military
- Today, quadrocopters are often still controlled by human pilots

Quadrocopter Platforms

- Commercial platforms
  - Ascending Technologies
  - Parrot Ardrone ⟵ **Used in the lab course**
  - …
- Community/open-source projects
  - Mikrokopter
  - Paparazzi
  - …

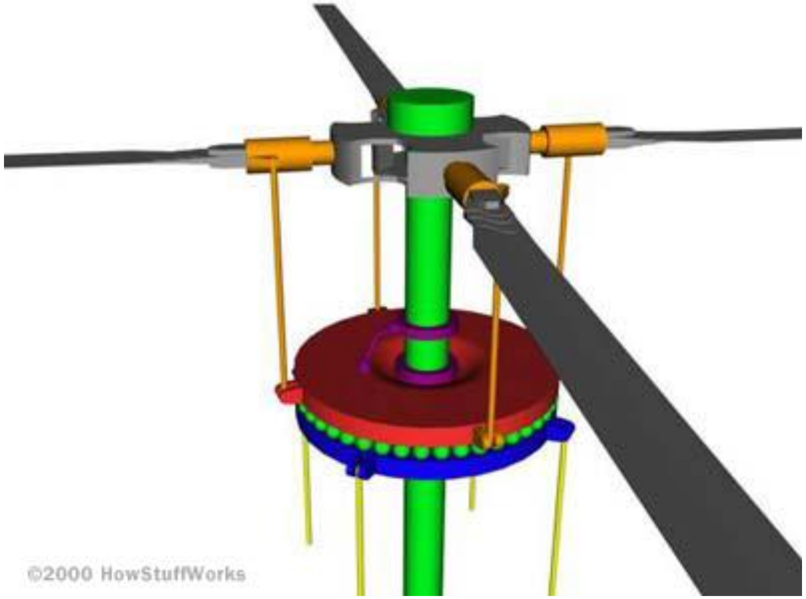
For more, see http://multicopter.org/wiki/Multicopter_Table

Flying Principles

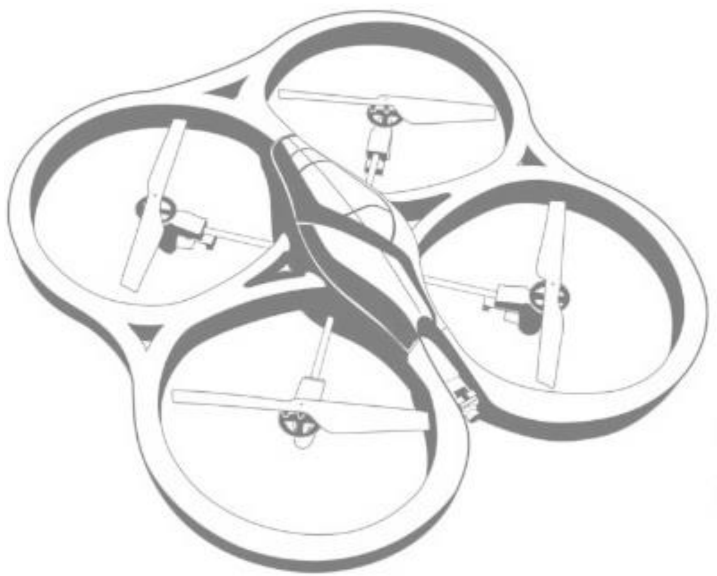
- Fixed-wing airplanes
  - generate lift through forward airspeed and the shape of the wings
  - controlled by flaps
- Helicopters/rotorcrafts
  - main rotor for lift, tail rotor to compensate for torque
  - controlled by adjusting rotor pitch
- Quadrocopter/quadrotor
  - four rotors generate thrust
  - controlled by changing the speeds of rotation

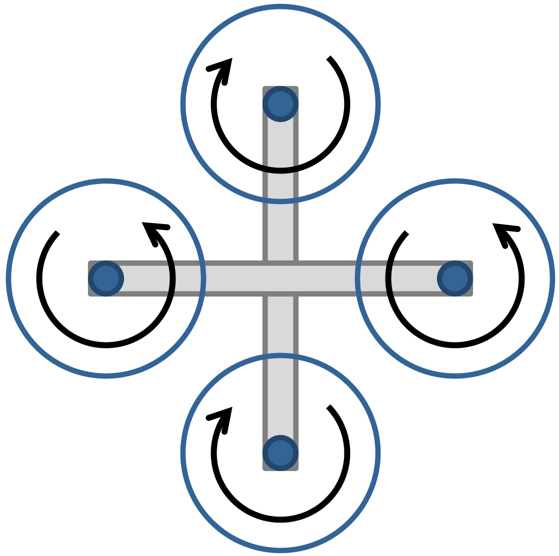
Helicopter

- Swash plate adjusts pitch of propeller cyclically, controls pitch and roll
- Yaw is controlled by tail rotor



Quadrocopter

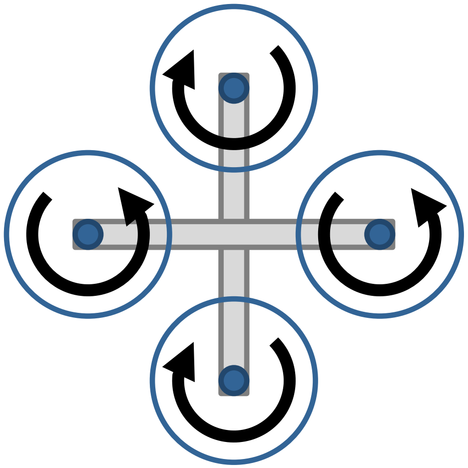




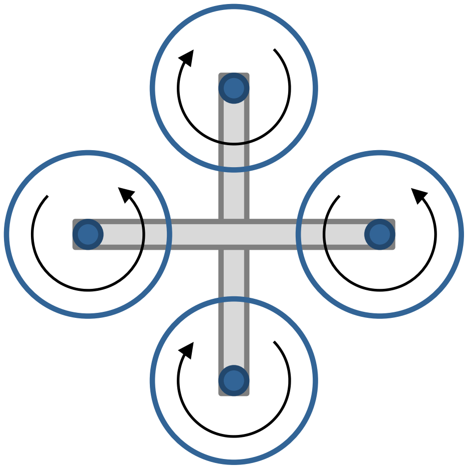
Keep position:

- Torques of all four rotors sum to zero
- Thrust compensates for earth gravity

Quadrocopter: Basic Motions

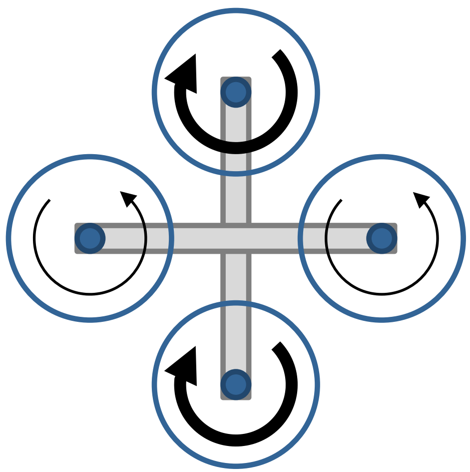


Ascend

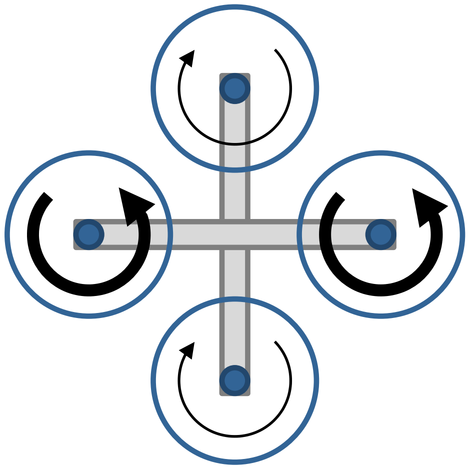


Descend

Quadrocopter: Basic Motions

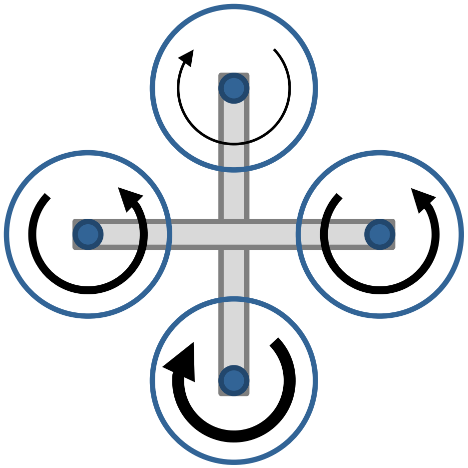


Turn Left

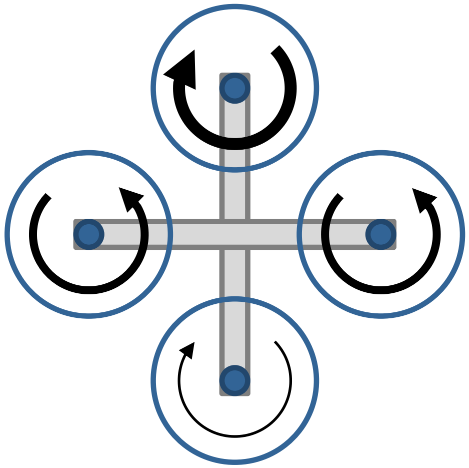


Turn Right

Quadrocopter: Basic Motions

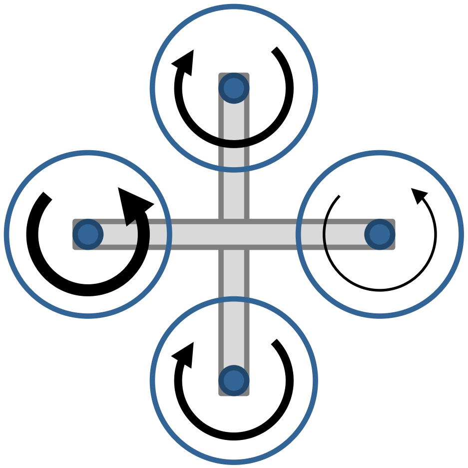


Accelerate
Forward

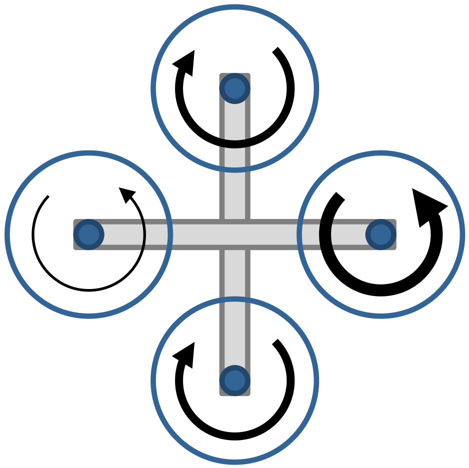


Accelerate
Backward

Quadrocopter: Basic Motions



Accelerate
to the Right



Accelerate
to the Left

Autonomous Flight

- Low level control (not covered in this course)
  - Maintain attitude, stabilize
  - Compensate for disturbances
- High level control
  - Compensate for drift
  - Avoid obstacles
  - Localization and Mapping
  - Navigate to point
  - Return to take-off position
  - Person following

Challenges

- Limited payload
  - Limited computational power
  - Limited sensors
- Limited battery life
- Fast dynamics, needs electronic stabilization
- Quadrocopter is always in motion
- Safety considerations

Roboticist Ethics

- Where does the responsibility for a robot lie?
- How are robots motivated?
- Where are humans in the control loop?
- How might society change with robotics?
- Should robots be programmed to follow a code of ethics, if this is even possible?

Robot Ethics

Three Laws of Robotics (Asimov, 1942):

- A robot may not injure a human being or, through inaction, allow a human being to come to harm.
- A robot must obey the orders given to it by human beings, except where such orders would conflict with the First Law.
- A robot must protect its own existence as long as such protection does not conflict with the First or Second Laws.

Robot Design

Imagine that we want to build a robot that has to perform navigation tasks…

How would you tackle this?

- What hardware would you choose?
- What software architecture would you choose?

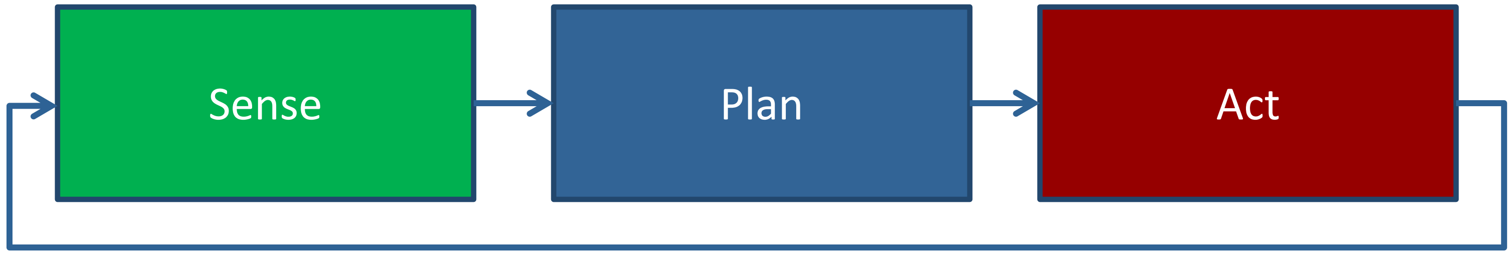
Robot Hardware/Components

- Sensors
- Actuators
- Control Unit/Software

Evolution of Paradigms in Robotics

- Classical robotics (mid-70s)
  - Exact models
  - No sensing necessary
- Reactive paradigms (mid-80s)
  - No models
  - Relies heavily on good sensing
- Hybrid approaches (since 90s)
  - Model-based at higher levels
  - Reactive at lower levels
- Current trends (since mid 2000s)
  - Big data
  - Cloud computing

Classical / hierarchical paradigm

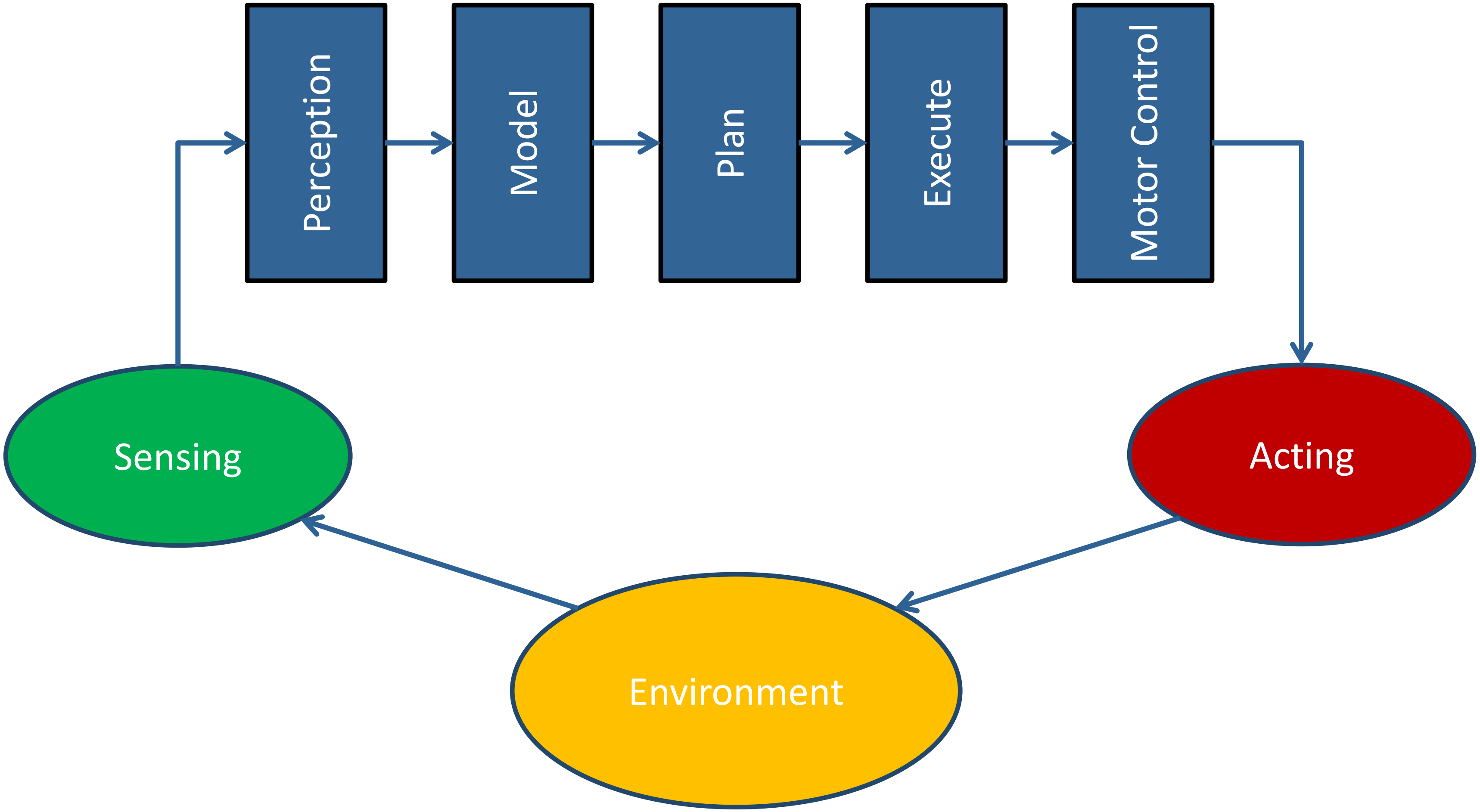


- Inspired by methods from Artificial Intelligence (70's)
- Focus on automated reasoning and knowledge representation
- STRIPS (Stanford Research Institute Problem Solver): Perfect world model, closed world assumption
- Shakey: Find boxes and move them to designated positions

Classical paradigm: Stanford Cart

- Take nine images of the environment, identify interesting points, estimate depth
- Integrate information into global world model
- Correlate images with previous image set to estimate robot motion
- On basis of desired motion, estimated motion, and current estimate of environment, determine direction in which to move
- Execute motion

Classical paradigm as horizontal/functional decomposition

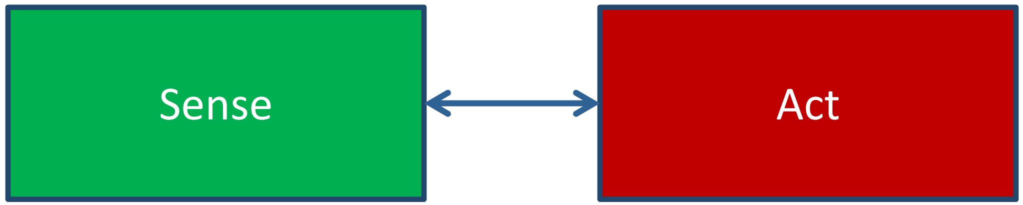


Characteristics of hierarchical paradigm

Good old-fashioned Artificial Intelligence (GOFAI):

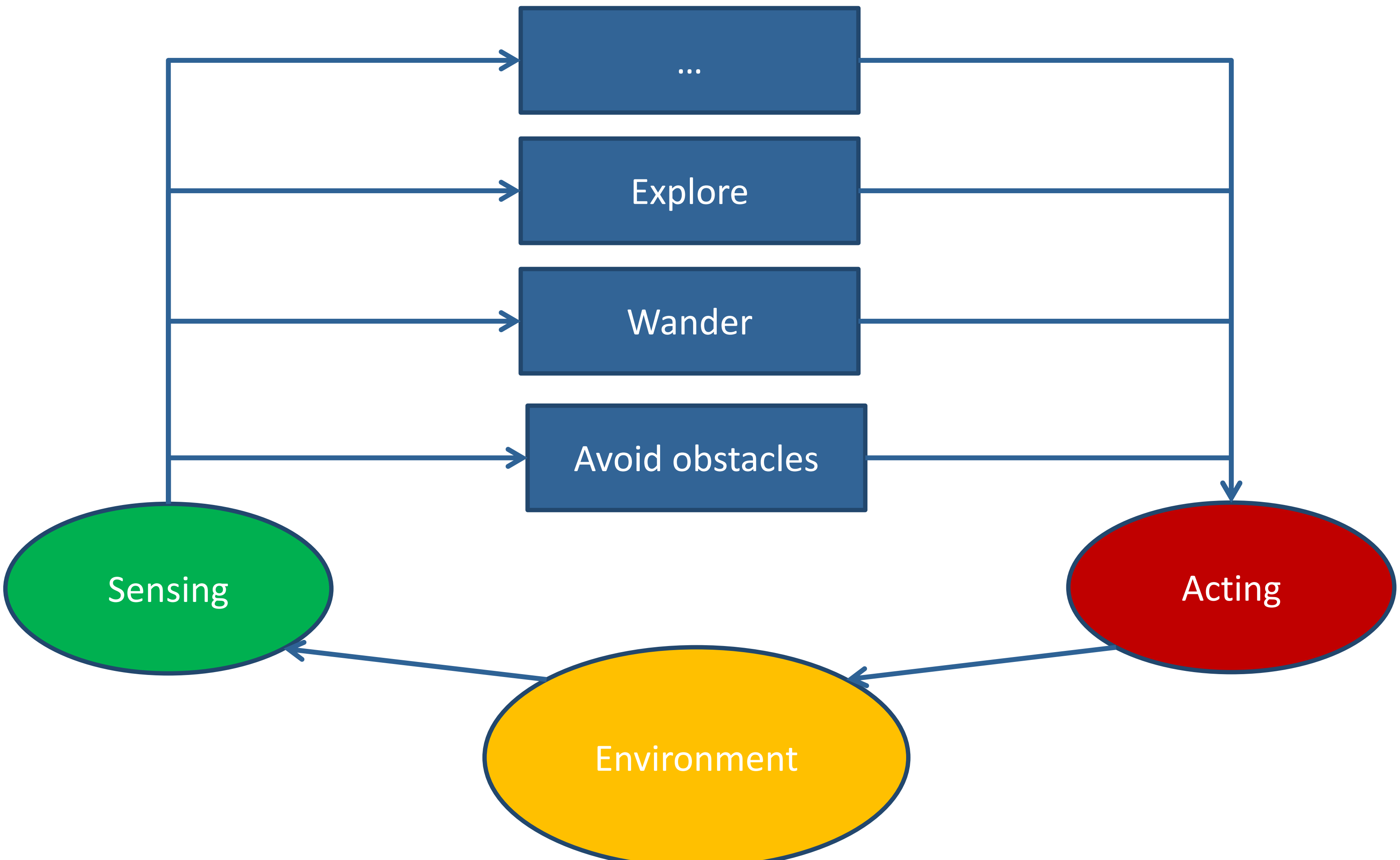
- Symbolic approaches
- Robot perceives the world, plans the next action, acts
- All data is inserted into a single, global world model
- Sequential data processing

Reactive Paradigm



- Sense-act type of organization
- Multiple instances of stimulus-response loops (called behaviors)
- Each behavior uses local sensing to generate the next action
- Combine several behaviors to solve complex tasks
- Run behaviors in parallel, behavior can override (subsume) output of other behaviors

Reactive Paradigm as Vertical Decomposition



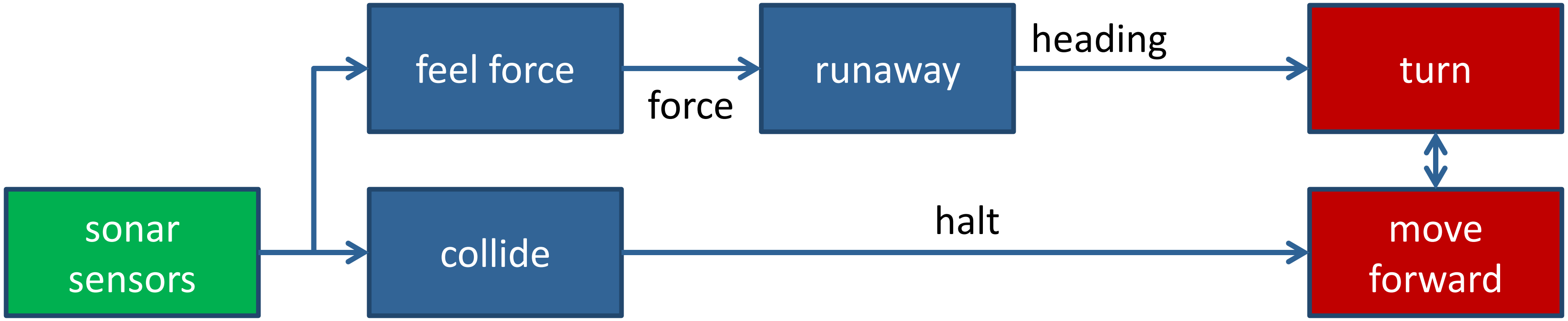
Characteristics of Reactive Paradigm

- Situated agent, robot is integral part of the world
- No memory, controlled by what is happening in the world
- Tight coupling between perception and action via behaviors
- Only local, behavior-specific sensing is permitted (ego-centric representation)

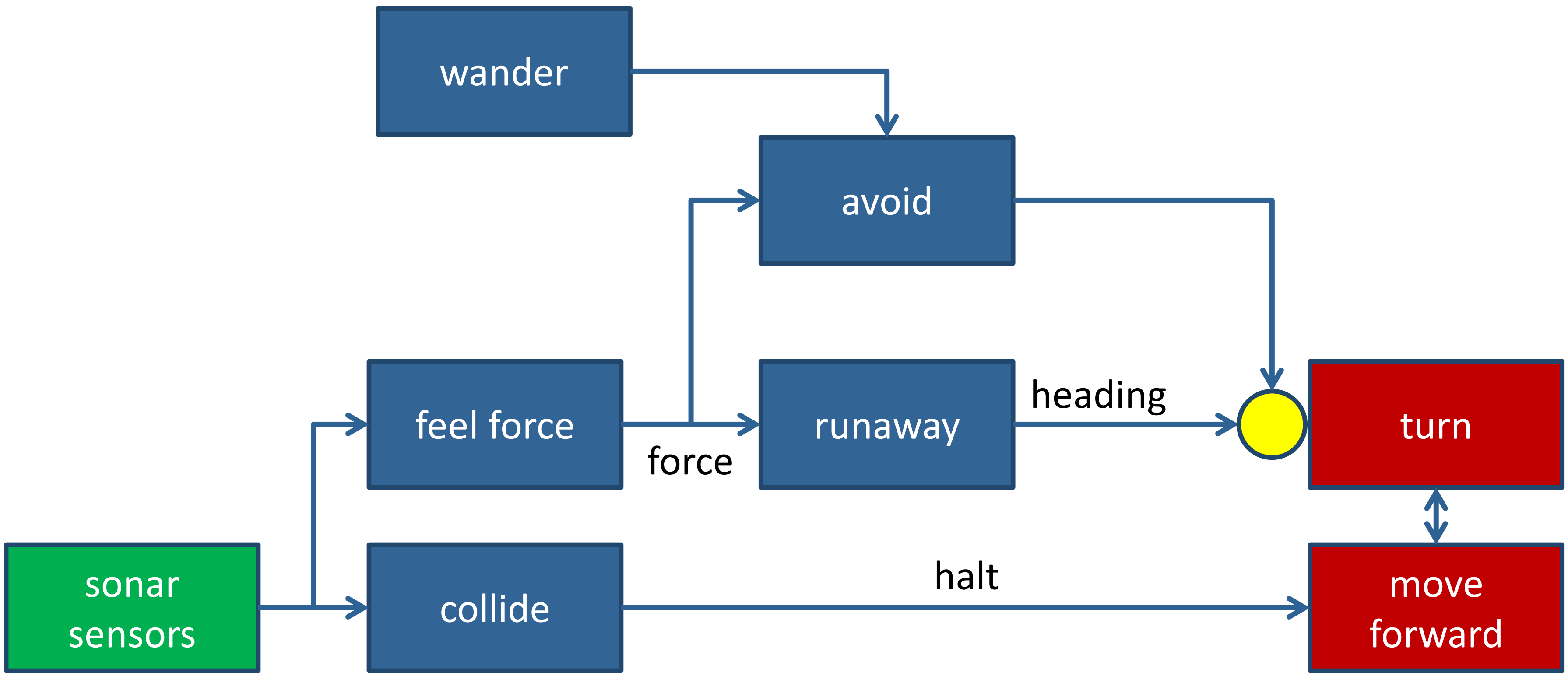
Subsumption Architecture

- Introduced by Rodney Brooks in 1986
- Behaviors are networks of sensing and acting modules (augmented finite state machines)
- Modules are grouped into layers of competence
- Layers can subsume lower layers

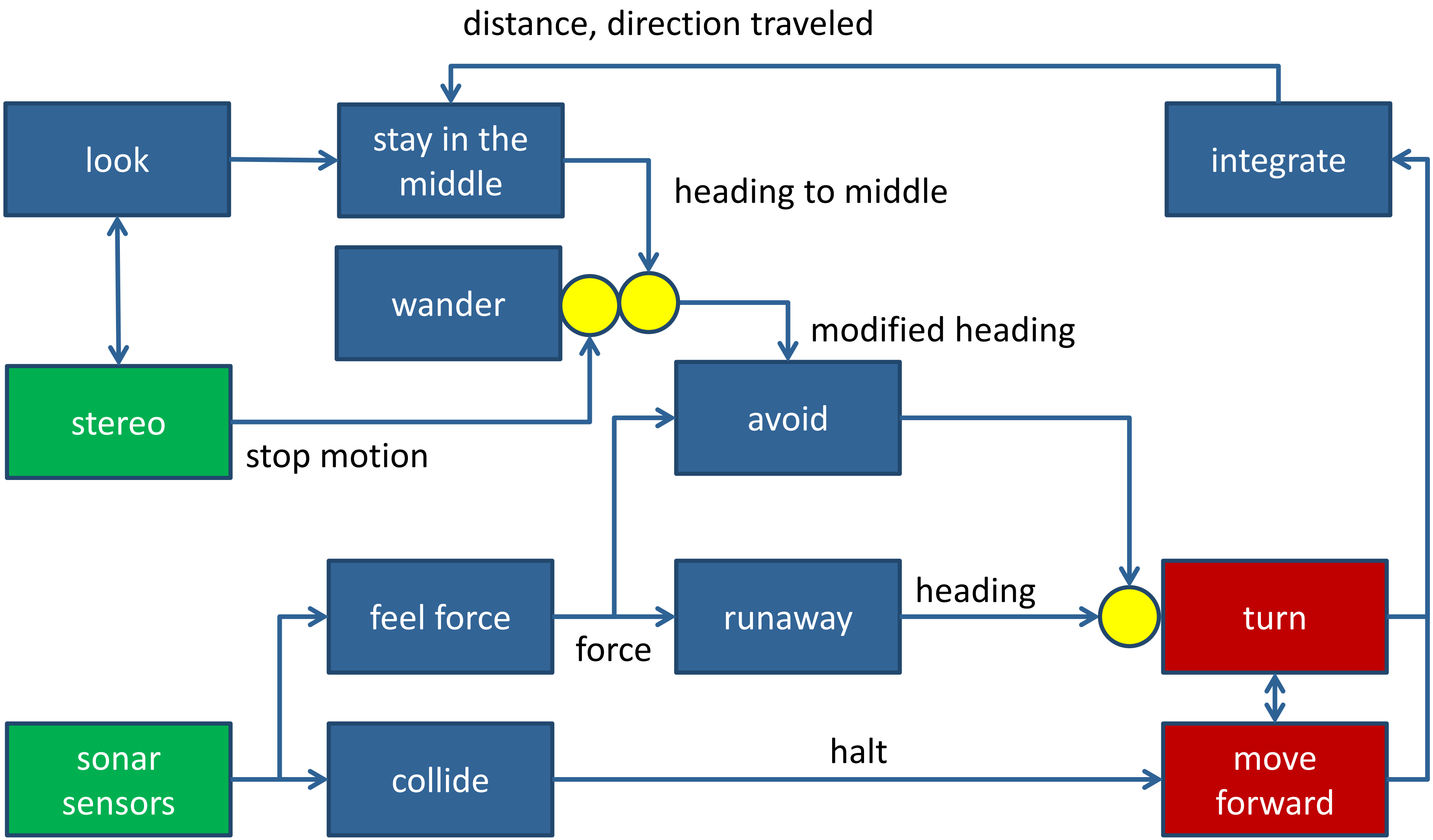
Level 1: Avoid



Level 2: Wander



Level 3: Follow Corridor



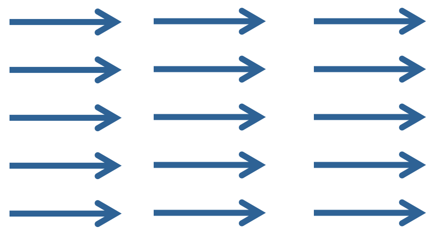
Roomba Robot

- Exercise: Model the behavior of a Roomba robot.

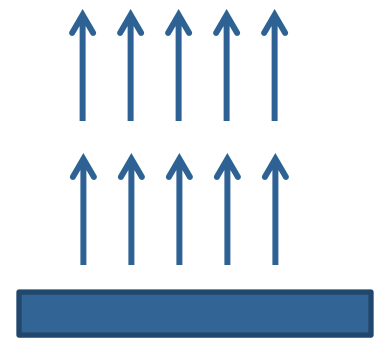
Navigation with Potential Fields

- Treat robot as a particle under the influence of a potential field
- Robot travels along the derivative of the potential
- Field depends on obstacles, desired travel directions and targets
- Resulting field (vector) is given by the summation of primitive fields
- Strength of field may change with distance to obstacle/target

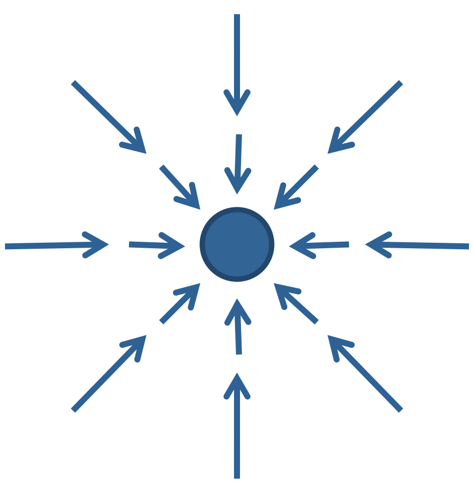
Primitive Potential Fields



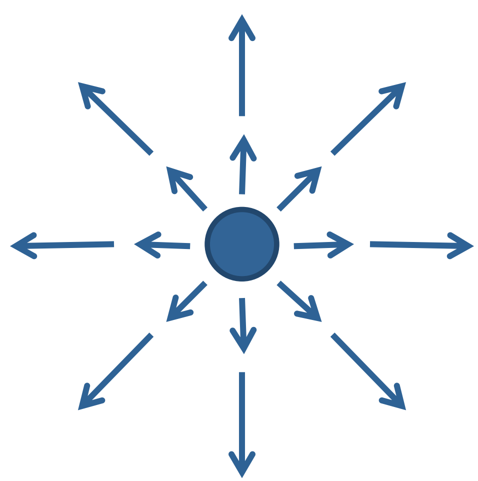
Uniform



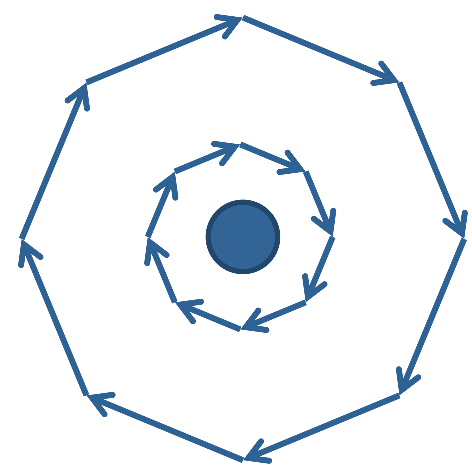
Perpendicular



Attractive

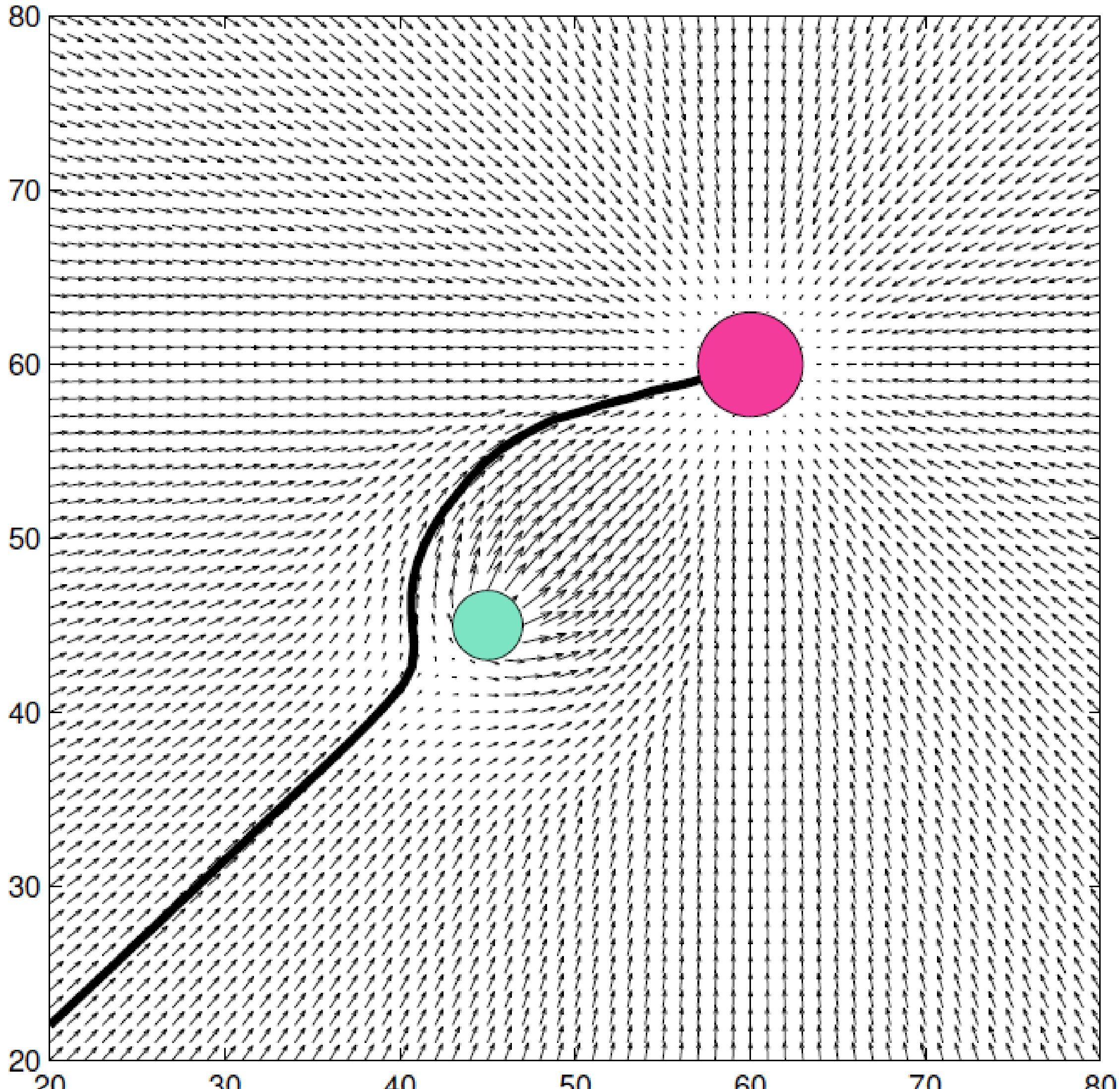


Repulsive



Tangential

Example: reach goal and avoid obstacles

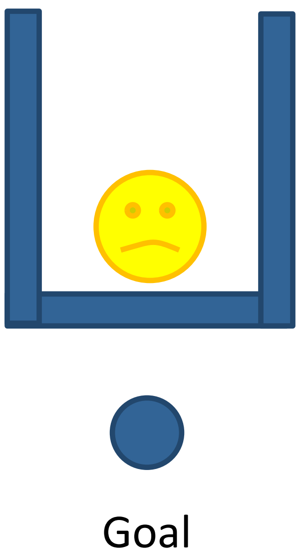


Corridor Following Robot

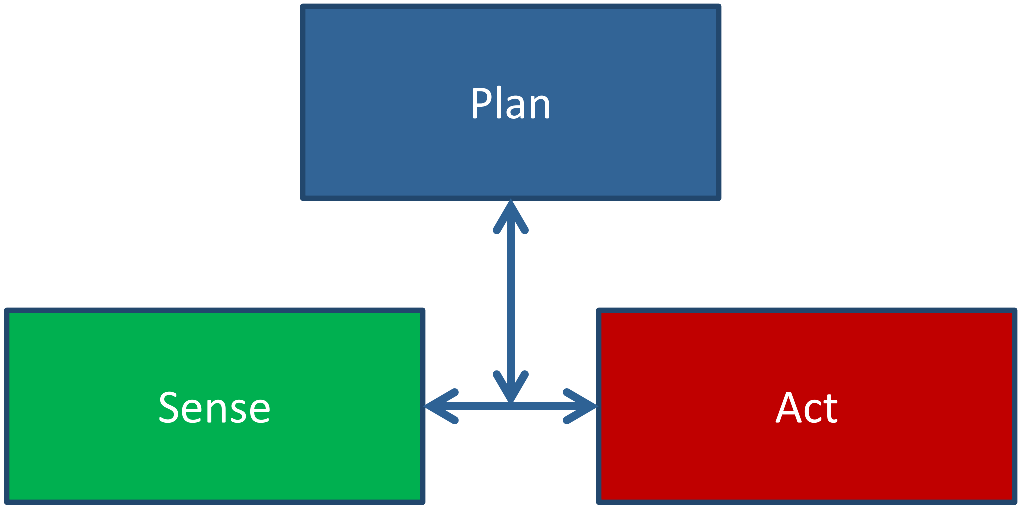
- Level 1 (collision avoidance)
  add repulsive fields for the detected obstacles
- Level 2 (wander)
  add a uniform field into a (random) direction
- Level 3 (corridor following)
  replaces the wander field by three fields (two perpendicular, one parallel to the walls)

Characteristics of Potential Fields

- Simple method which is often used
- Easy to visualize
- Easy to combine different fields (with parameter tuning)
- But: Suffer from local minima
  - Random motion to escape local minimum
  - Backtracking
  - Increase potential of visited regions
  - High-level planner



Hybrid deliberative/reactive Paradigm



- Combines advantages of previous paradigms
  - World model used in high-level planning
  - Closed-loop, reactive low-level control

Modern Robot Architectures

- Robots became rather complex systems
- Often, a large set of individual capabilities is needed
- Flexible composition of different capabilities for different tasks

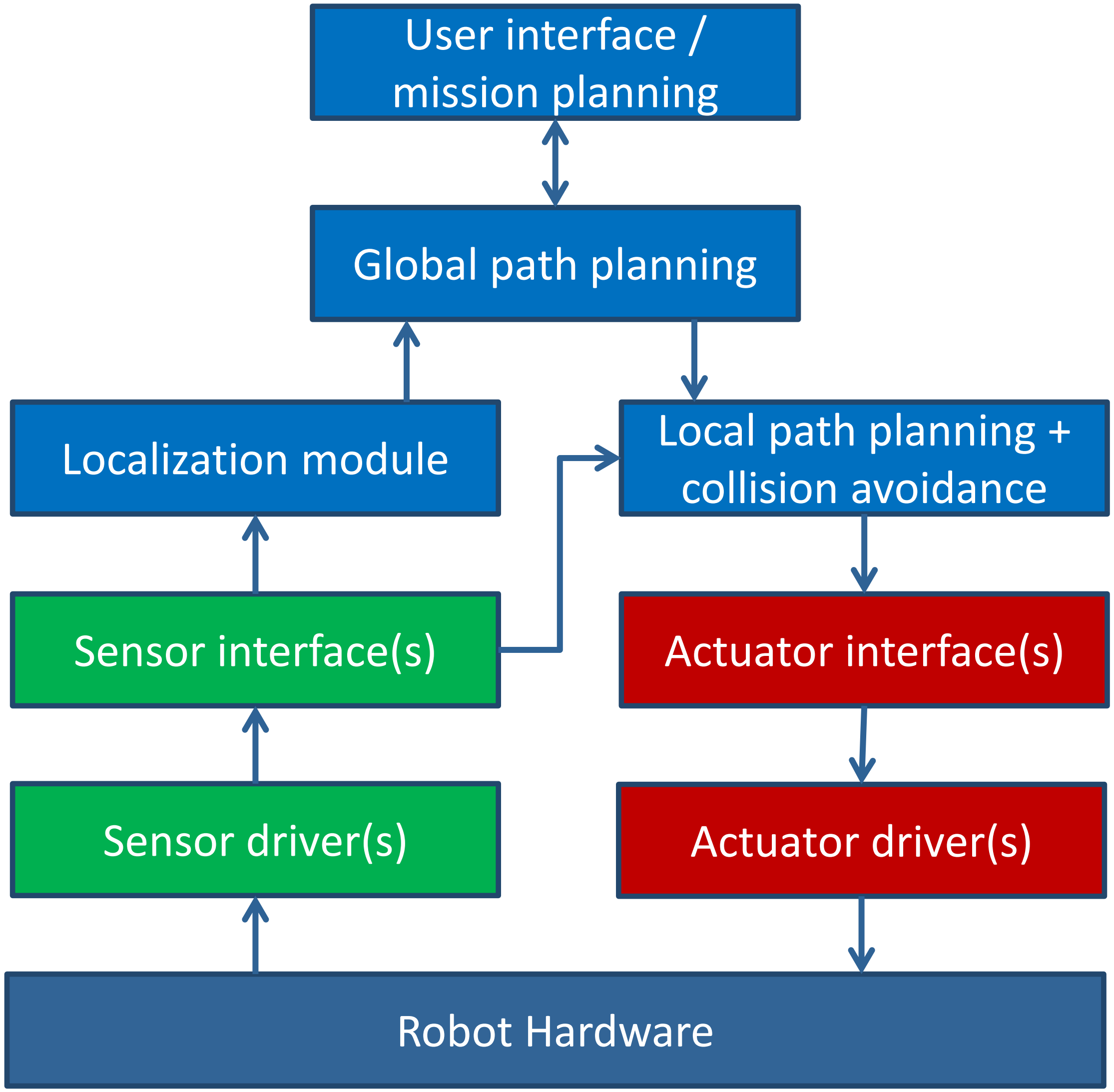
Best Practices for Robot Architectures

- Modular
- Robust
- De-centralized
- Facilitate software re-use
- Hardware and software abstraction
- Provide introspection
- Data logging and playback
- Easy to learn and to extend

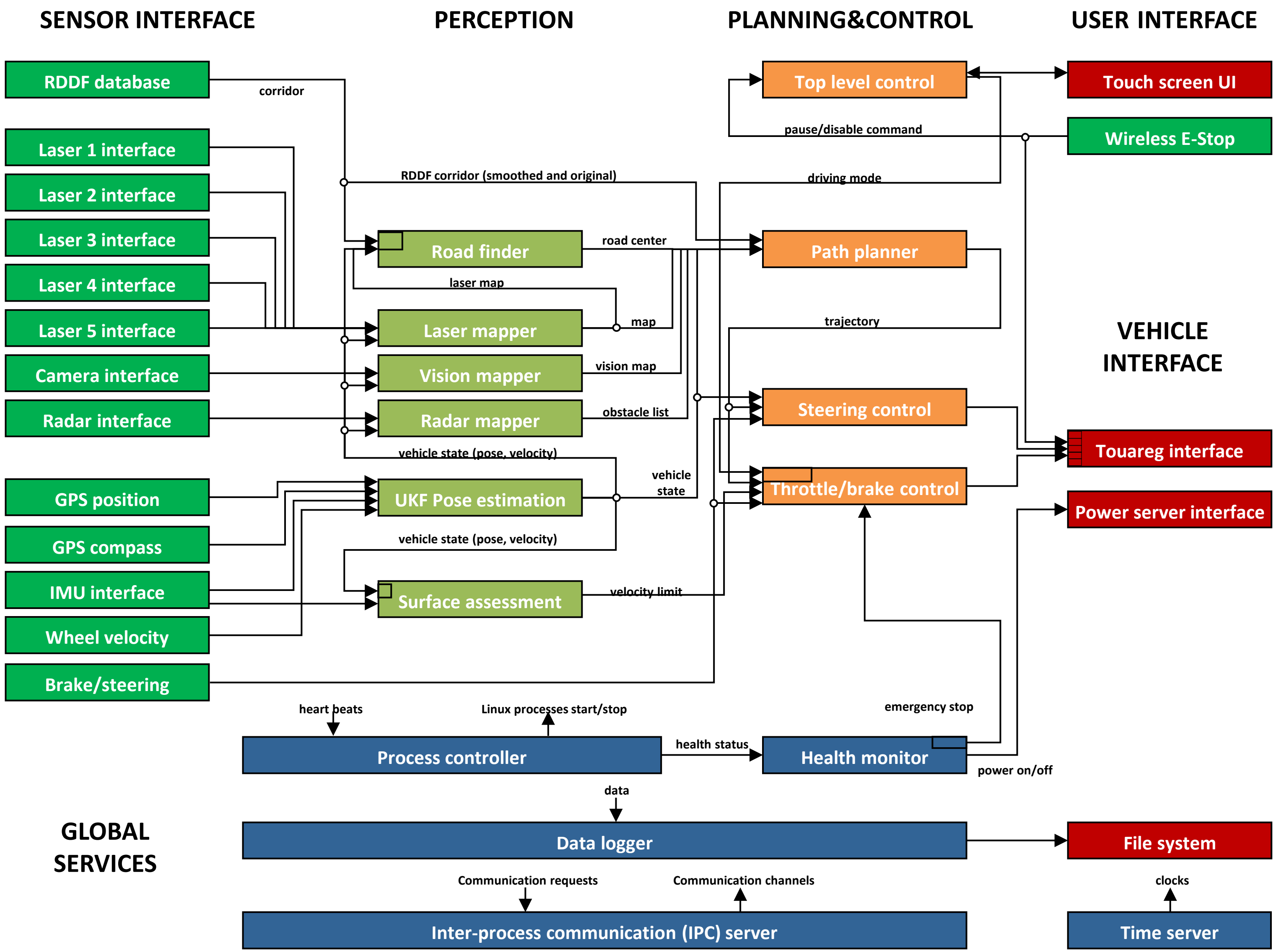
Robotic Middleware

- Provides infrastructure
- Communication between modules
- Data logging facilities
- Tools for visualization
- Several systems available
  - Open-source: ROS (Robot Operating System), Player/Stage, CARMEN, YARP, OROCOS
  - Closed-source: Microsoft Robotics Studio

Example Architecture for Navigation

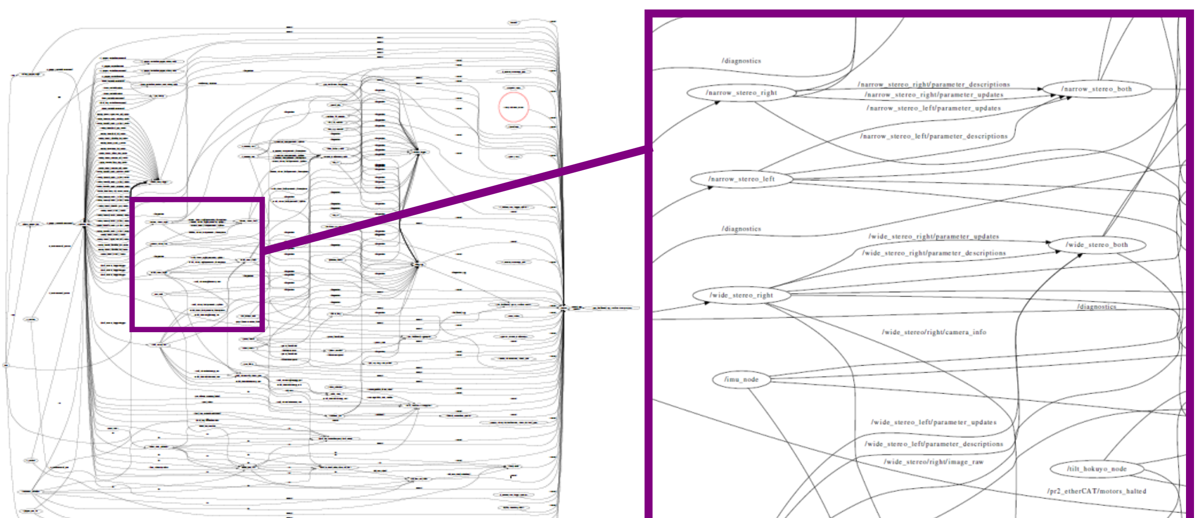


Stanley's Software Architecture



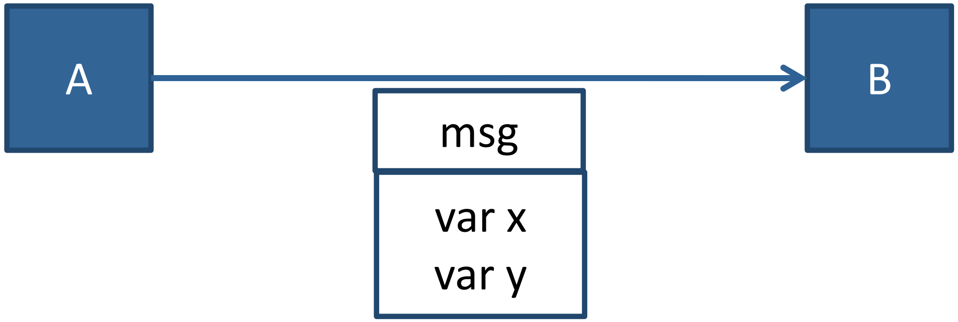
PR2 Software Architecture

- Two 7-DOF arms, grippers, torso, 2-DOF head
- 7 cameras, 2 laser scanners
- Two 8-core CPUs, 3 network switches
- 73 nodes, 328 message topics, 174 services

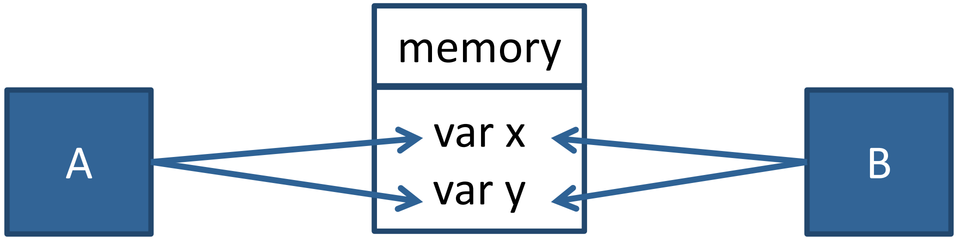


Communication Paradigms

- Message-based communication



- Direct (shared) memory access



Forms of Communication

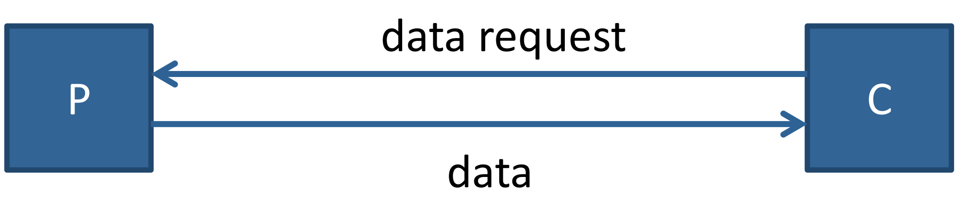
- Push
- Pull
- Publisher/subscriber
- Publish to blackboard
- Remote procedure calls / service calls
- Preemptive tasks / actions

Push

- Broadcast
- One-way communication
- Send as the information is generated by the producer P

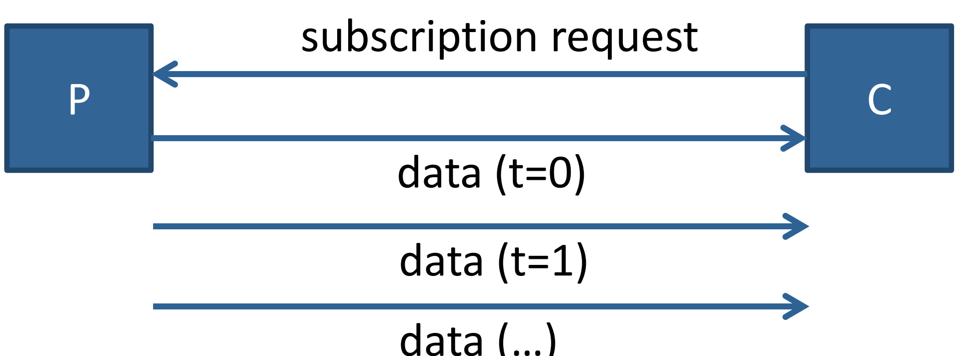
Pull

- Data is delivered upon request by the consumer C (e.g., a map of the building)
- Useful if the consumer C controls the process and the data is not required (or available) at high frequency



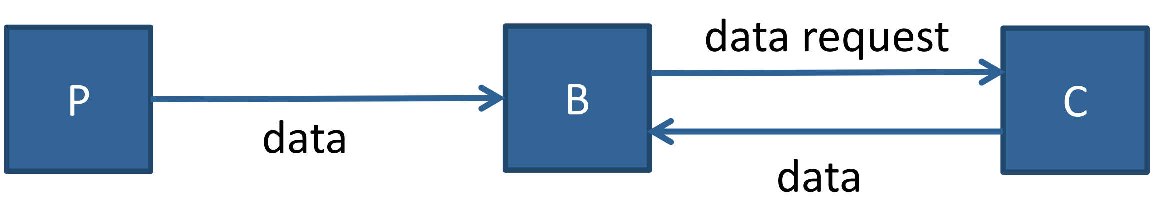
Publisher/Subscriber

- The consumer C requests a subscription for the data by the producer P (e.g., a camera or GPS)
- The producer P sends the subscribed data as it is generated to C
- Data generated according to a trigger (e.g., sensor data, computations, other messages, …)



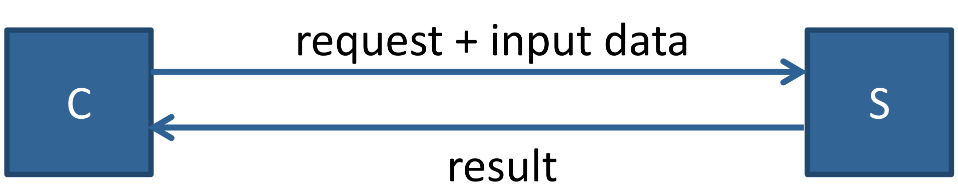
Publish to Blackboard

- The producer P sends data to the blackboard (e.g., parameter server)
- A consumer C pull data from the blackboard B
- Only the last instance of data is stored in the blackboard B



Service Calls

- The client C sends a request to the server S
- The server returns the result
- The client waits for the result (synchronous communication)
- Also called: Remote Procedure Call



Actions (Preemptive Tasks)

- The client requests the execution of an enduring action (e.g., navigate to a goal location)
- The server executes this action and sends continuously status updates
- Task execution may be canceled from both sides (e.g., timeout, new navigation goal,…)

Robot Operating System (ROS)

- We will use ROS in the lab course
- http://www.ros.org/
- Installation instructions, tutorials, docs

Concepts in ROS

- Nodes: programs that communicate with each other
- Messages: data structure (e.g., “Image”)
- Topics: typed message channels to which nodes can publish/subscribe (e.g., “/camera1/image_color”)
- Parameters: stored in a blackboard

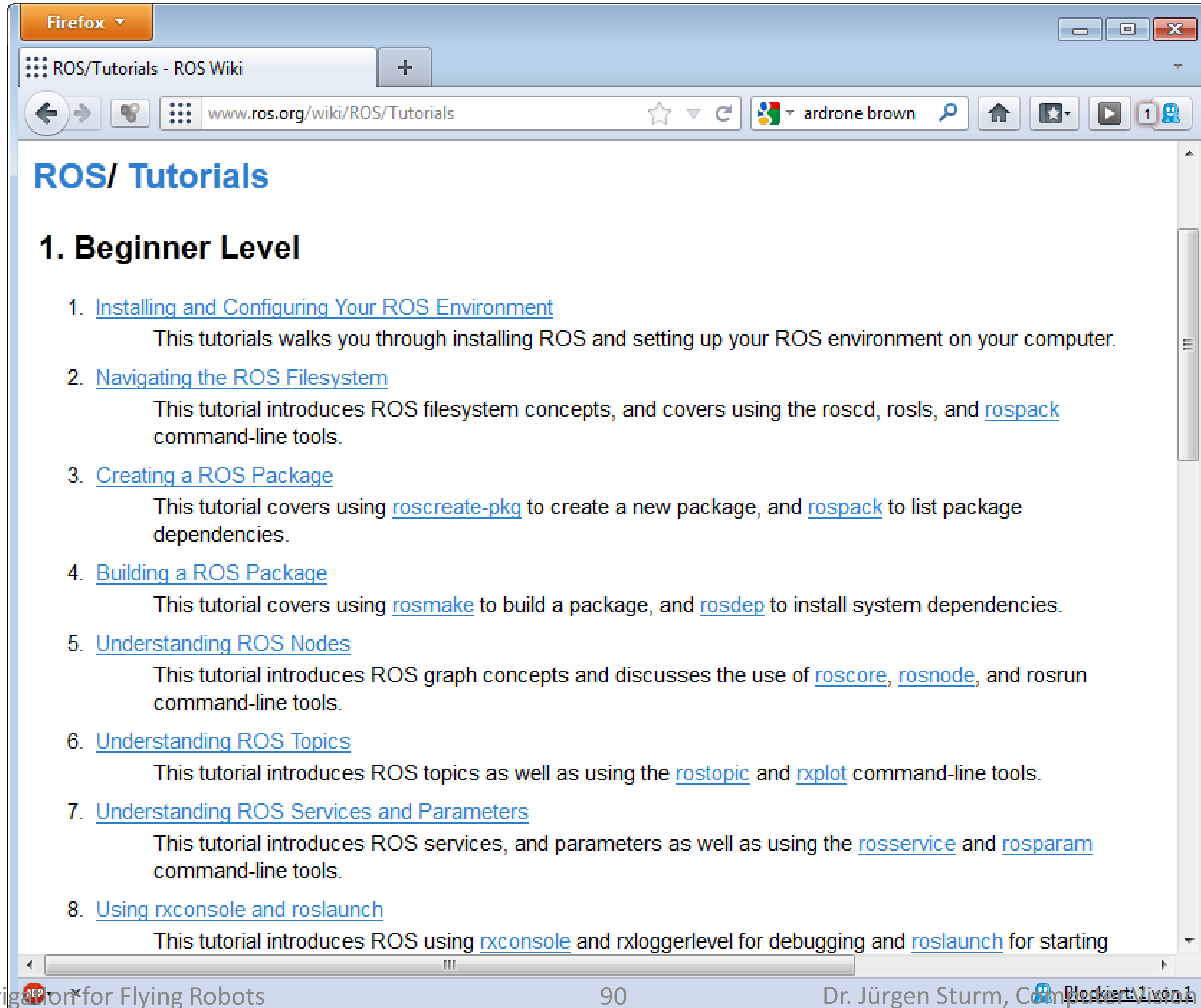
Software Management

- Package: atomic unit of building, contains one or more nodes and/or message definitions
- Stack: atomic unit of releasing, contains several packages with a common theme
- Repository: contains several stacks, typically one repository per institution

Useful Tools

- roscreate-pkg
- rosmake
- roscore
- rosnode list/info
- rostopic list/echo
- rosbag record/play
- rosrun

Tutorials in ROS



ROS/ Tutorials

1. Beginner Level

1. Installing and Configuring Your ROS Environment
   This tutorials walks you through installing ROS and setting up your ROS environment on your computer.
2. Navigating the ROS Filesystem
   This tutorial introduces ROS filesystem concepts, and covers using the roscd, rosls, and rospack command-line tools.
3. Creating a ROS Package
   This tutorial covers using roscreate-pkg to create a new package, and rospack to list package dependencies.
4. Building a ROS Package
   This tutorial covers using rosmake to build a package, and rosdep to install system dependencies.
5. Understanding ROS Nodes
   This tutorial introduces ROS graph concepts and discusses the use of roscore, rosnode, and rosrun command-line tools.
6. Understanding ROS Topics
   This tutorial introduces ROS topics as well as using the rostopic and rxplot command-line tools.
7. Understanding ROS Services and Parameters
   This tutorial introduces ROS services, and parameters as well as using the rosservice and rosparam command-line tools.
8. Using rxconsole and roslaunch
   This tutorial introduces ROS using rxconsole and rxloggerlevel for debugging and roslaunch for starting

Summary

- History of mobile robotics
- Brief intro on quadrocopters
- Paradigms in robotics
- Architectures and middleware

Questions?

- See you next week!