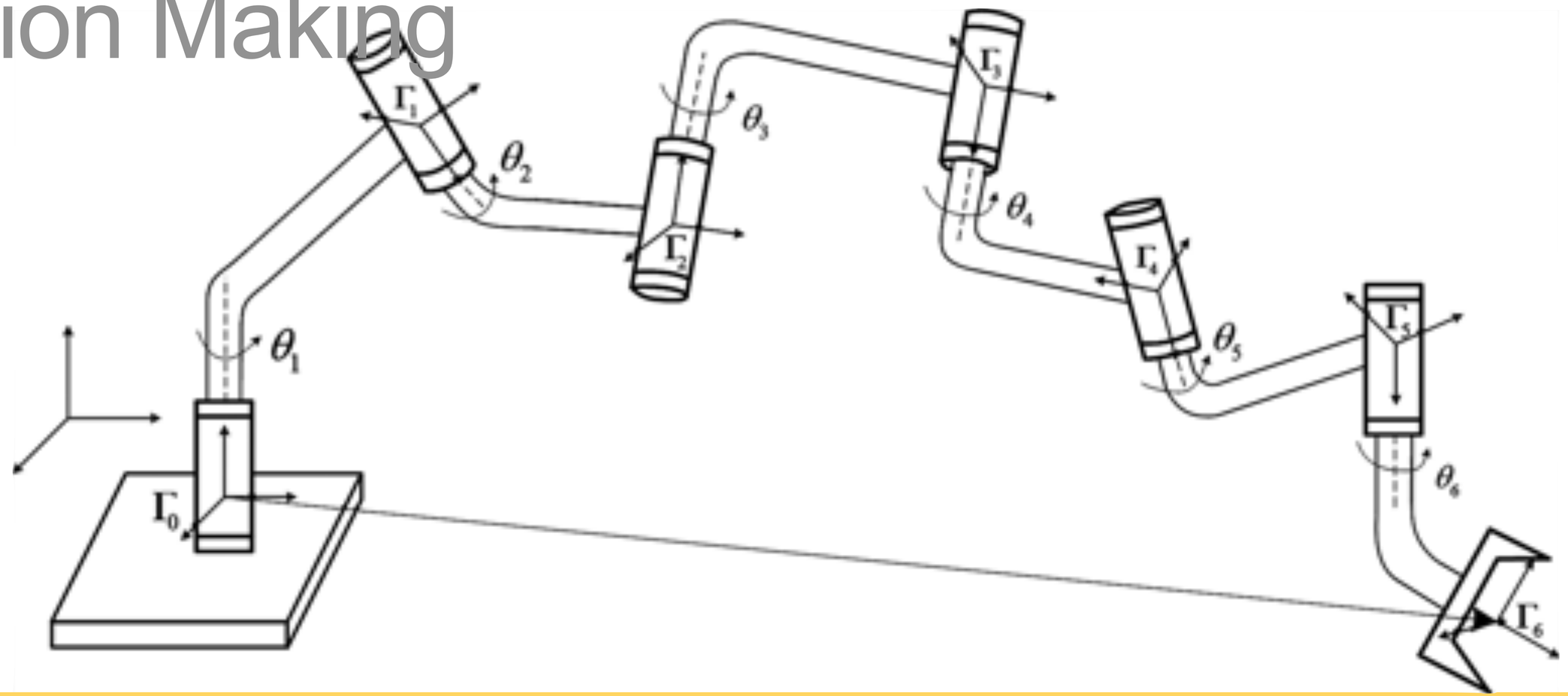
Lecture 05
Manipulation - I
Forward Kinematics
& Decision Making



Course Logistics

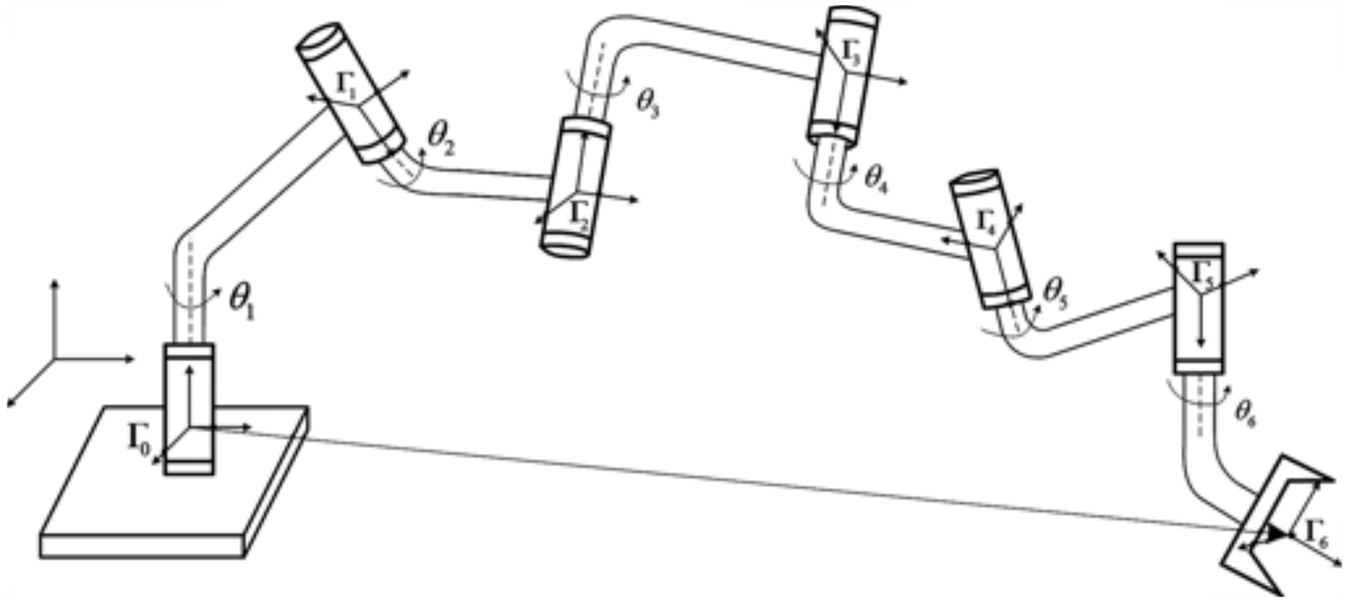
- **Quiz 3 was posted today and was due before the lecture.**
- Project 0 was posted on 09/13 and will be due **09/25 (extended)**.
- Autograder will be made available for you to test and submit your code.
  - **CSE-IT is still working on it. Will be made available soon.**
- Project 1 will be posted on 09/20 **(today)** and will be due 10/02.

Robot Kinematics

Goal: Given the structure of a robot arm, compute

– **Forward kinematics**: infer the pose of the end-effector, given the state of each joint.

– **Inverse kinematics**: infer the joint states to reach a desired end-effector pose.



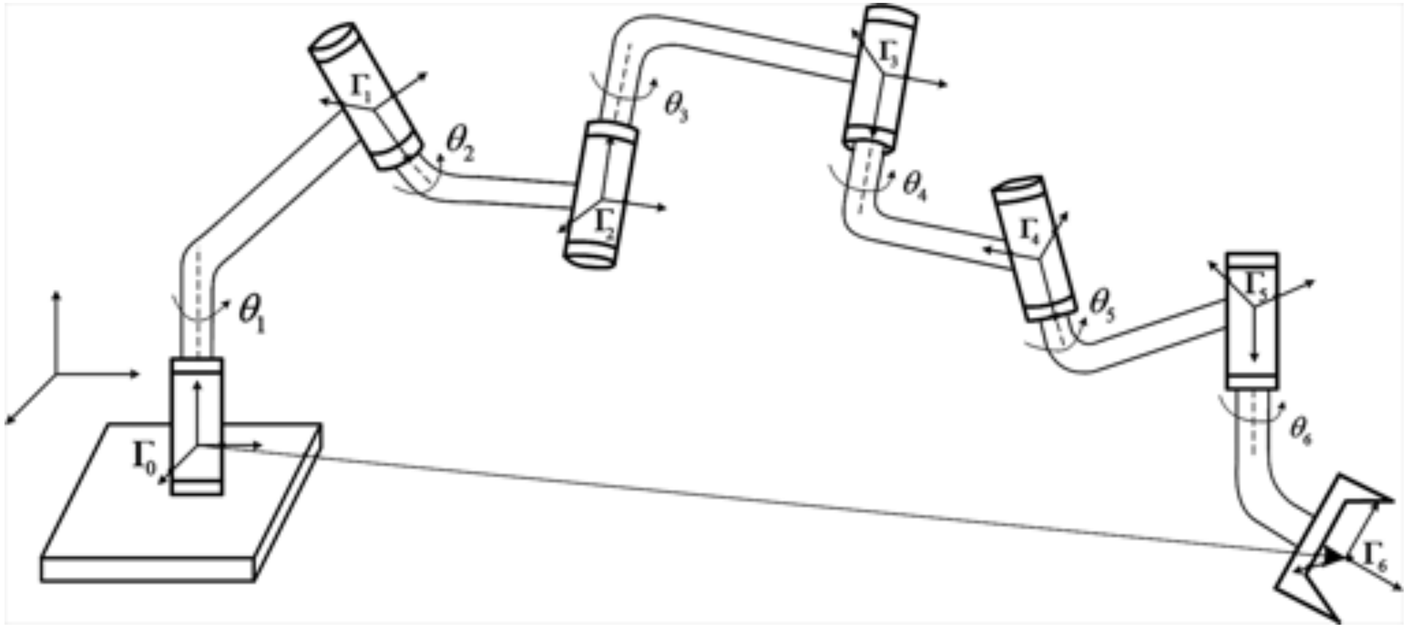
Robot Kinematics

– **Forward kinematics**: infer the pose of the end-effector, given the state of each joint.

Infer: pose of each joint and link in a common world workspace

Assuming as given the:

- robot's kinematic definition
- geometry of each link
- current state of all joints
  - zero configuration
  - add motor motion



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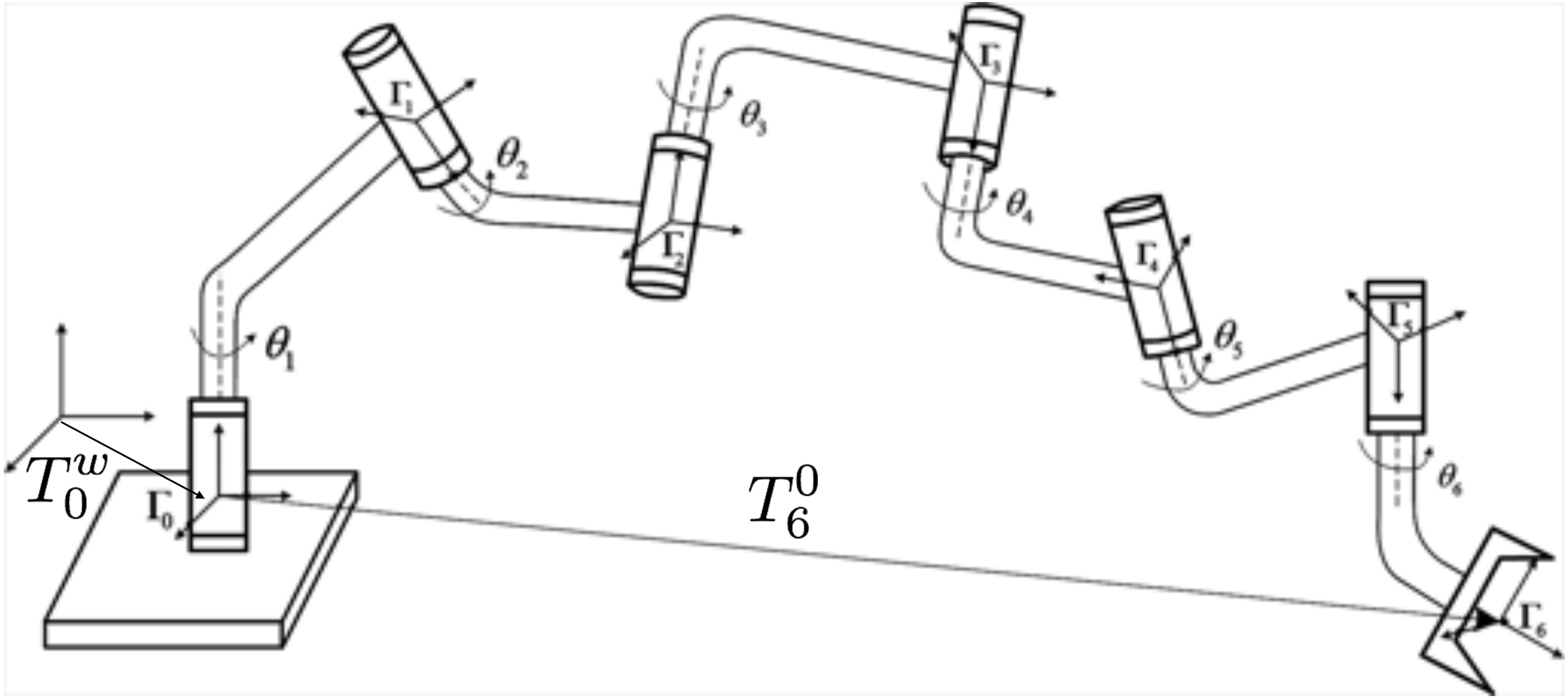
Forward kinematics: many-to-one mapping of robot configuration to reachable workspace endeffector poses



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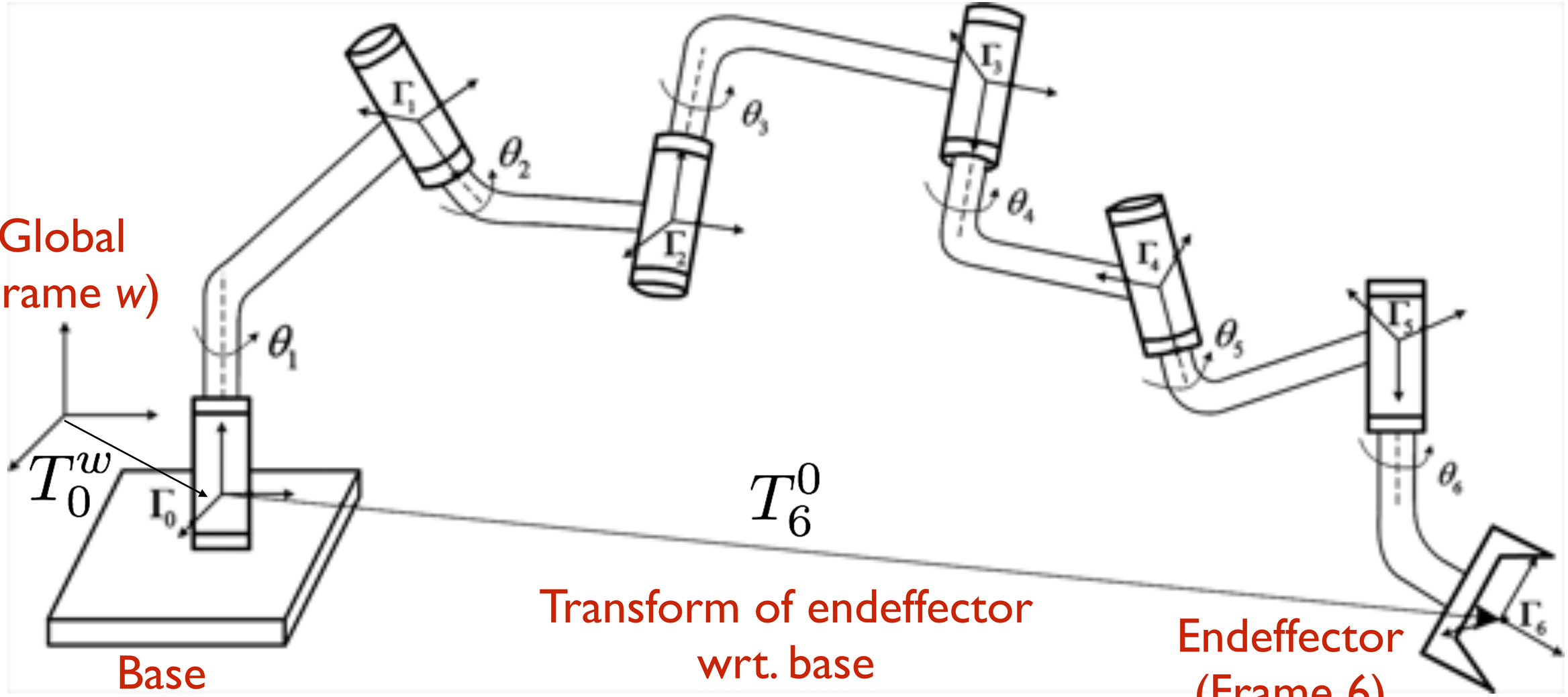
Forward kinematics: many-to-one mapping of robot configuration to reachable workspace endeffector poses



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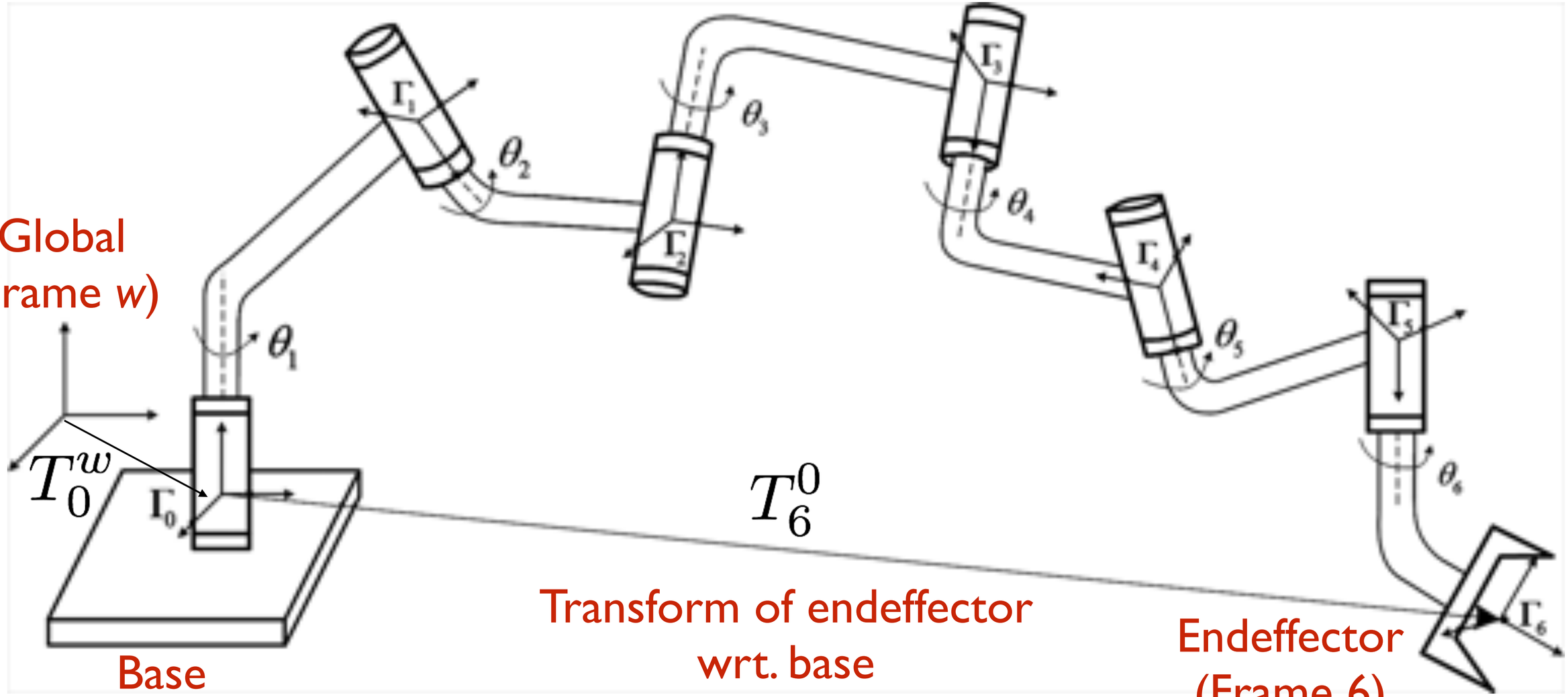
Workspace: 3D space defined in the global frame



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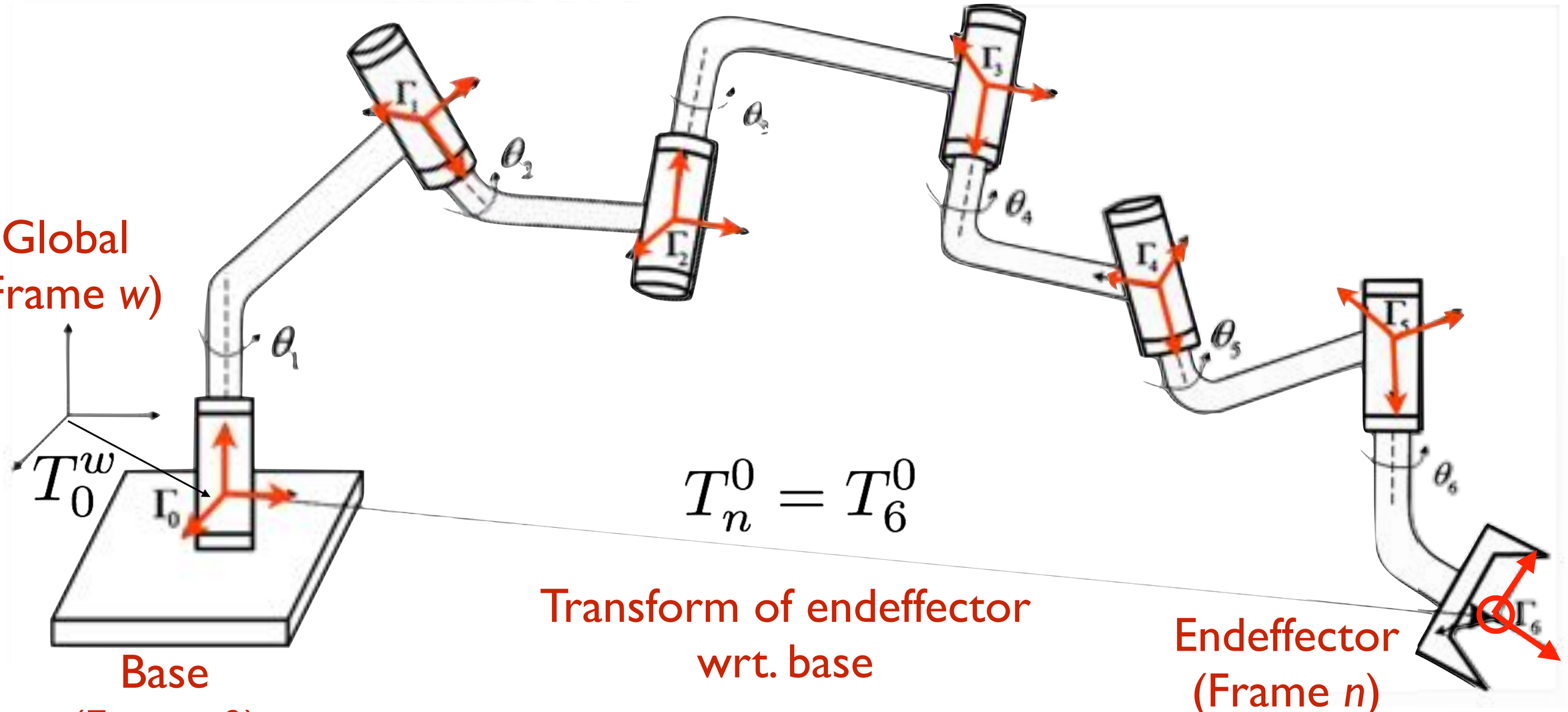
Kinematic chain: connects N+1 links together by N joints;
with a coordinate frame on each link



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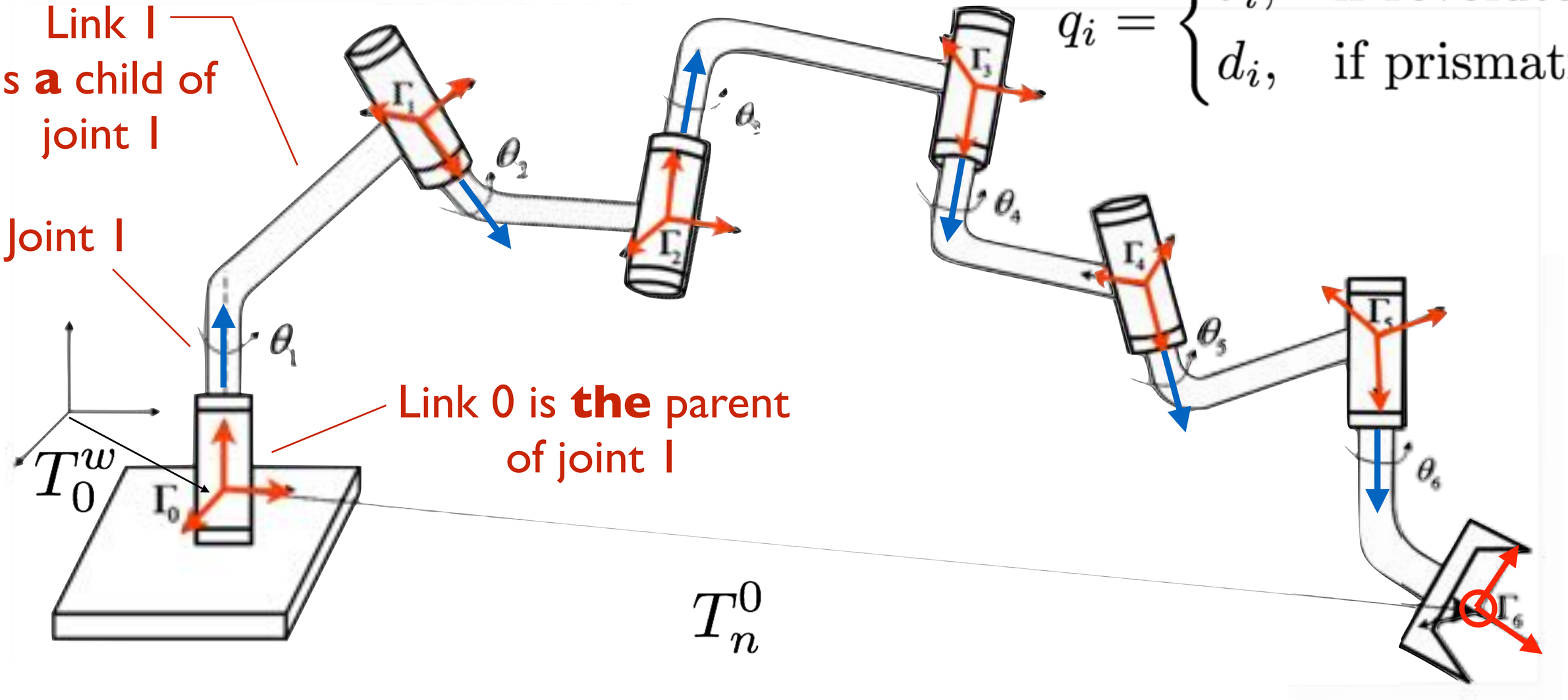
Joint (q_i): relates the motion of one link (the child link) wrt. another link (the parent)
joint motion only affects the child link

$$q_i = \begin{cases} \theta_i, & \text{if revolute} \\ d_i, & \text{if prismatic} \end{cases}$$



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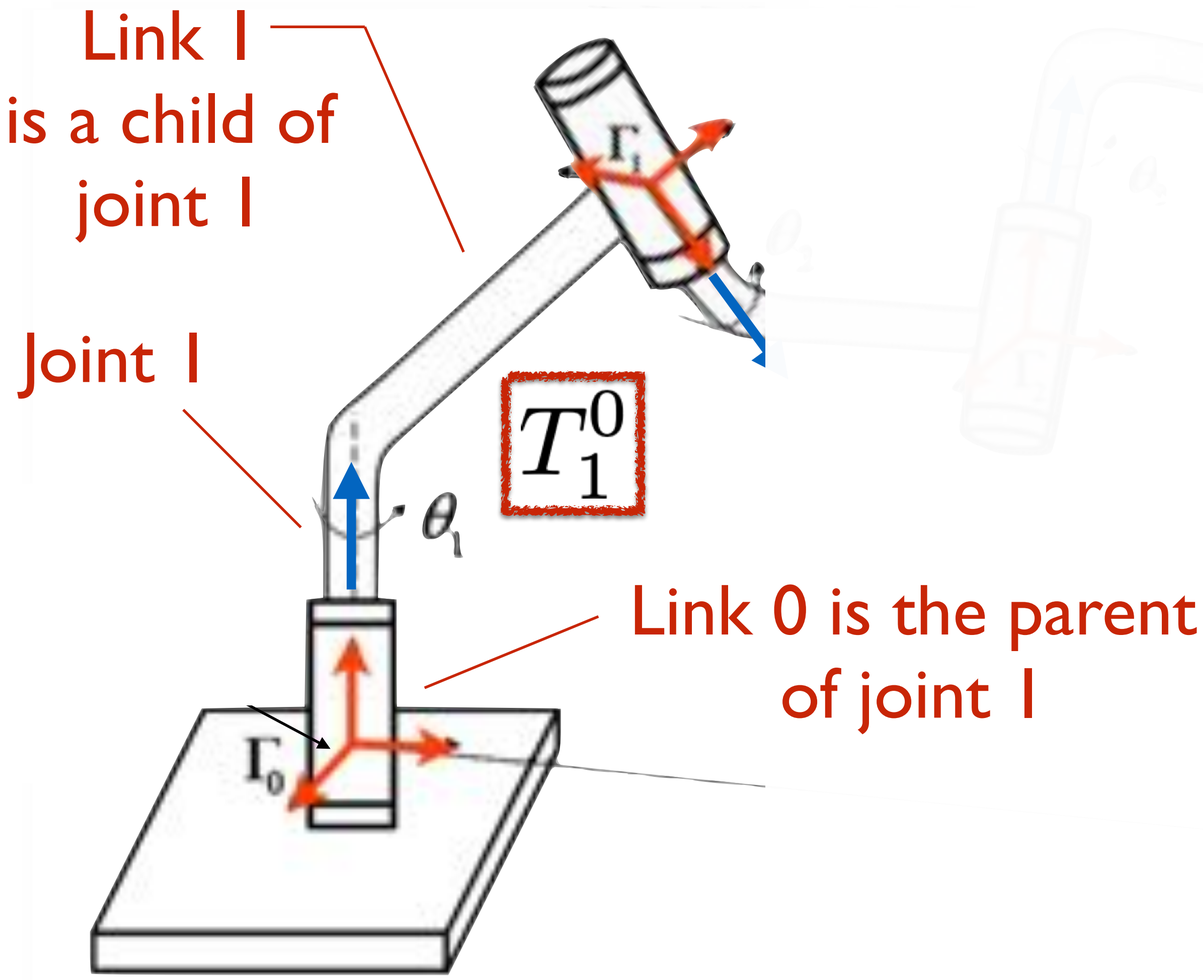
Joint (q_i): relates the motion of one link (the child link) wrt. another link (the parent)
joint motion only affects the child link, where its state



$$q_i = \begin{cases} \theta_i, & \text{if revolute} \\ d_i, & \text{if prismatic} \end{cases}$$

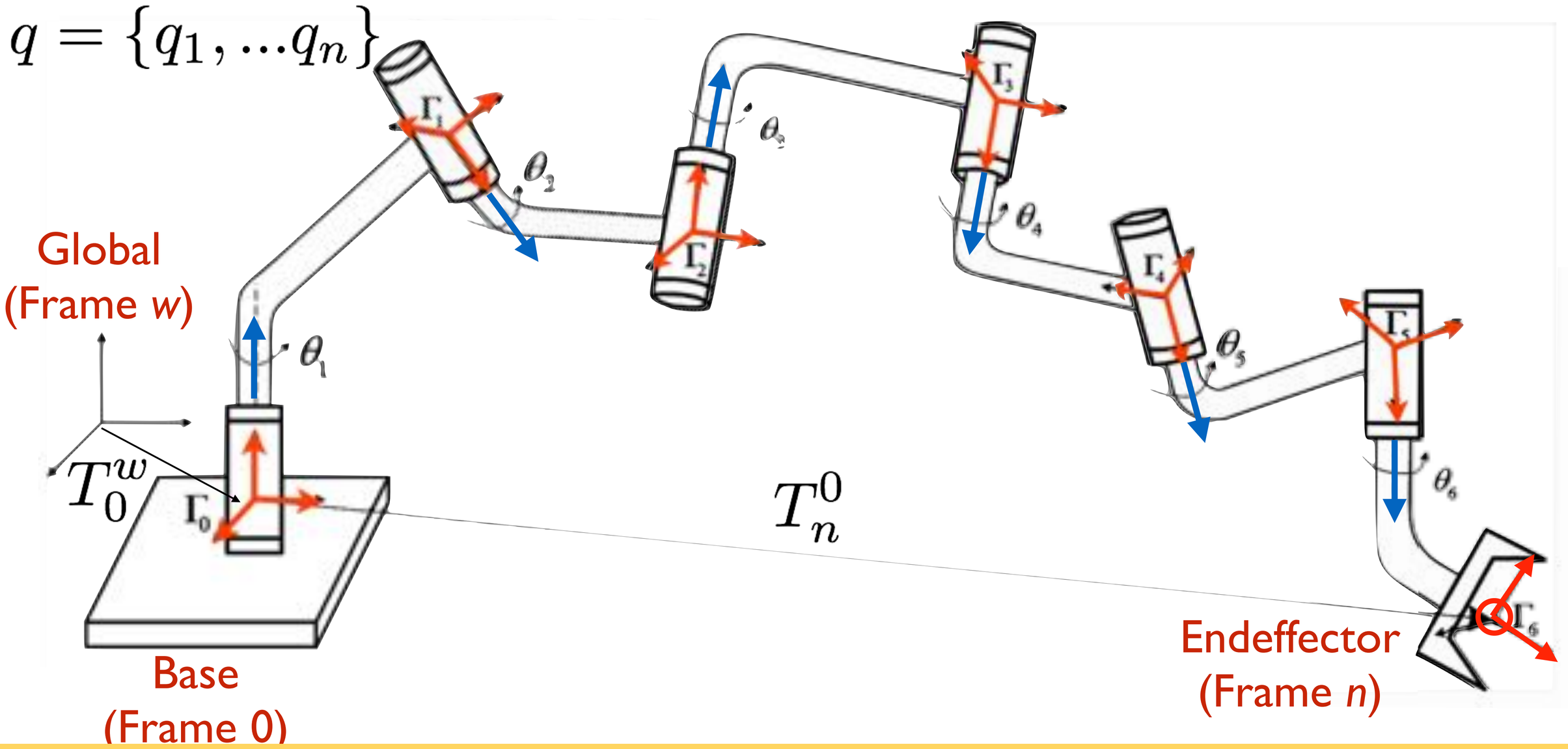
is used to express a *4*-by-*4* homogeneous transform $\boldsymbol{A_i(q_i)}$:

$$A_i = \begin{bmatrix} R_i^{i-1} & o^{i-1} \\ 0 & 1 \end{bmatrix}$$

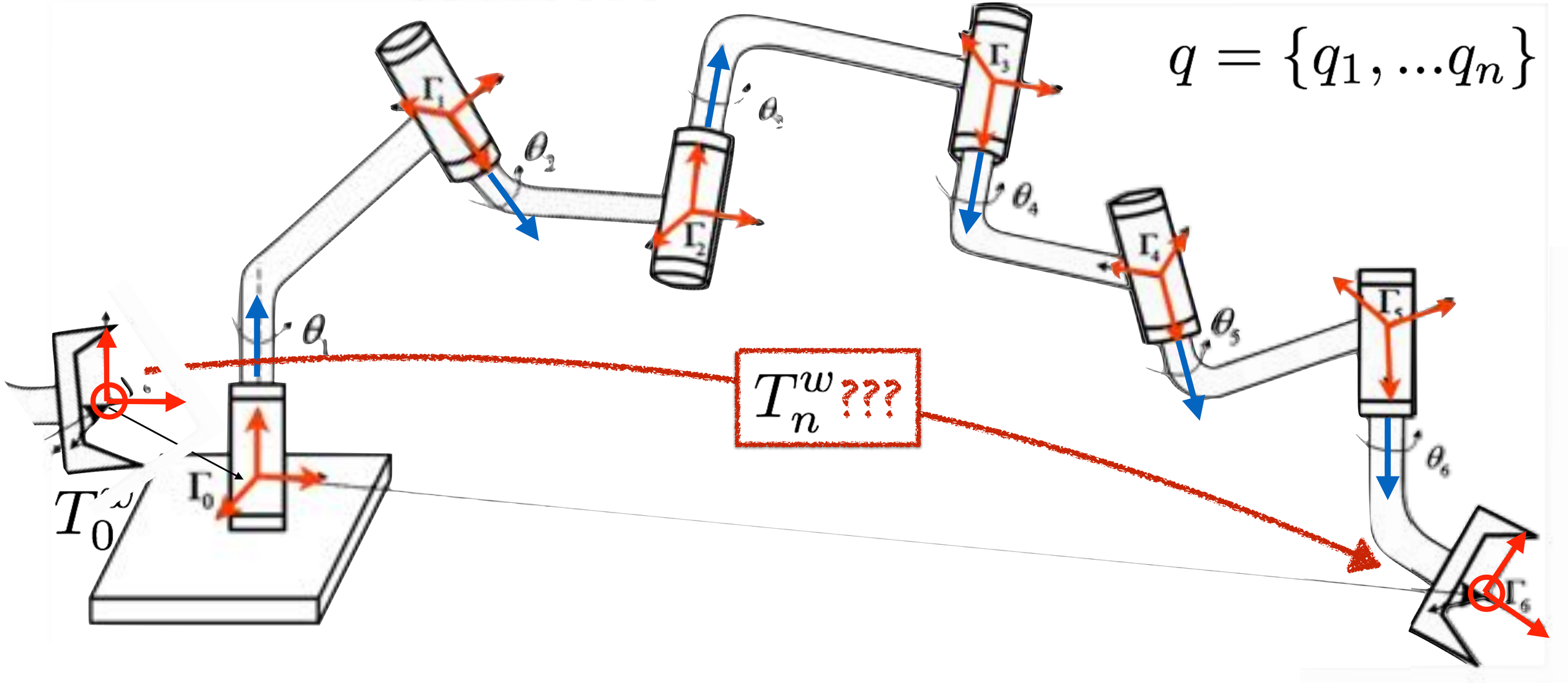
such that frames in a kinematic chain are related as by $\boldsymbol{T^i_j}$:

$$T_j^i = \begin{cases} A_{i+1} A_{i+2} \dots A_{j-1} A_j & \text{if } i < j \\ I & \text{if } i = j \\ (T_j^i)^{-1} & \text{if } j > i \end{cases}$$

Configuration (*q*): is the state of all joints in the kinematic chain
Configuration space: the space of all possible configurations



Forward kinematics restated: Given ***q***, *find* T^w_n;
T^w_n *transforms endeffector into workspace*



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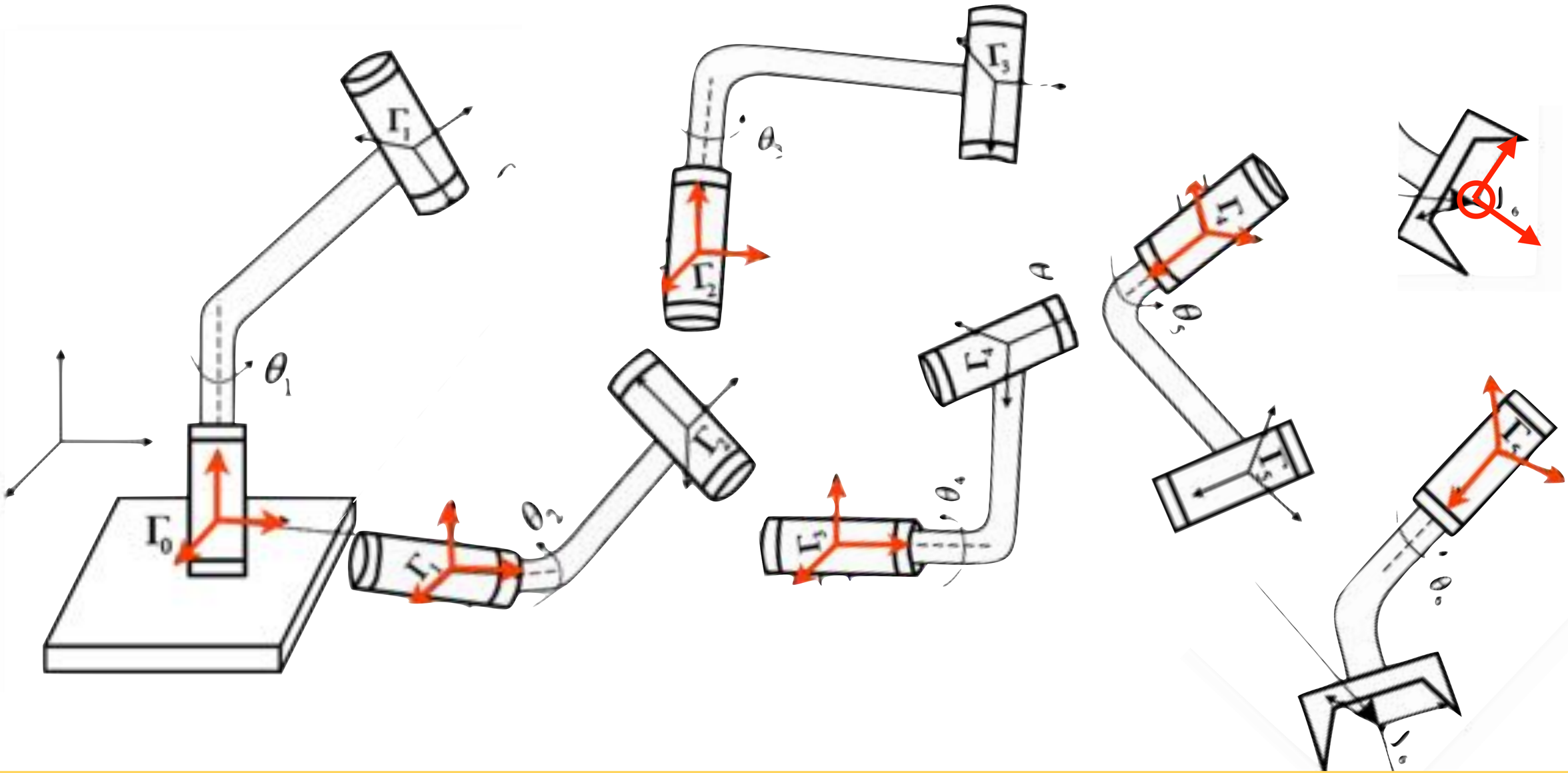
Problem: Every link considers itself to the center of the universe.
How do we properly pose link with respect to each other?



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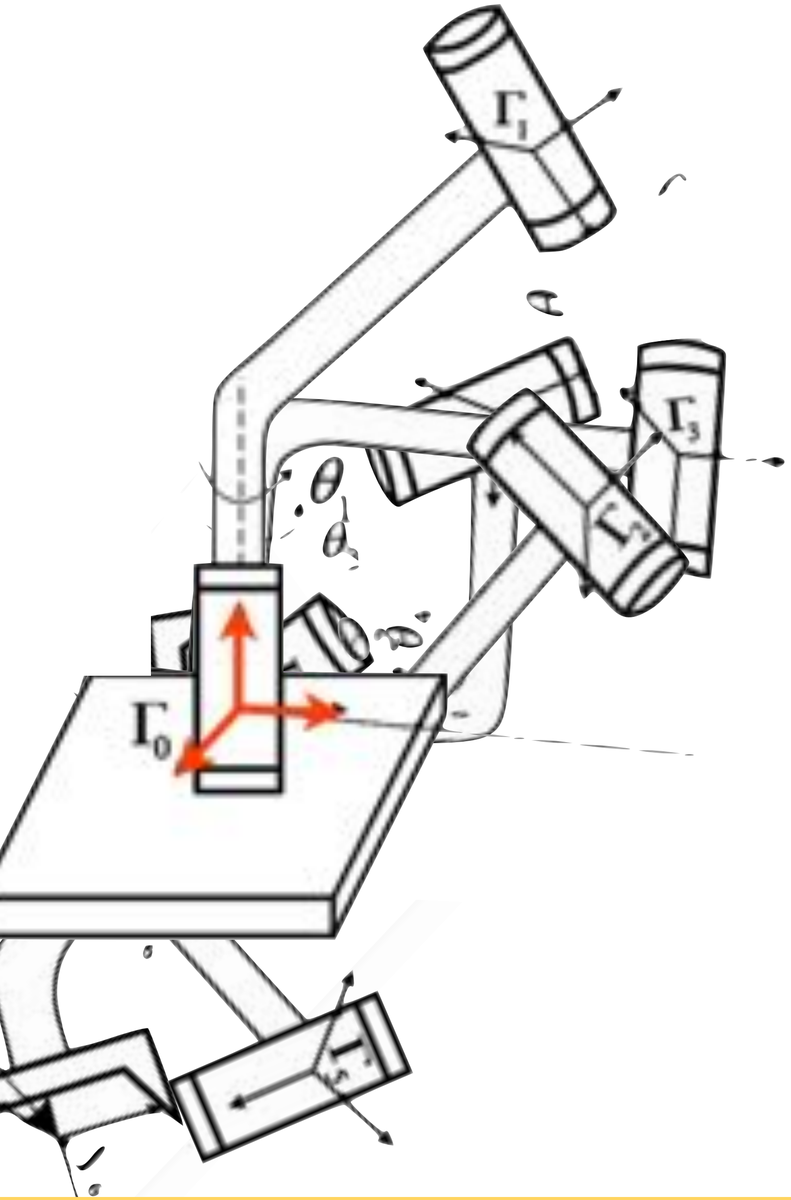
Approach: Consider all links to be aligned with the global origin …



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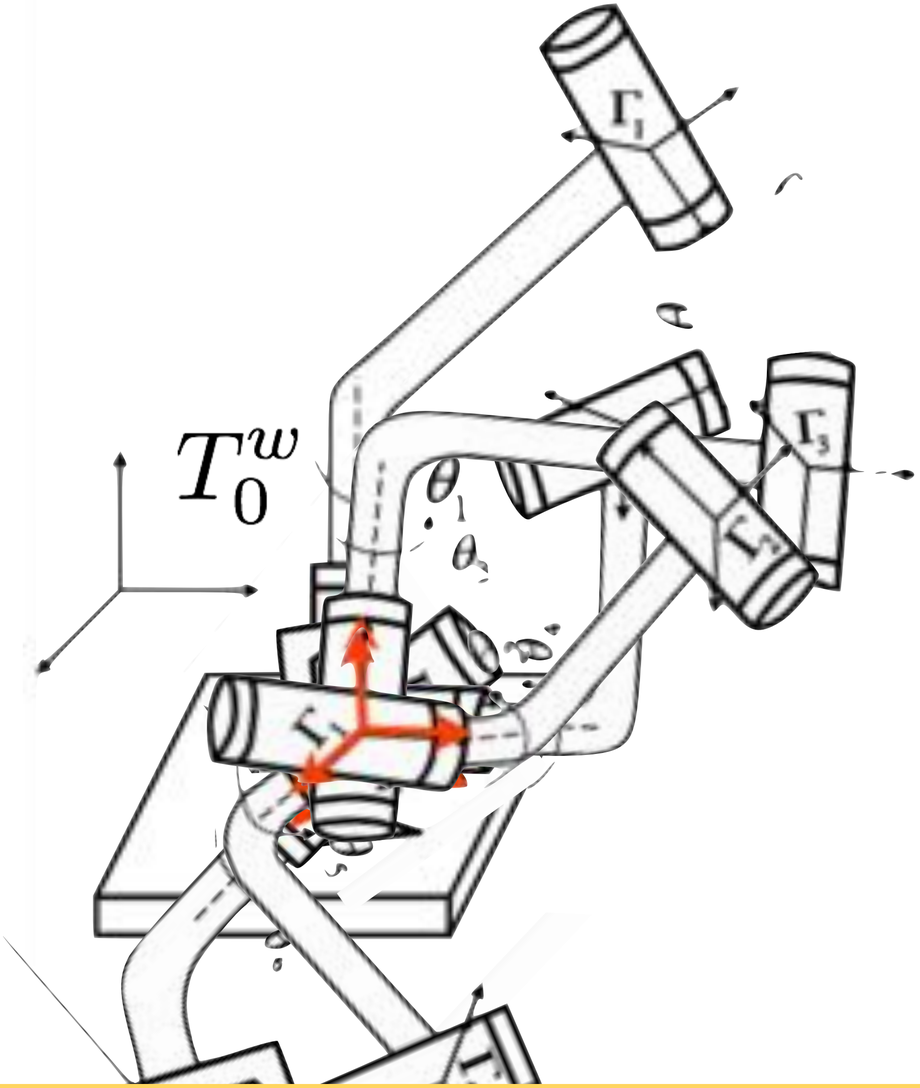
Approach: transform along kinematic chain bringing descendants along; each transform will consist of a rotation and a translation



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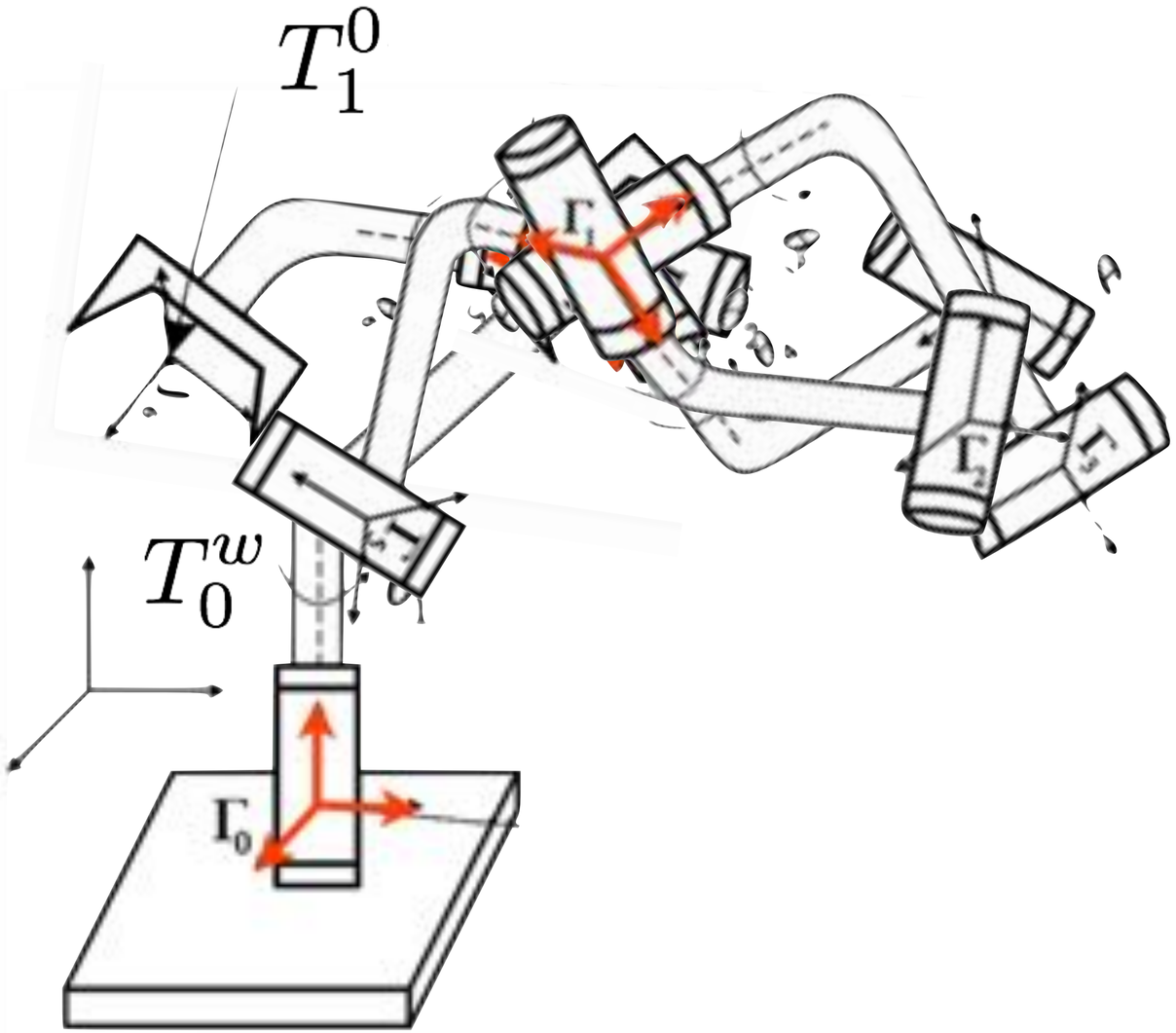

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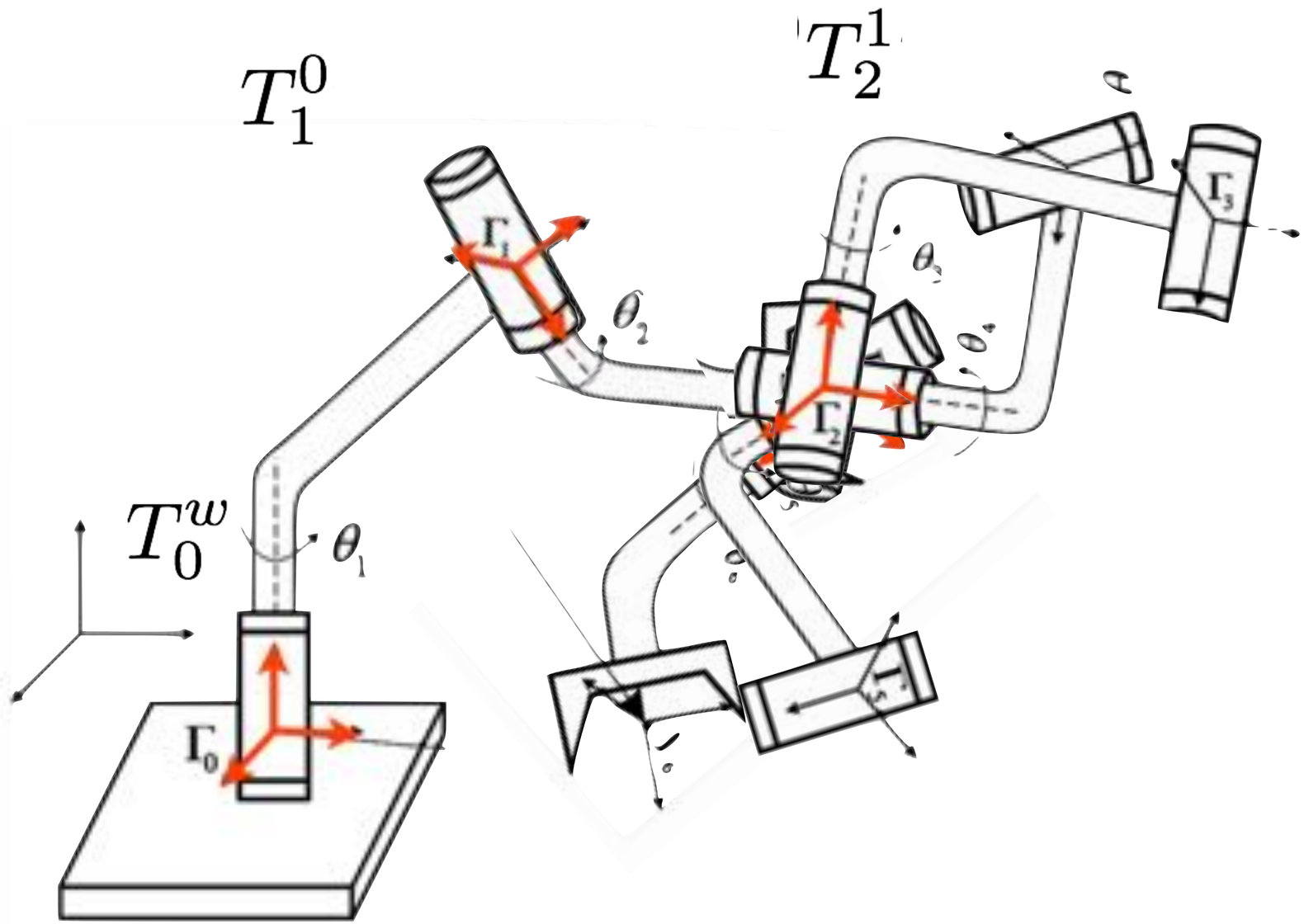

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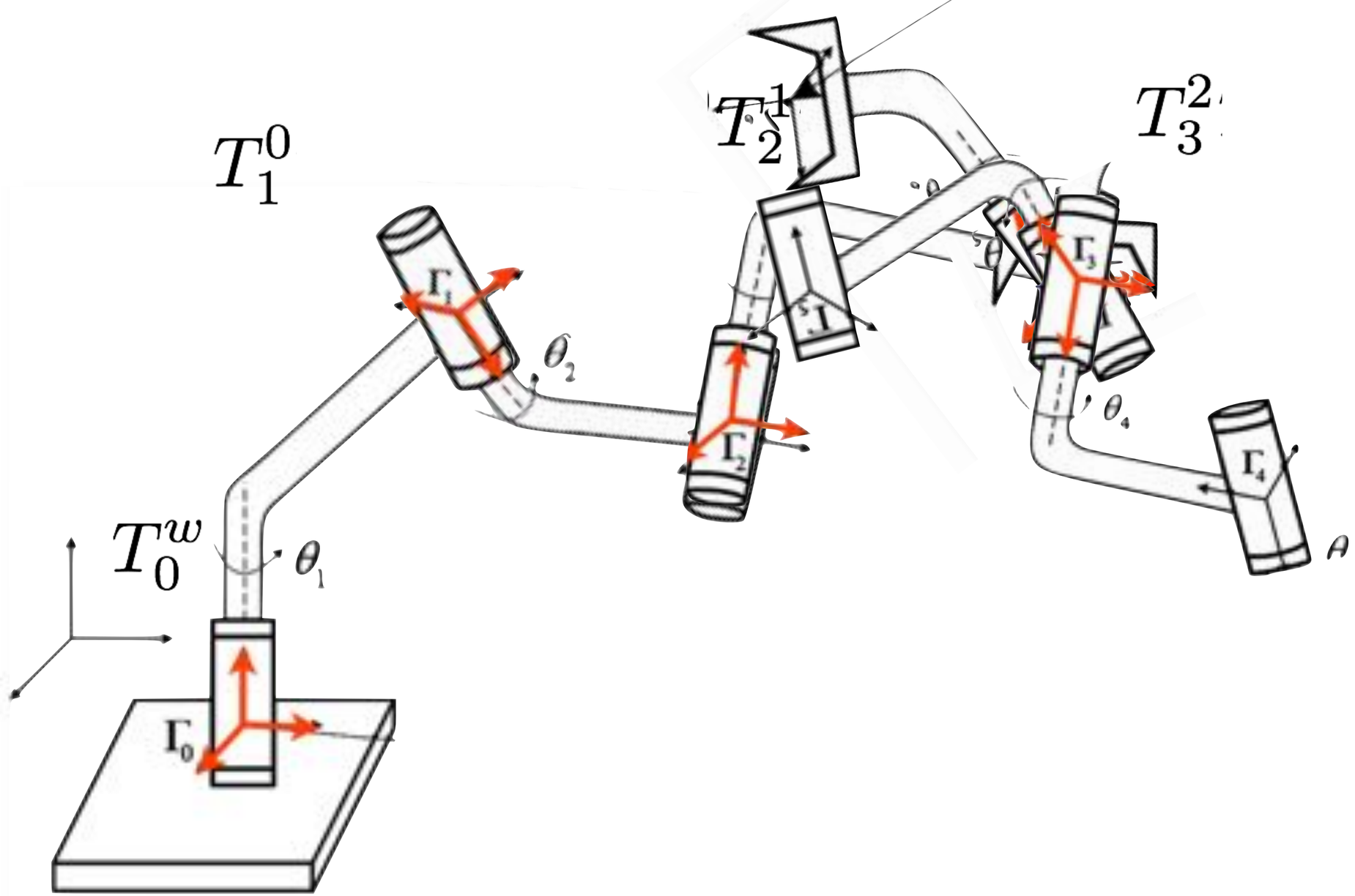

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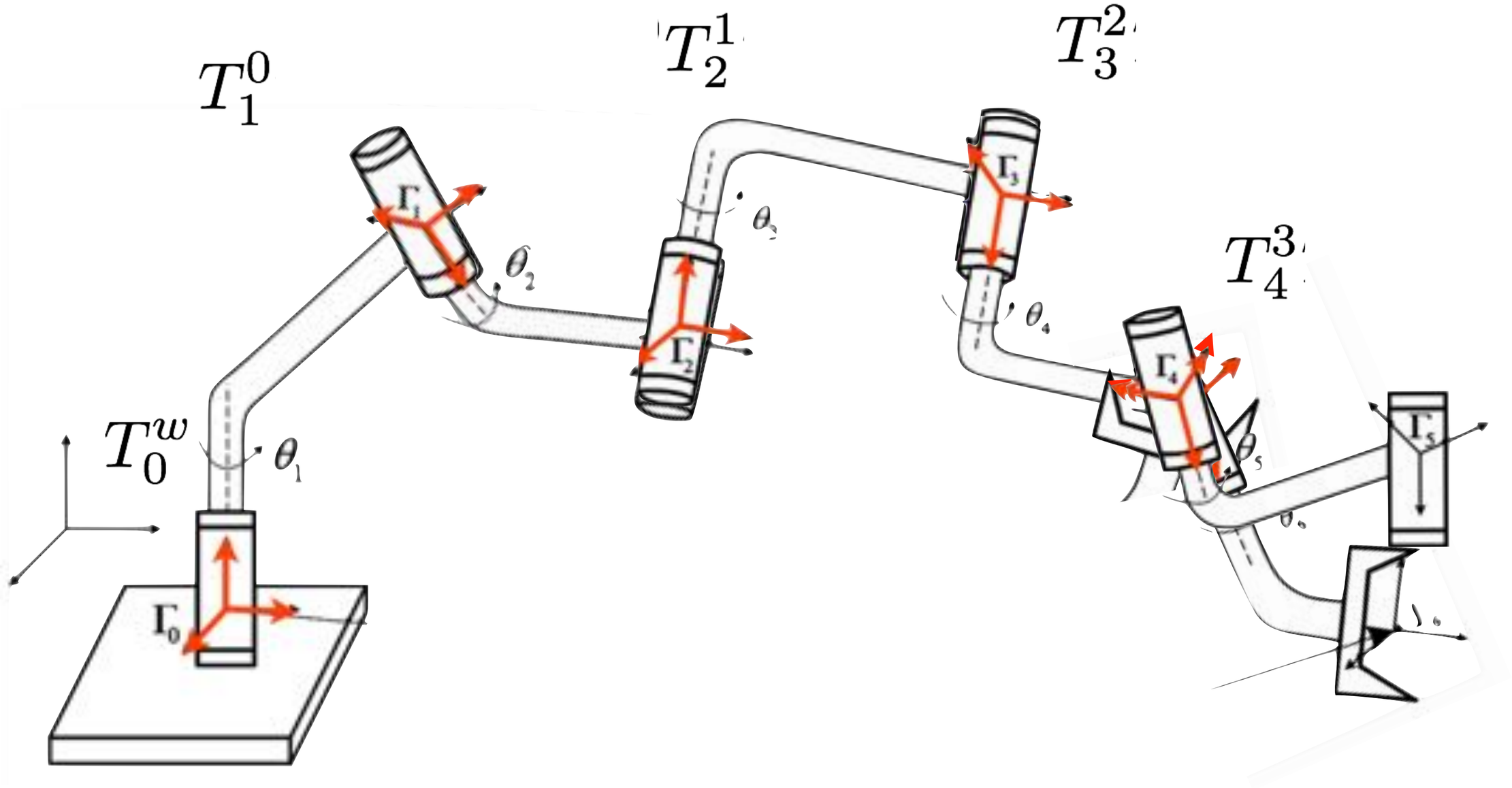

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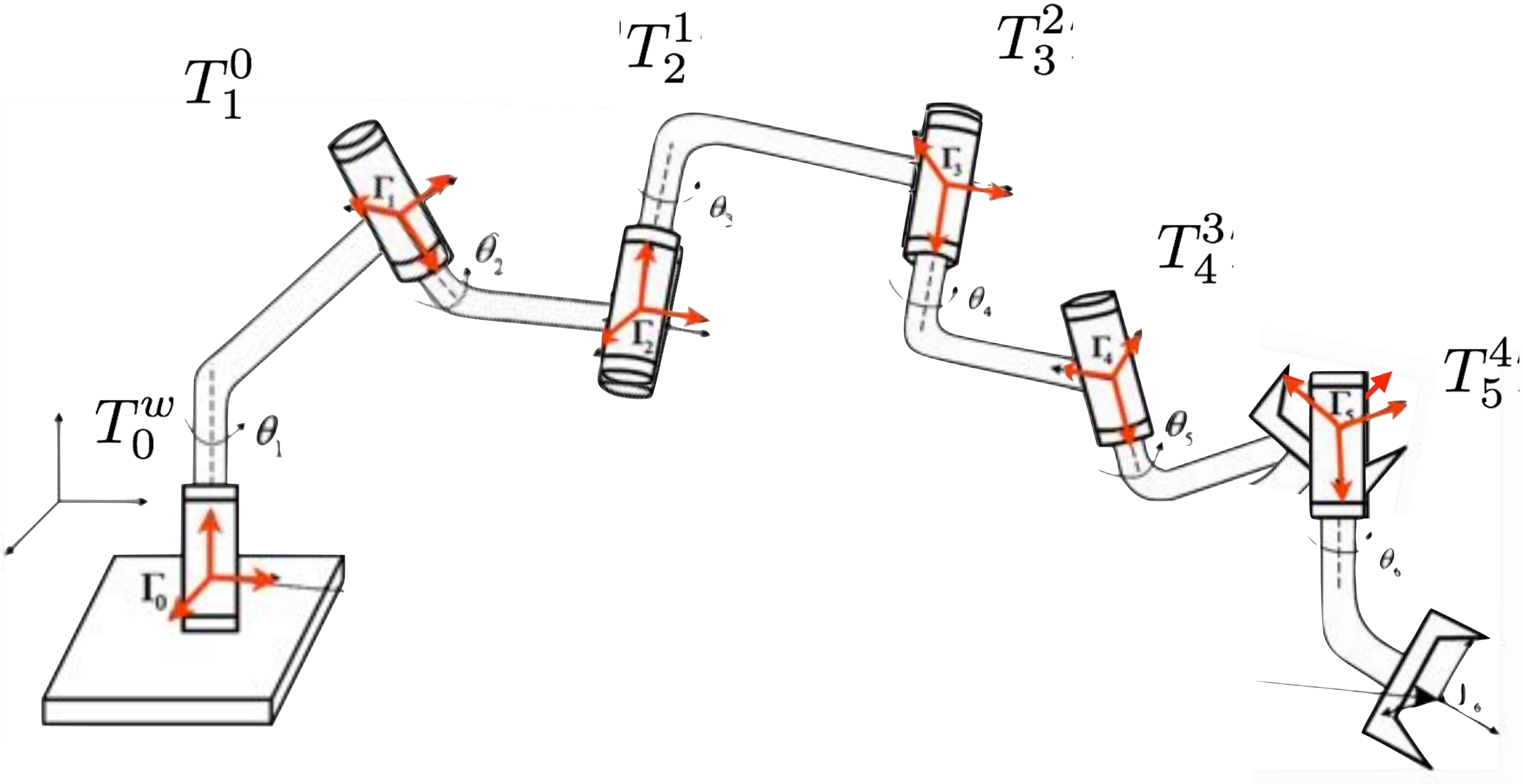

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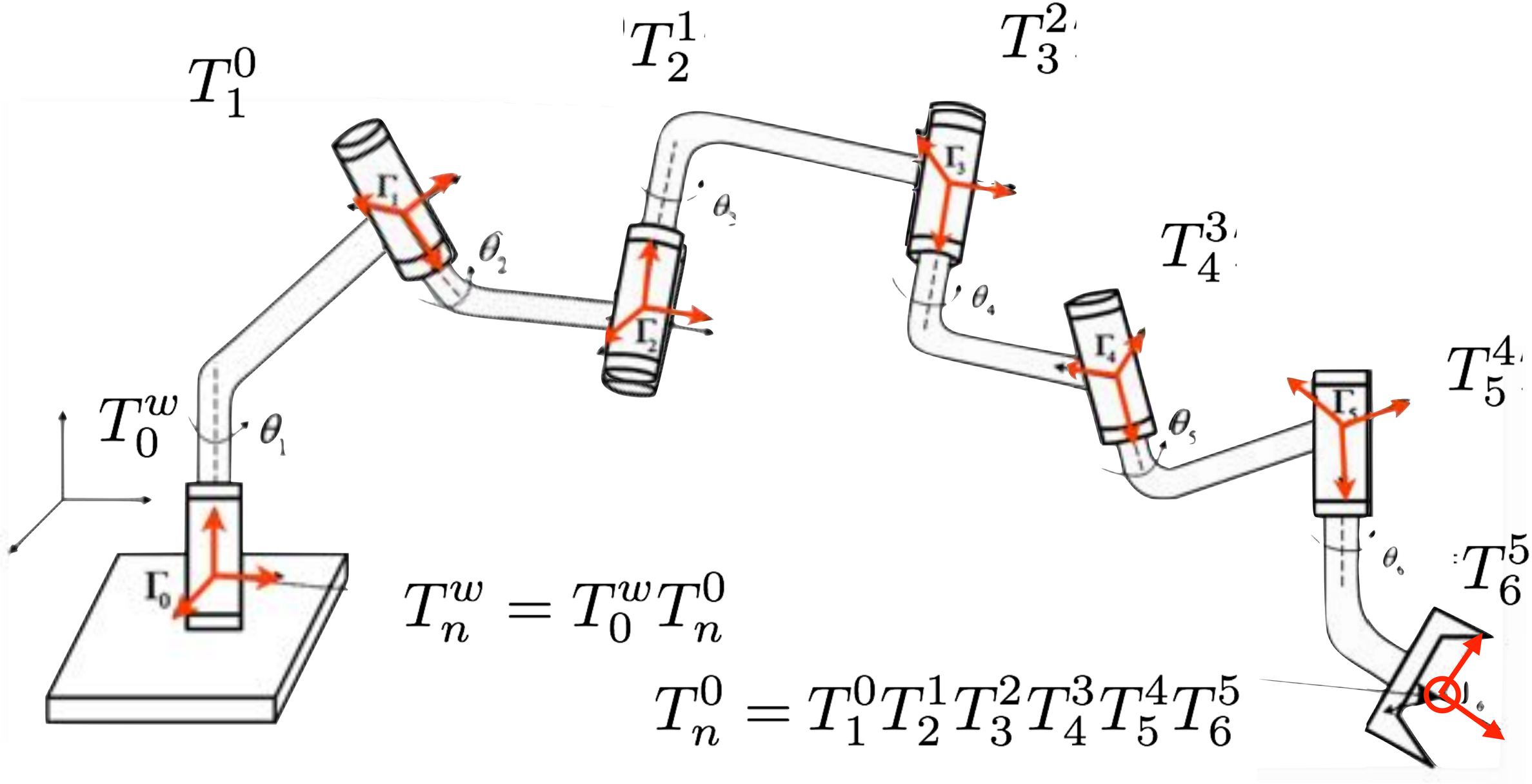

$$T_n^w = T_0^w T_n^0$$

$$T_n^0 = T_1^0 T_2^1 T_3^2 T_4^3 T_5^4 T_6^5$$

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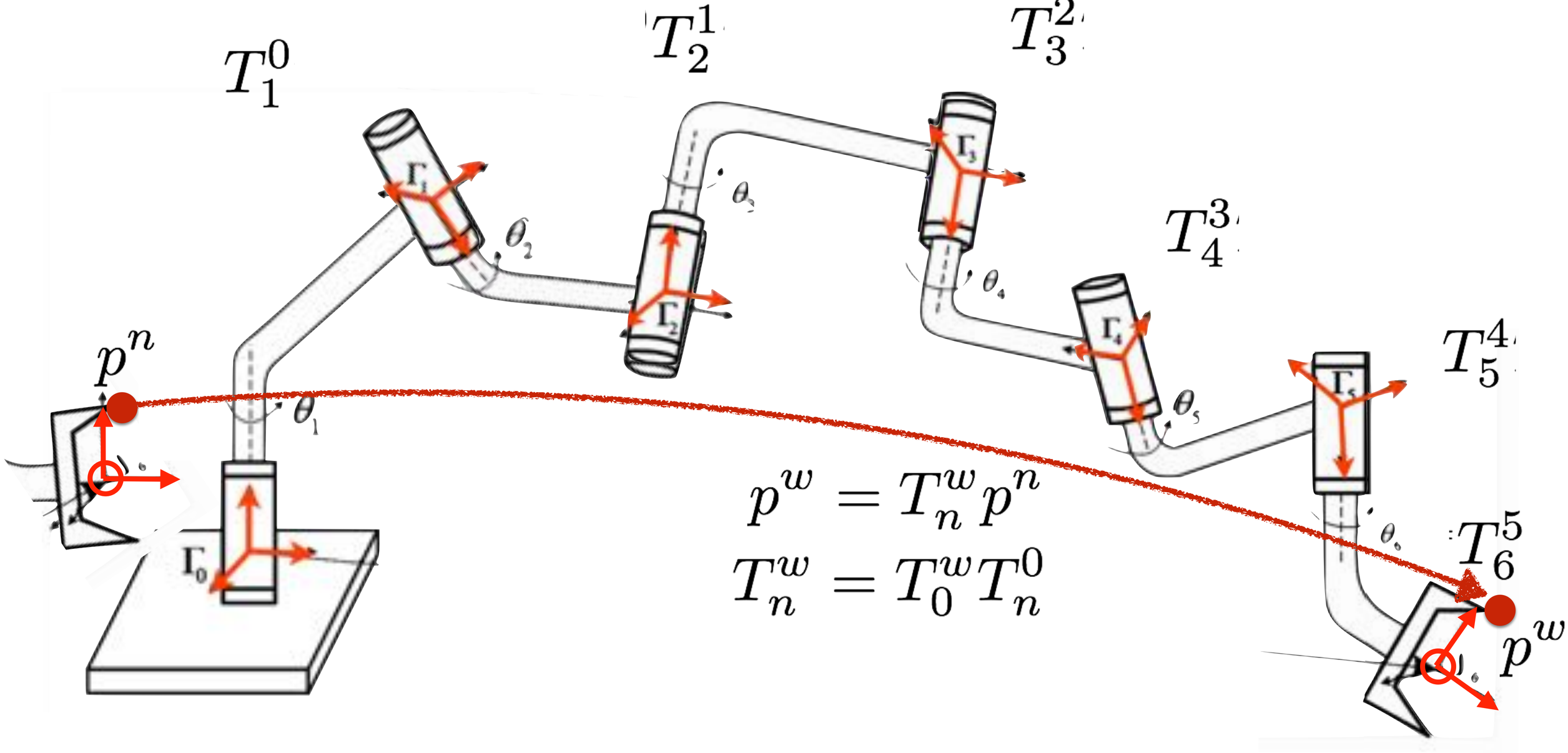
Any point on the endeffector can be transformed to its location in the world



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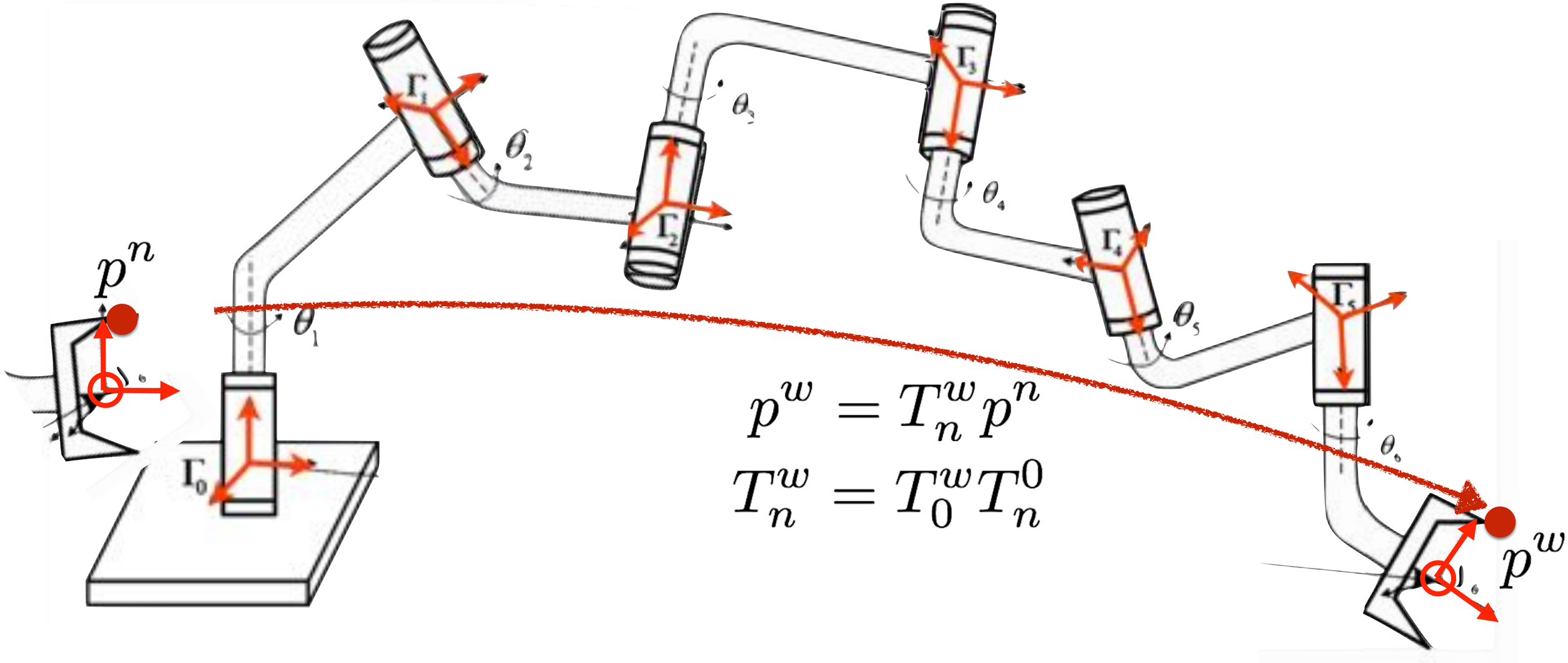
1) How to represent homogeneous transforms?

2) How to compute transform to endeffector?



$$p^w = T_n^w p^n$$

$$T_n^w = T_0^w T_n^0$$

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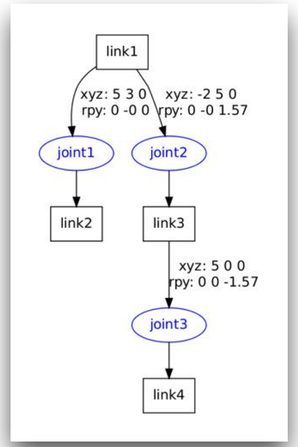
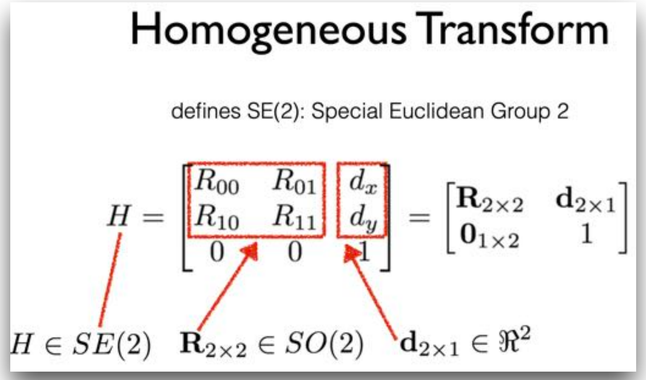
Previously

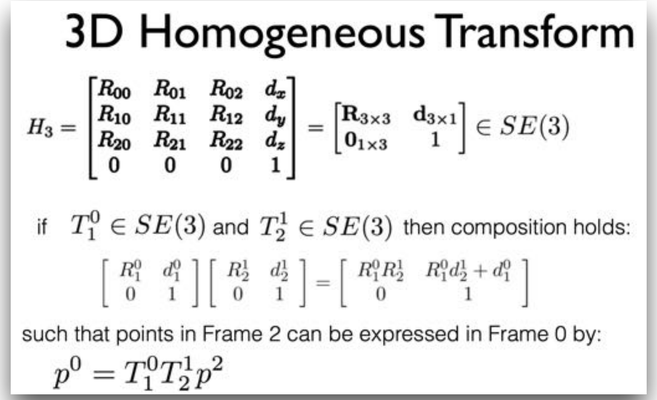
1) How to represent homogeneous transforms?

Assuming as given the:

- geometry of each link
- robot's kinematic definition

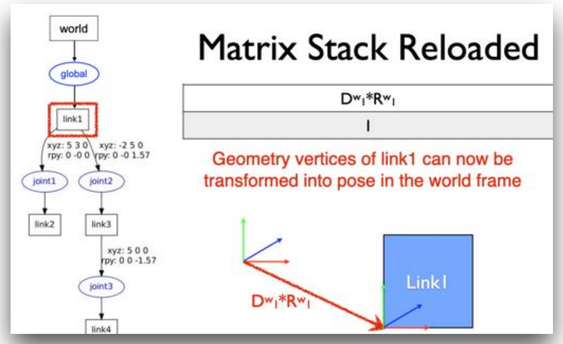






2) How to compute transform to endeffector?

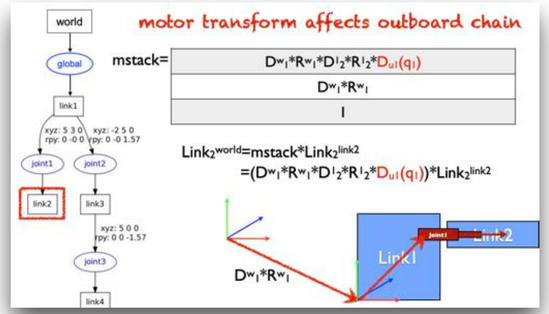
Zero configuration

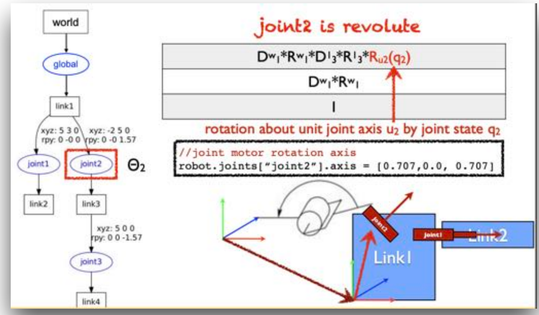


Assuming as given the:

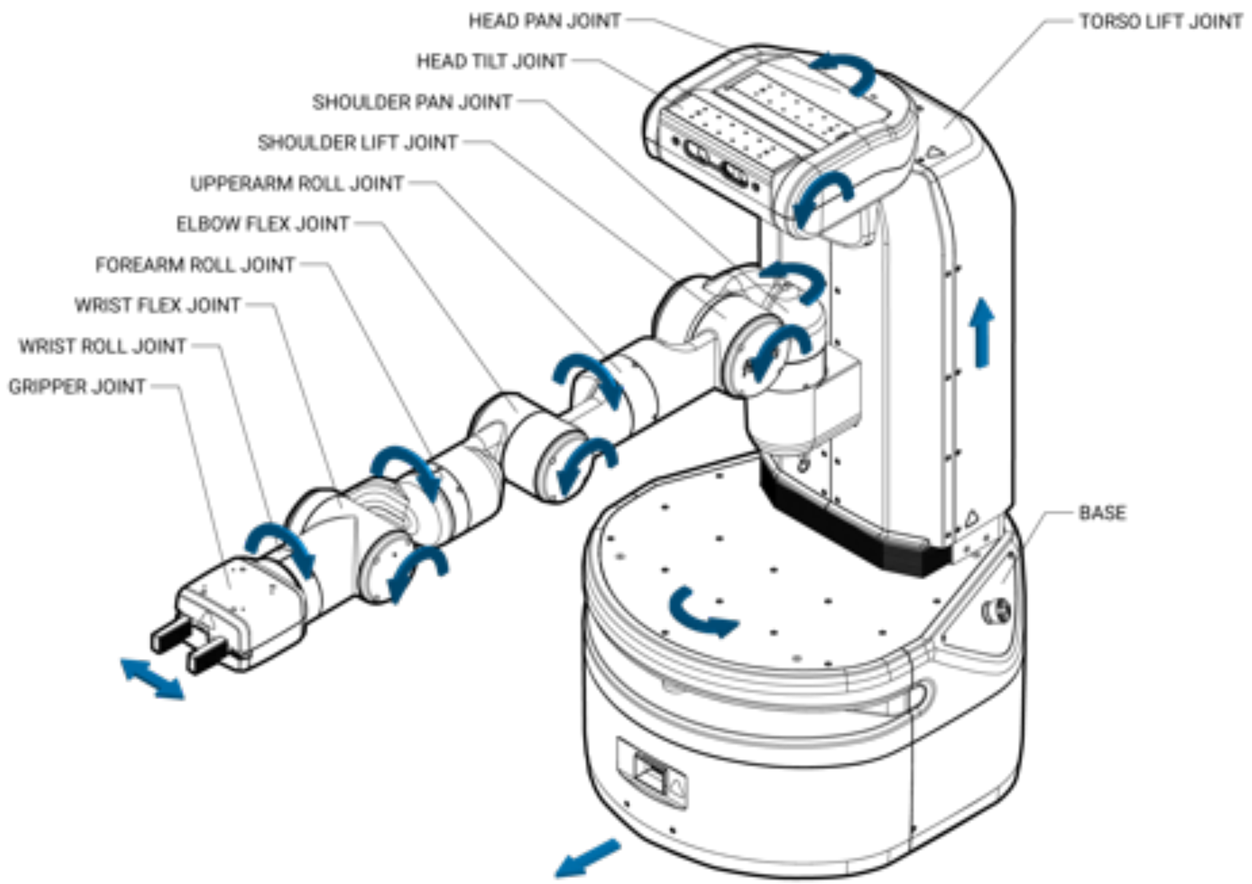
- geometry of each link
- robot's kinematic definition
- **current state of all joints**

Add motor motion





Can a joint move infinitely far?



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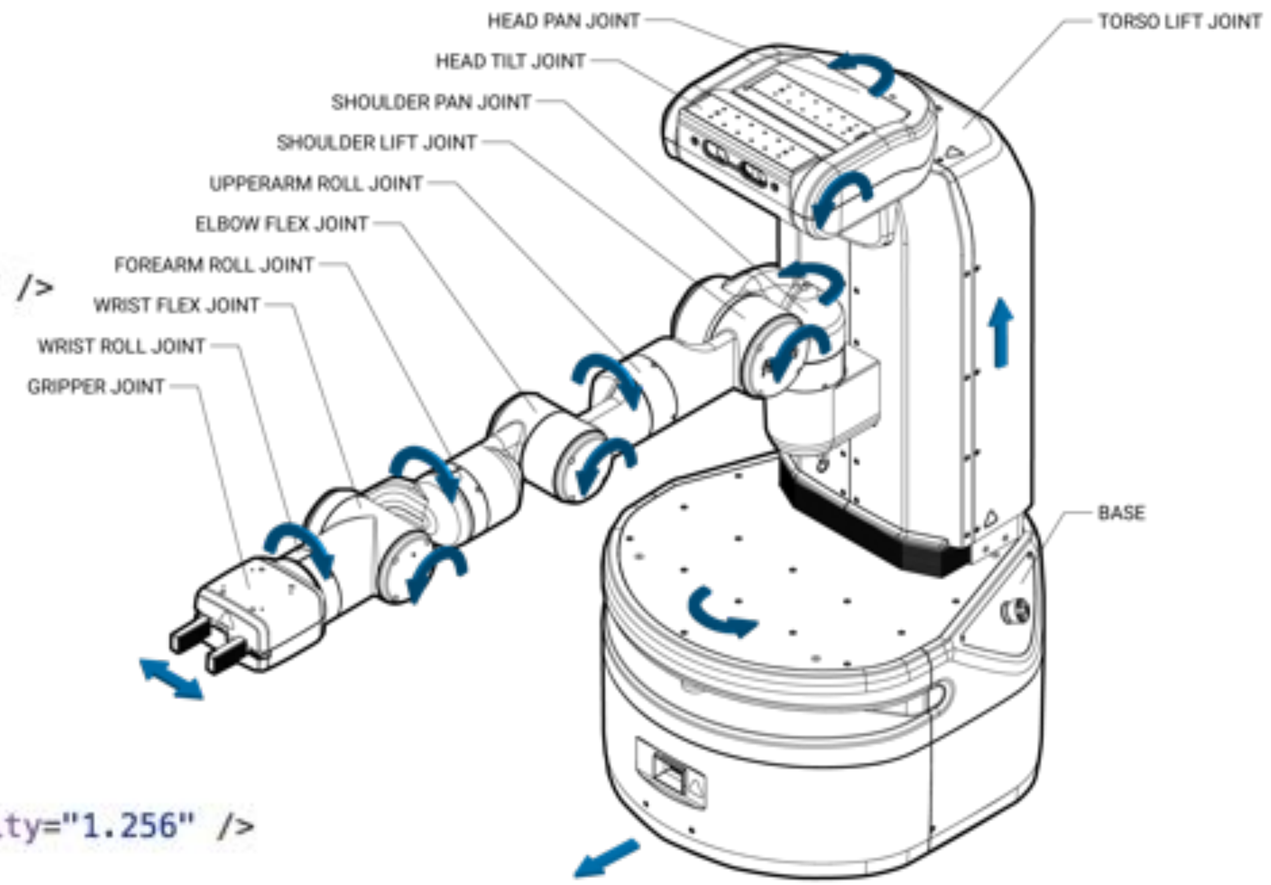
Joint Limits

Prismatic joint description

```
<joint name="torso_lift_joint" type="prismatic">
  <origin rpy="-6.123E-17 0 0" xyz="-0.086875 0 0.37743" />
  <parent link="base_link" />
  <child link="torso_lift_link" />
  <axis xyz="0 0 1" />
  <limit effort="450.0" lower="0" upper="0.4" velocity="0.1" />
<dynamics damping="100.0" /></joint>
```



Revolute joint description

```
<joint name="shoulder_pan_joint" type="revolute">
  <origin rpy="0 0 0" xyz="0.119525 0 0.34858" />
  <parent link="torso_lift_link" />
  <child link="shoulder_pan_link" />
  <axis xyz="0 0 1" />
  <dynamics damping="1.0" />
  <limit effort="33.82" lower="-1.6056" upper="1.6056" velocity="1.256" />
</joint>
```

Continuous joints have no limits

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Joint Limits

Prismatic joint description

```
<joint name="torso_lift_joint" type="prismatic">
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  <axis xyz="0 0 1" />
  <dynamics damping="1.0" />
  <limit effort="33.82" lower="-1.6056" upper="1.6056" velocity="1.256" />
</joint>
```

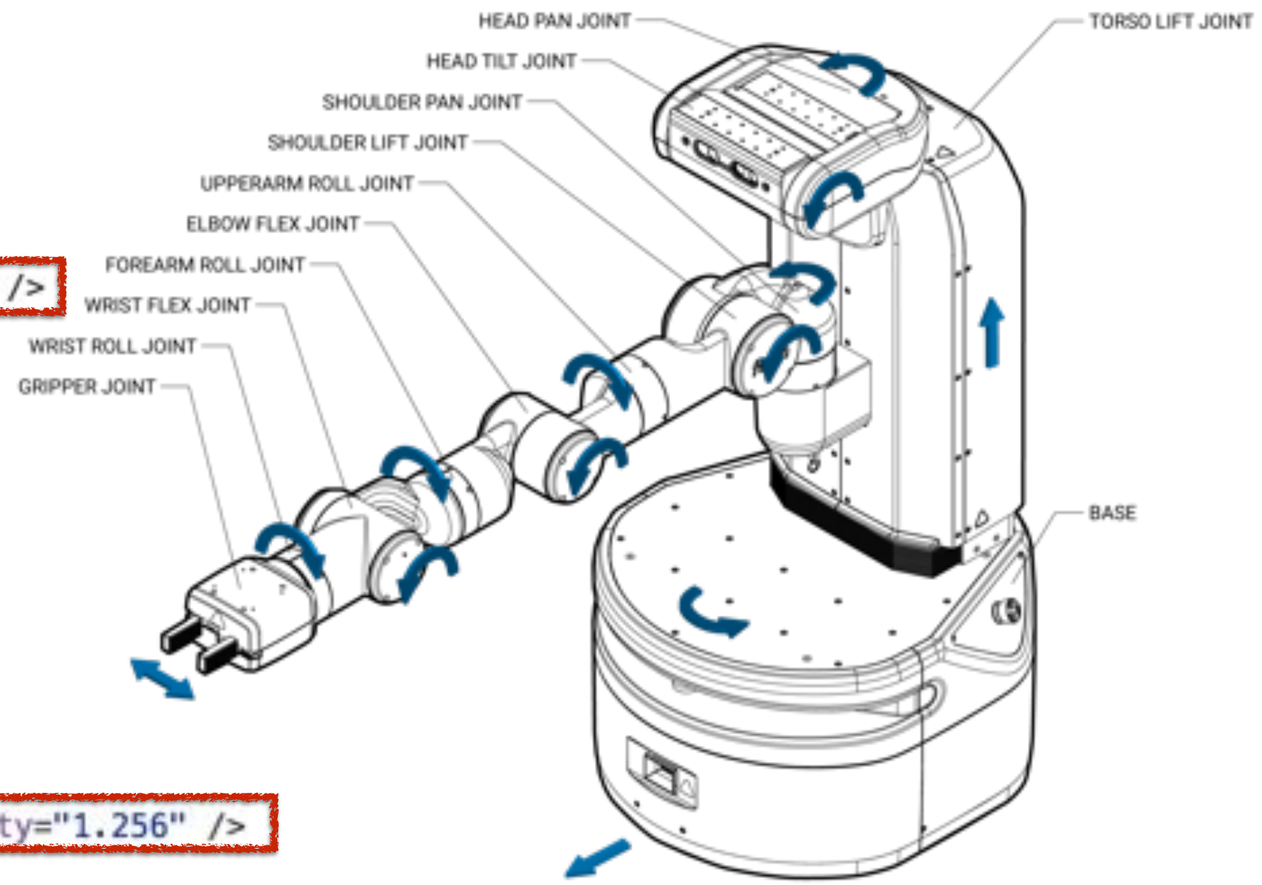

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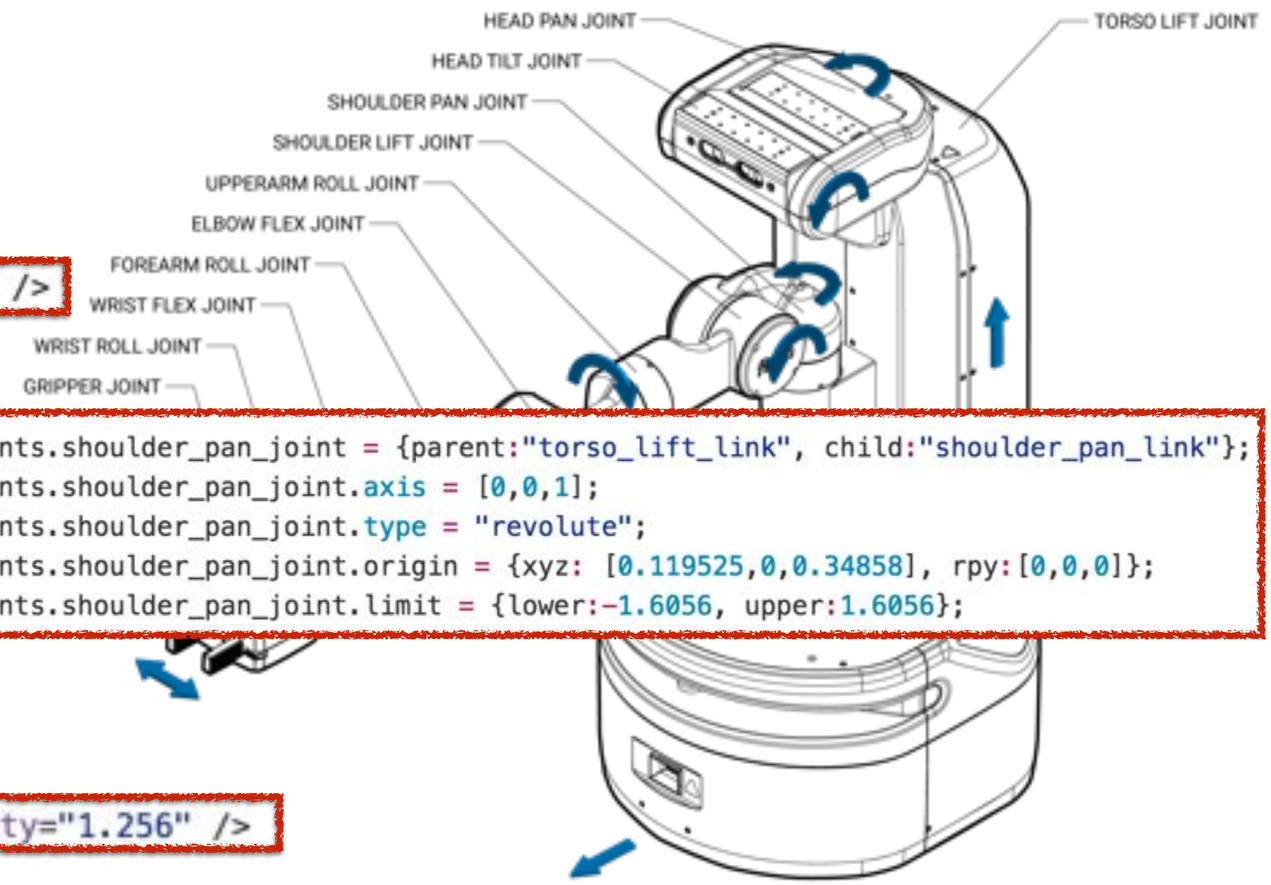
Prismatic joint description

```
<joint name="torso_lift_joint" type="prismatic">
  <origin rpy="-6.123E-17 0 0" xyz="-0.086875 0 0.37743" />
  <parent link="base_link" />
  <child link="torso_lift_link" />
  <axis xyz="0 0 1" />
  <limit effort="450.0" lower="0" upper="0.4" velocity="0.1" />
<dynamics damping="100.0" /></joint>
```

```
robot.joints.torso_lift_joint = {parent:"base_link", child:"torso_lift_link"};
robot.joints.torso_lift_joint.axis = [0,0,1];
robot.joints.torso_lift_joint.type = "prismatic";
robot.joints.torso_lift_joint.origin = {xyz: [-0.086875,0,0.37743], rpy:[-6.123E-17,0,0]};
robot.joints.torso_lift_joint.limit = {lower:0, upper:0.4};
```

Revolute joint description

```
<joint name="shoulder_pan_joint" type="revolute">
  <origin rpy="0 0 0" xyz="0.119525 0 0.34858" />
  <parent link="torso_lift_link" />
  <child link="shoulder_pan_link" />
  <axis xyz="0 0 1" />
  <dynamics damping="1.0" />
  <limit effort="33.82" lower="-1.6056" upper="1.6056" velocity="1.256" />
</joint>
```




```
robot.joints.shoulder_pan_joint = {parent:"torso_lift_link", child:"shoulder_pan_link"};
robot.joints.shoulder_pan_joint.axis = [0,0,1];
robot.joints.shoulder_pan_joint.type = "revolute";
robot.joints.shoulder_pan_joint.origin = {xyz: [0.119525,0,0.34858], rpy:[0,0,0]};
robot.joints.shoulder_pan_joint.limit = {lower:-1.6056, upper:1.6056};
```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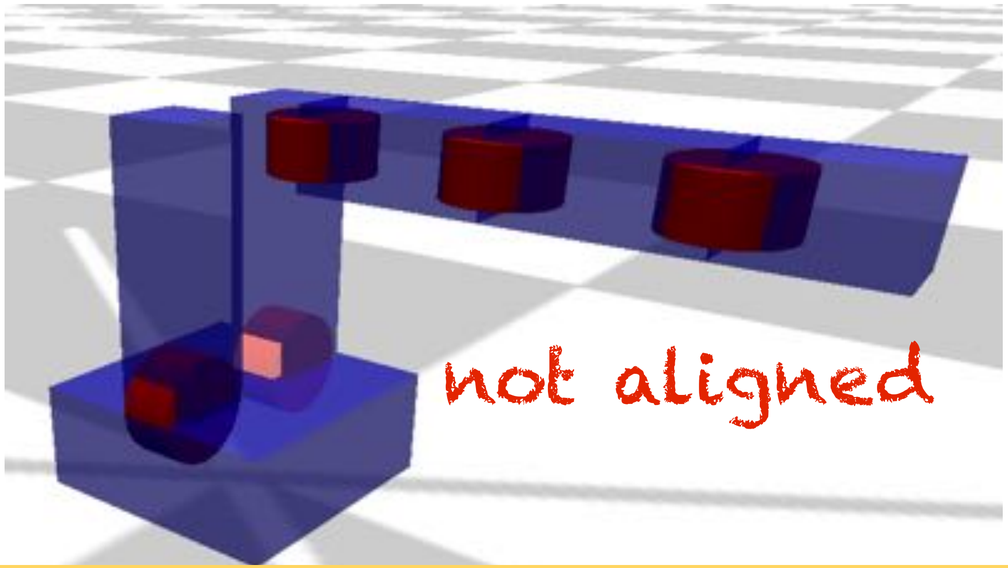
Important notes

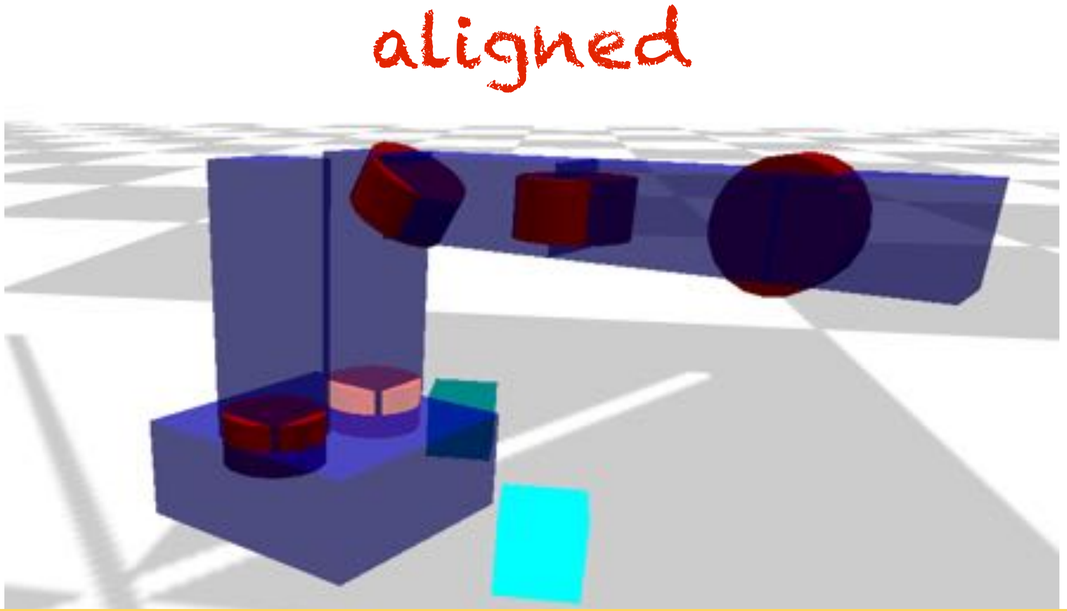
Important notes

- Rotation order I use: **XYZ** ($R_z R_y R_x$)
- vector_cross(): code stencil tests for and uses this function
- Base controls: must be implemented for interactive control
- The ".origin" field of links and joints are used to store transforms without consideration of joint motion (provided only for debugging)
- A joint and its child link will share the same coordinate frame

KinEval joint cylinder rendering

- threejs creates cylinders with axes aligned along y-axis
- you need to implement vector_cross() for KinEval to render joint cylinders properly along joint axis





Global controls for base

- Assume we have a base that is holonomic wrt. ground plane
  - holonomic: can move in any direction
- kineval_userinput.js assumes:

How to perform this base movement?

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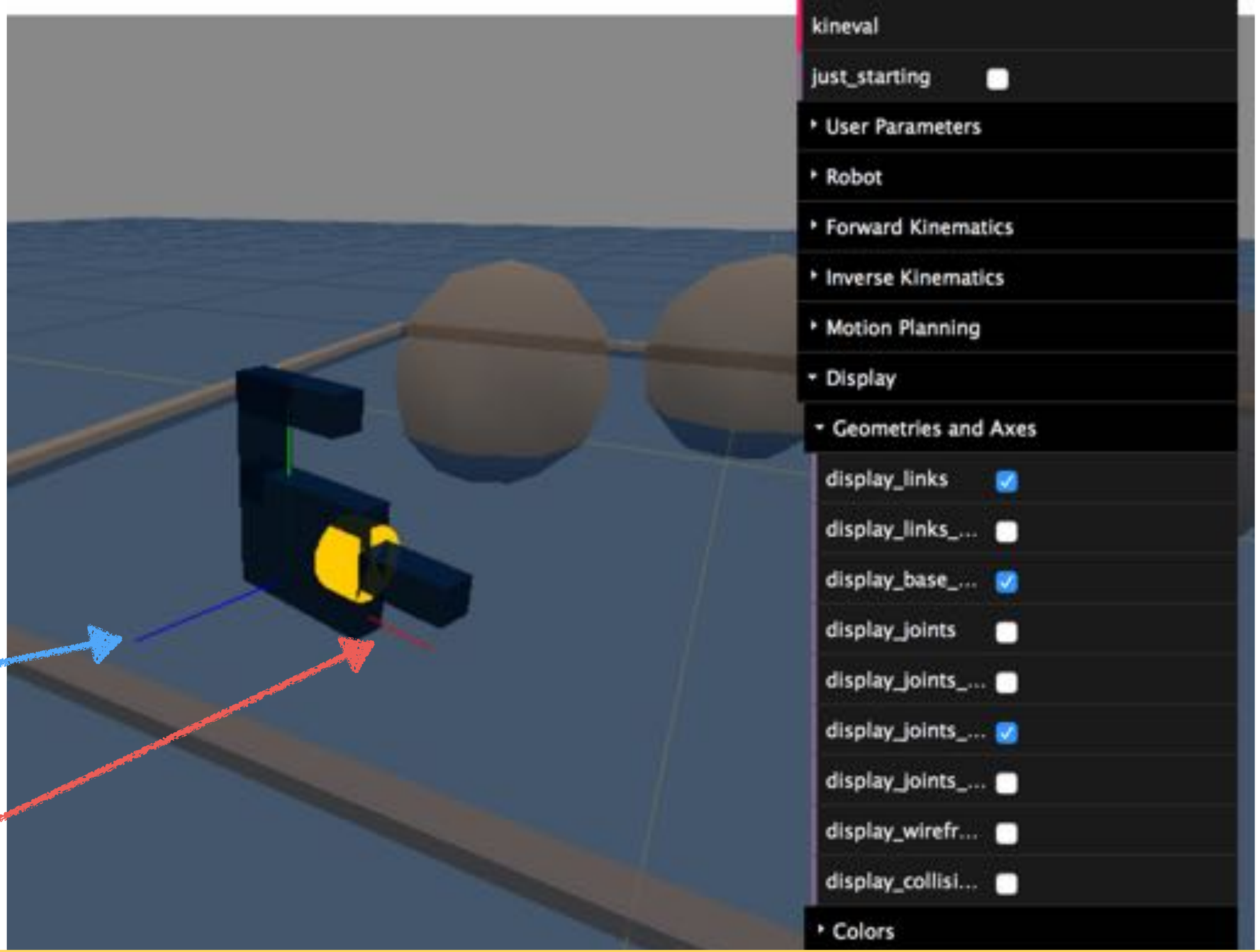
Transform vectors for heading (local z-axis) and lateral (local x-axis) of robot base into world coordinates

Store transformed vectors in variables “robot_heading” and “robot lateral”



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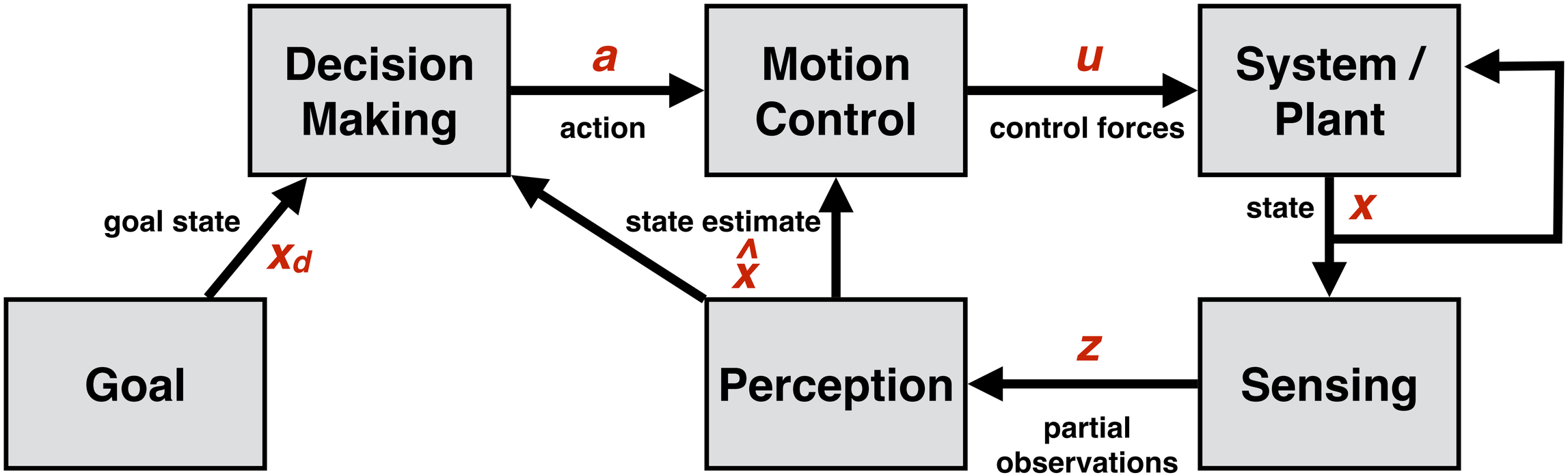
Alternatives for FK

- Denavit-Hartenberg Convention
- Product of Exponentials with Matrix Stack AutoRob & 5551
- Screw vectors as Dual Quaternions

[Kenwright 2012, Daniilidis 1999]

Decision Making

Robot Control Loop



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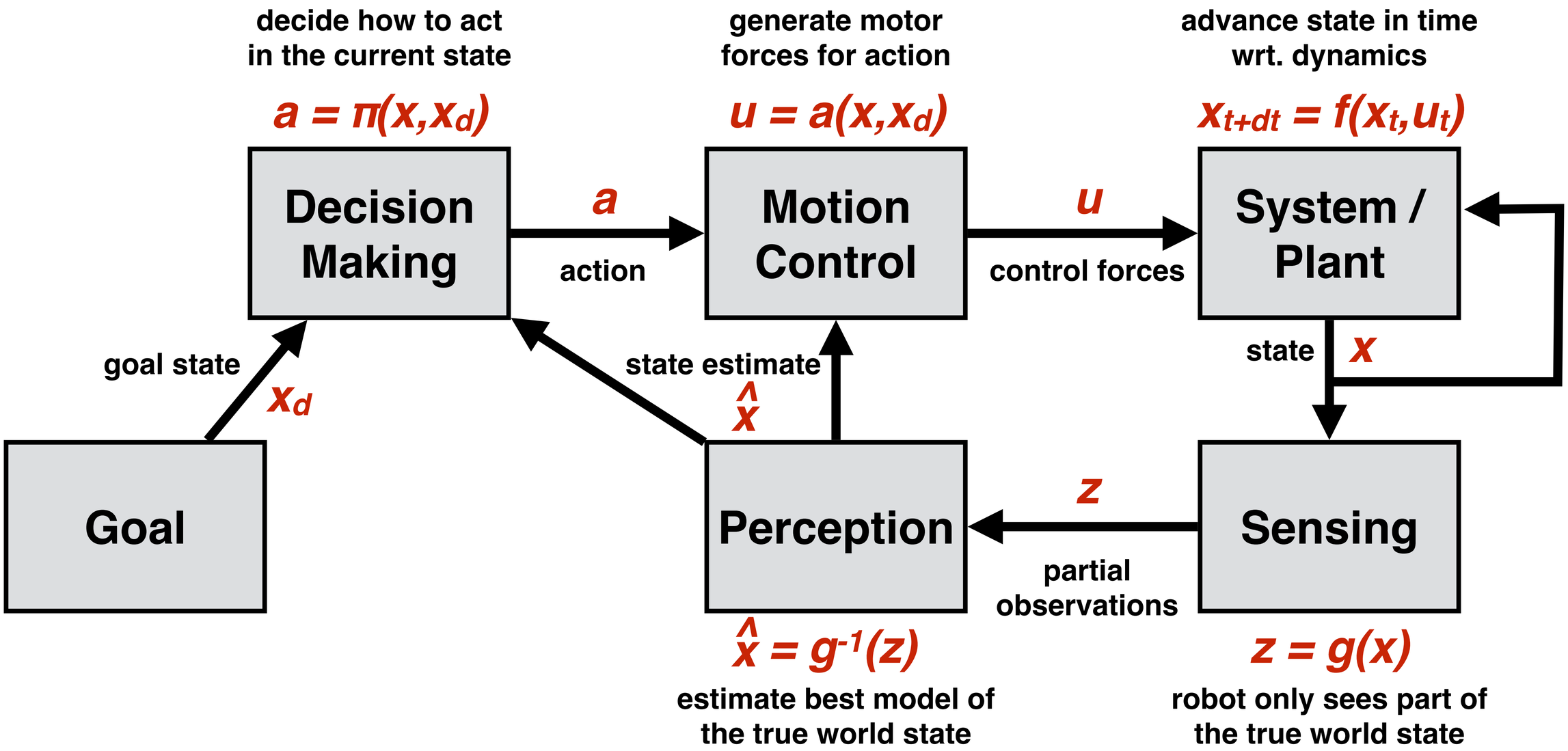
Robot Control Loop



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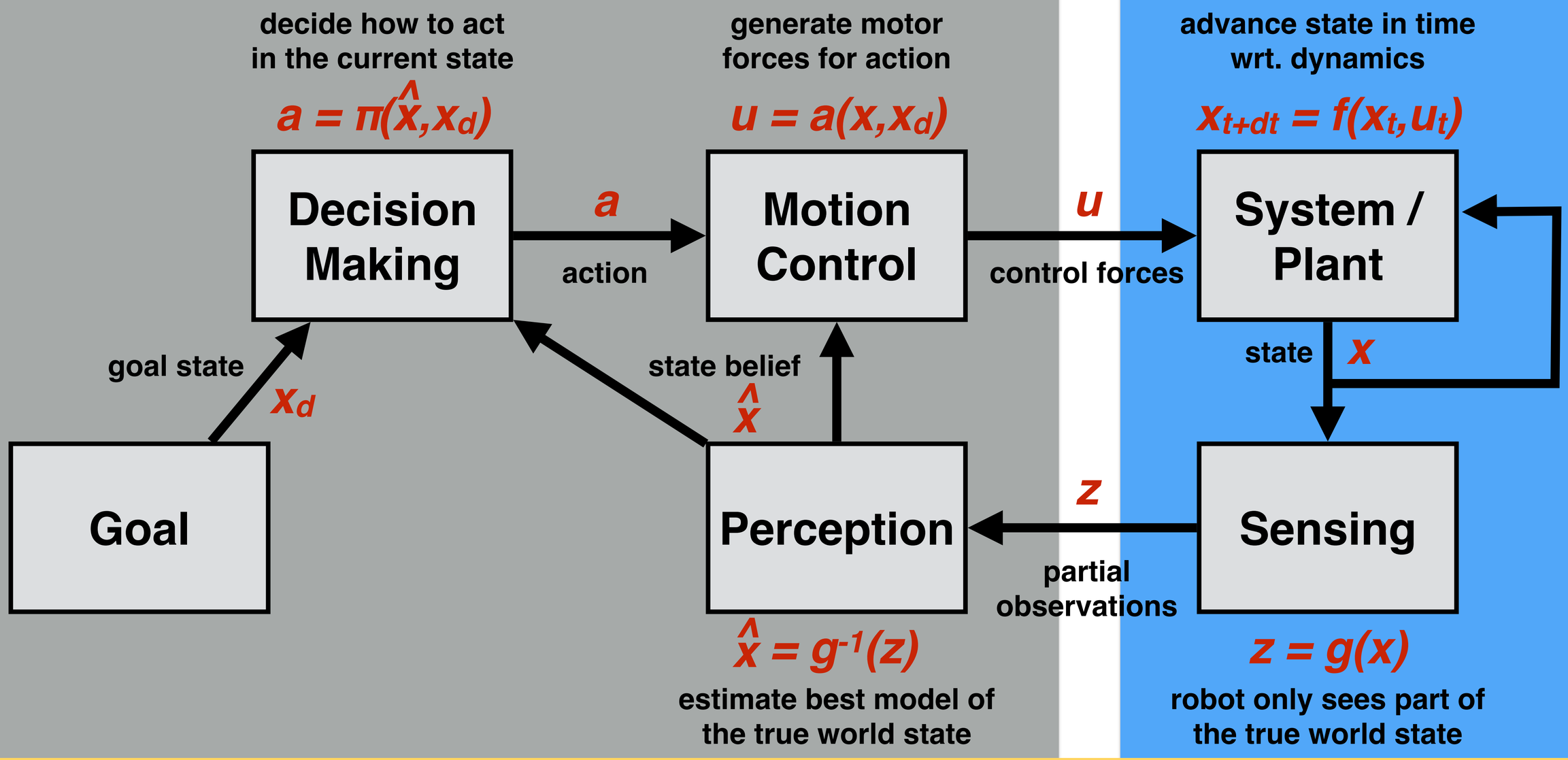
Autonomy

Embodiment



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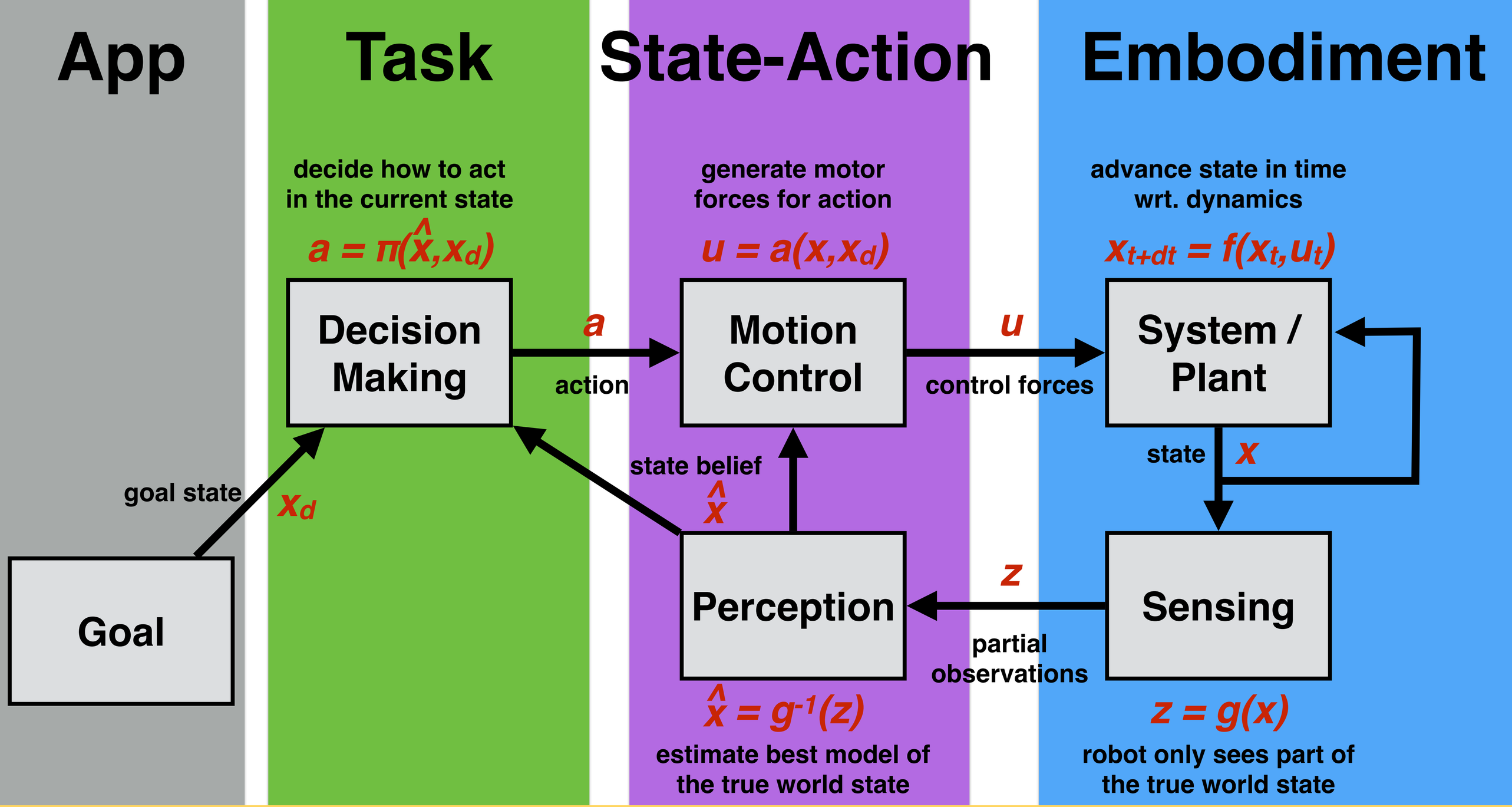

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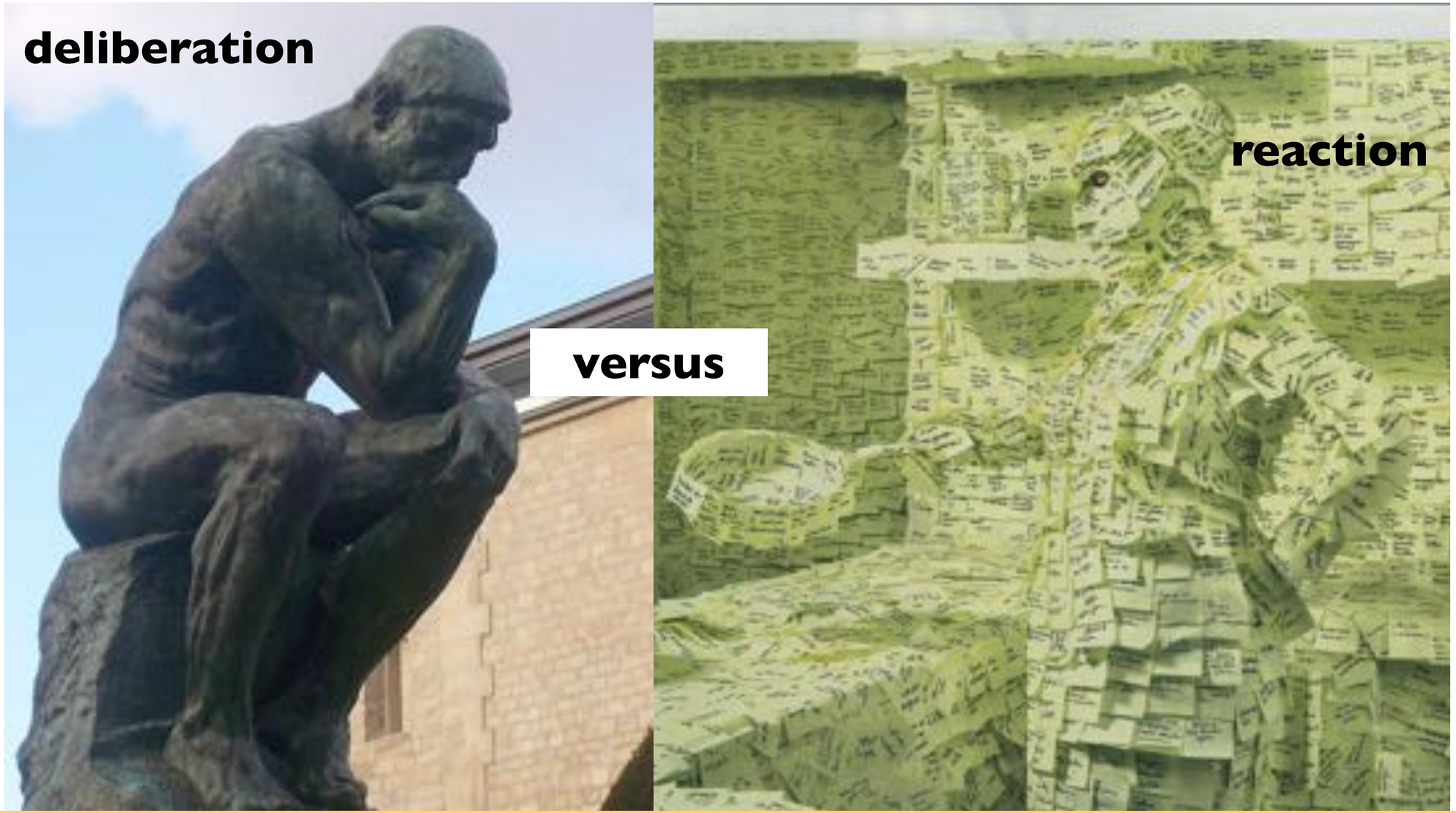
Robot Decision Making



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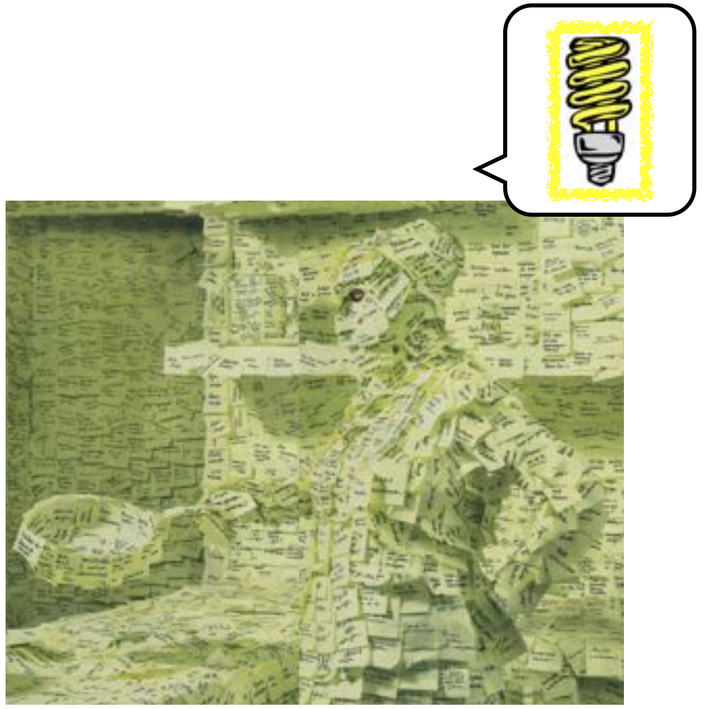
Should your robot's decision making

OR

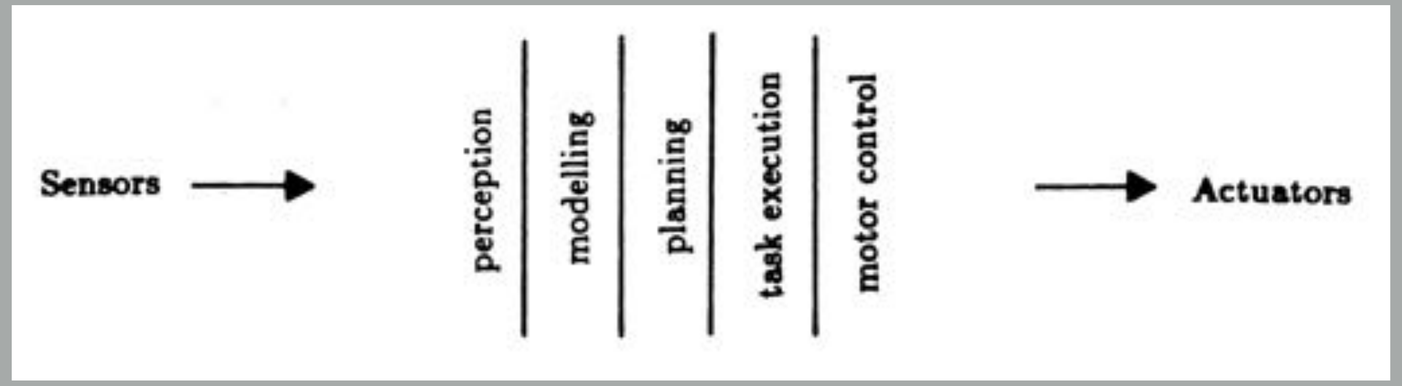


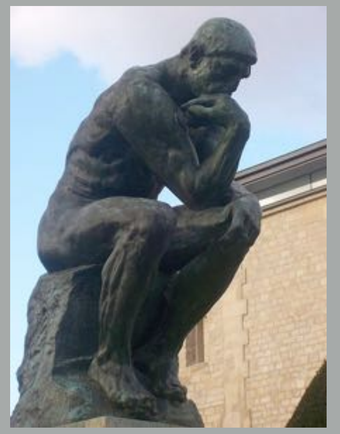
fully think through solving a problem?

react quickly to changes in its world?

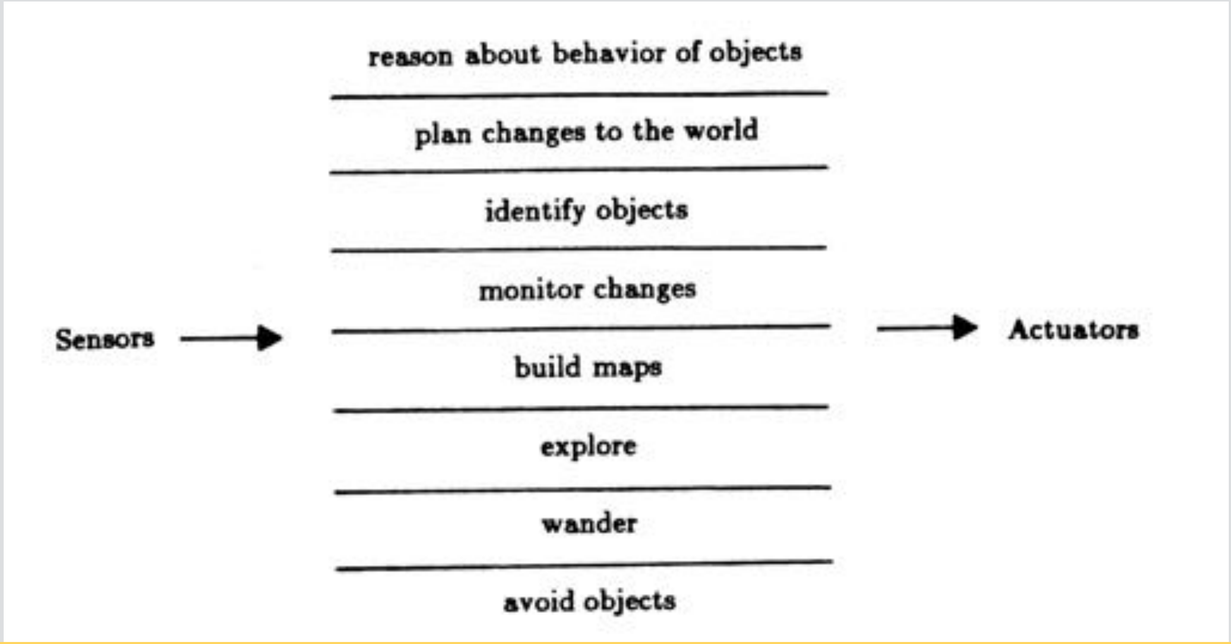
Deliberation v. Reaction

deliberative:
sense-plan-act,
path planning
motion planning





reaction:
controllers acting in parallel
subsumption,
Finite State Machine



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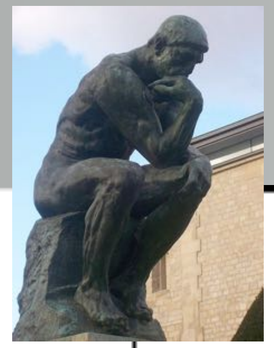
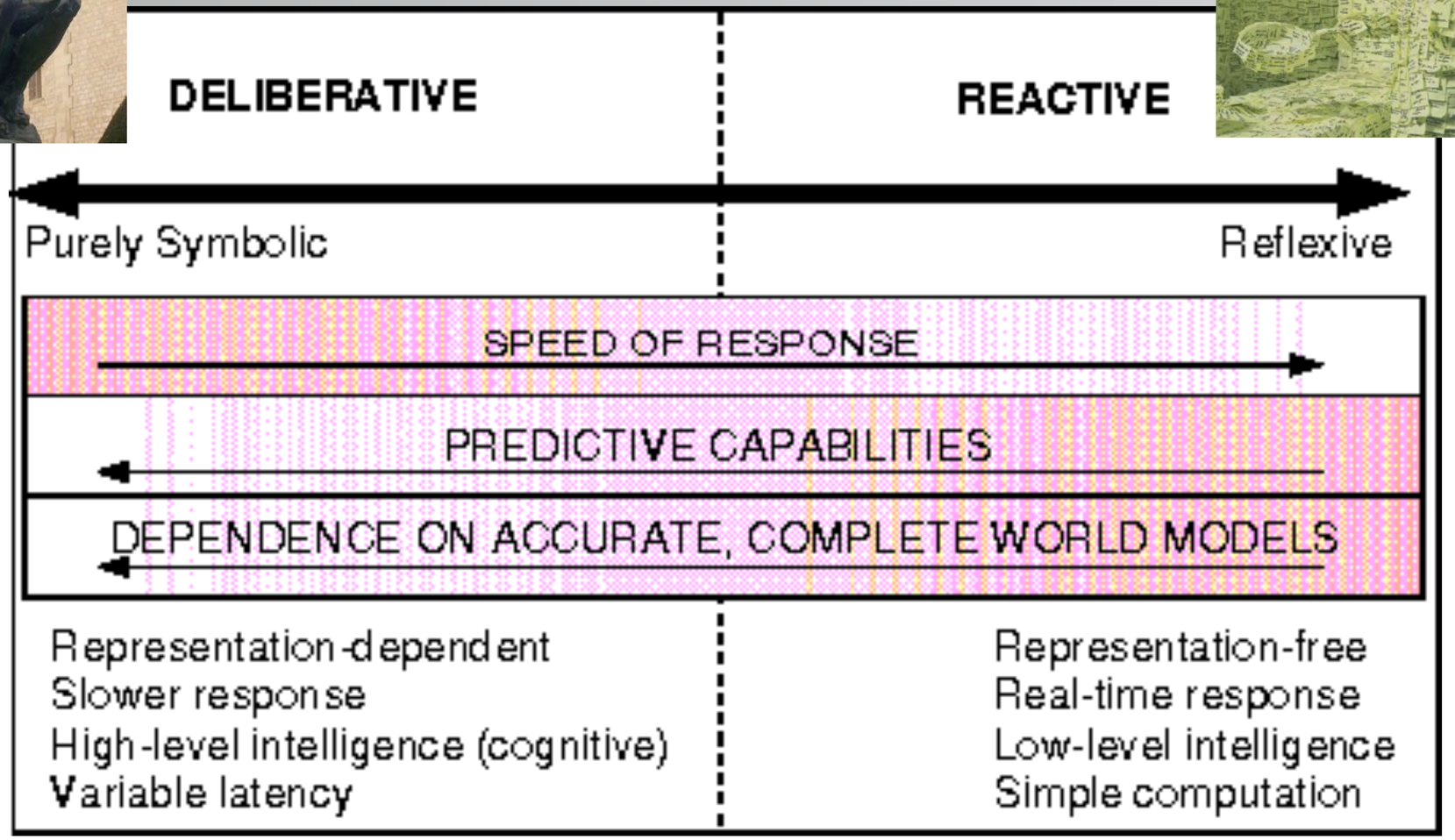
[Arkin 1998]

Deliberation-Reaction spectrum



Complete
Adaptive
Optimal
Slower

Requires complete model of the world



Faster
Cheaper
More robust
Forgetful

Requires a complete design of the problem

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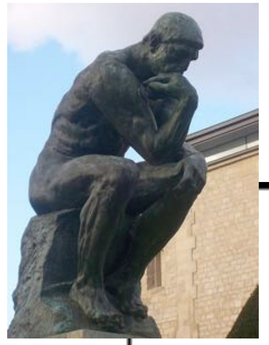
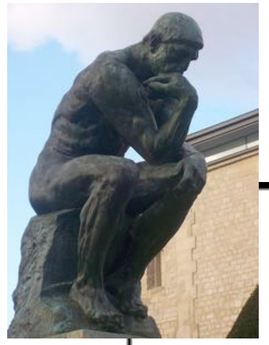
Examples?



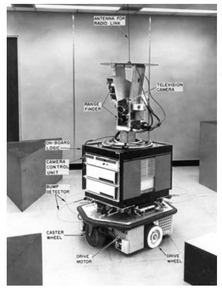
example???

Examples?



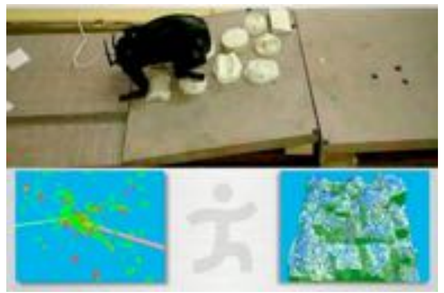
https://www.youtube.com/watch?v=jCB3pd-wBw0

Deliberation



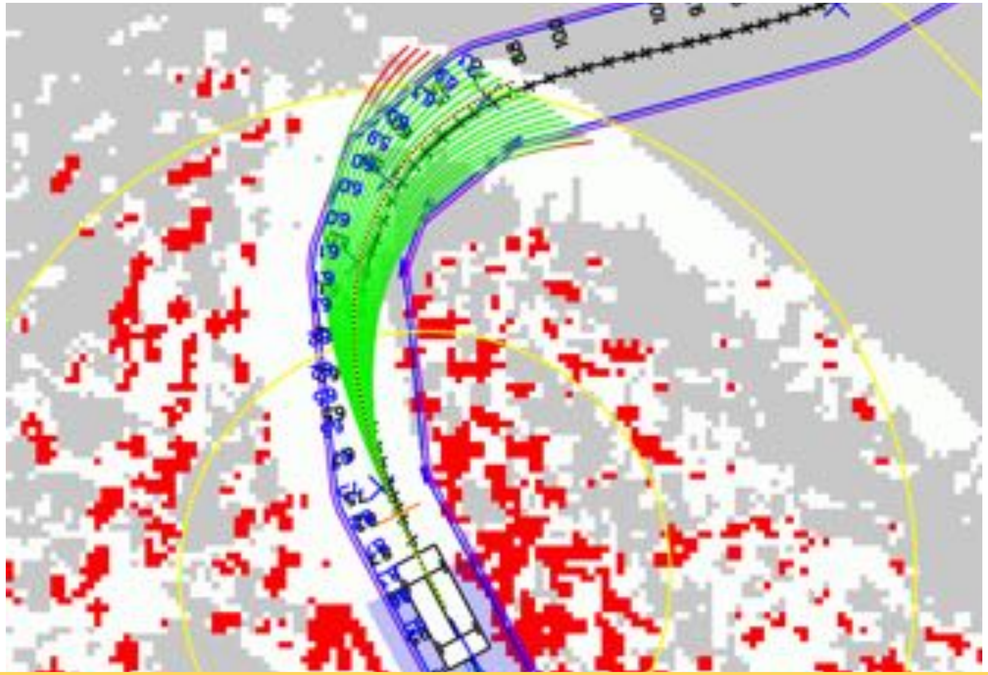
"Sense-Plan-Act" paradigm

- sense: build most complete model of world
  - GPS, SLAM, 3D reconstruction, affordances
- plan: search over all possible outcomes
  - Graph search, Roadmap planning
- act: execute plan through motor forces
  - PID control, Model predictive control



Stanley (Grand Challenge)

Road detection



Navigation

2005

MIT Talos (Urban Challenge)

2007

2013

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Deliberation
requires a model of the world

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Color+Depth Camera

Laser Rangefinder

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Simultaneous Localization and Mapping

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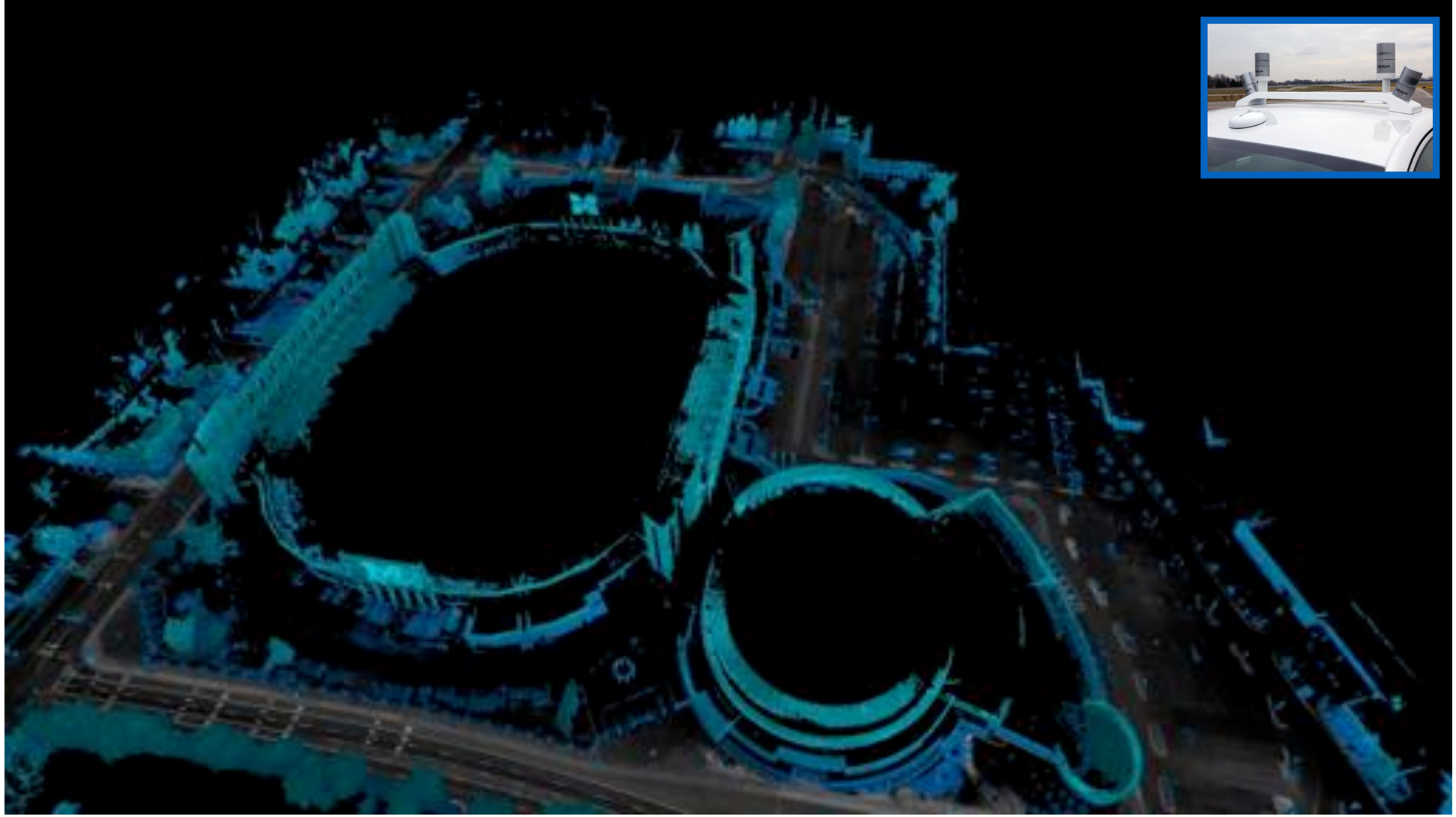
Autonomous robot navigation from previously built map

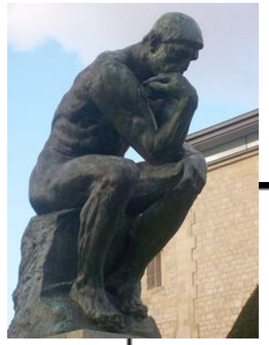
Michigan Next Generation Vehicle (Eustice, Olson et al.)



Autonomous Transportation

Michigan Next Generation Vehicle (Eustice, Olson et al.)

Examples?



DELIBERATIVE

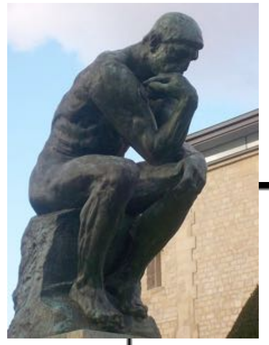
REACTIVE

Purely Symbolic

Reflexive

more common example???

Examples?



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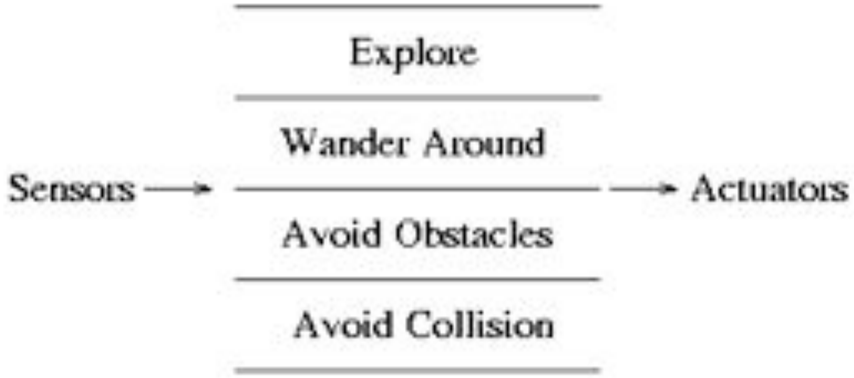
Reaction



- No representation of state
  - Typically, fast hardcoded rules
- Embodied intelligence
  - behavior ← control + embodiment
  - Stigmergy (e.g, ant scouts using pheromones)

- Finite State Machines
  - most common
- Subsumption architecture
  - prioritized reactive policies

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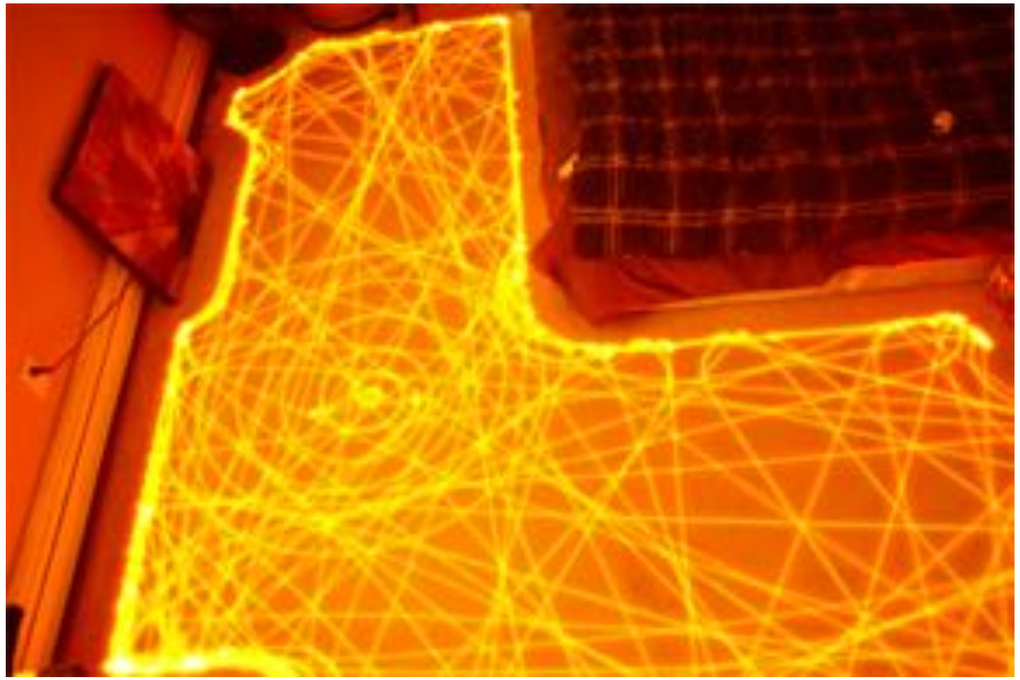
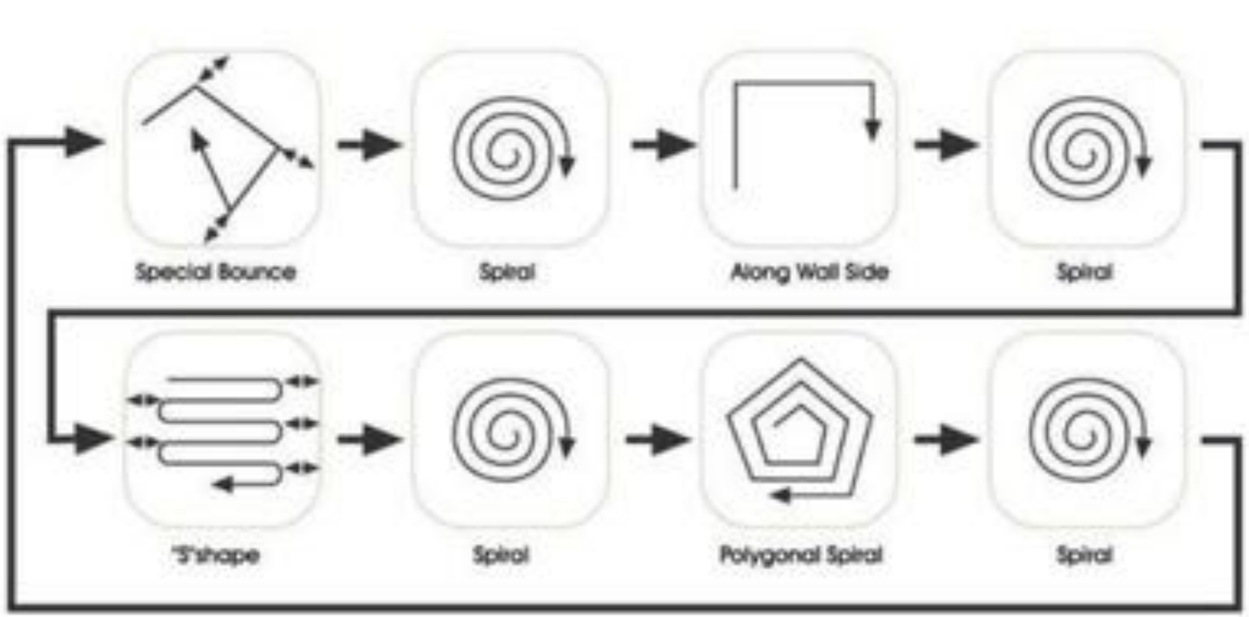
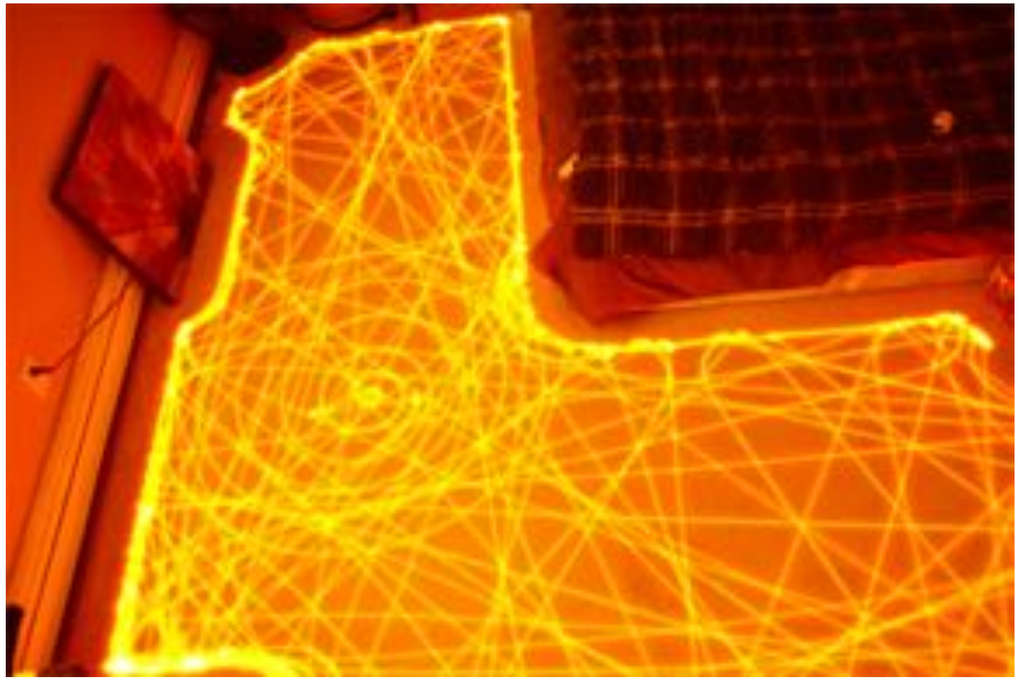
Roomba cleaning pattern



https://www.youtube.com/watch?v=G4ocrevf4ng

Vacuuming Finite State Machine





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Manipulation Gaits

Collections of robust manipulation controllers

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How do we computationally represent reactive control?

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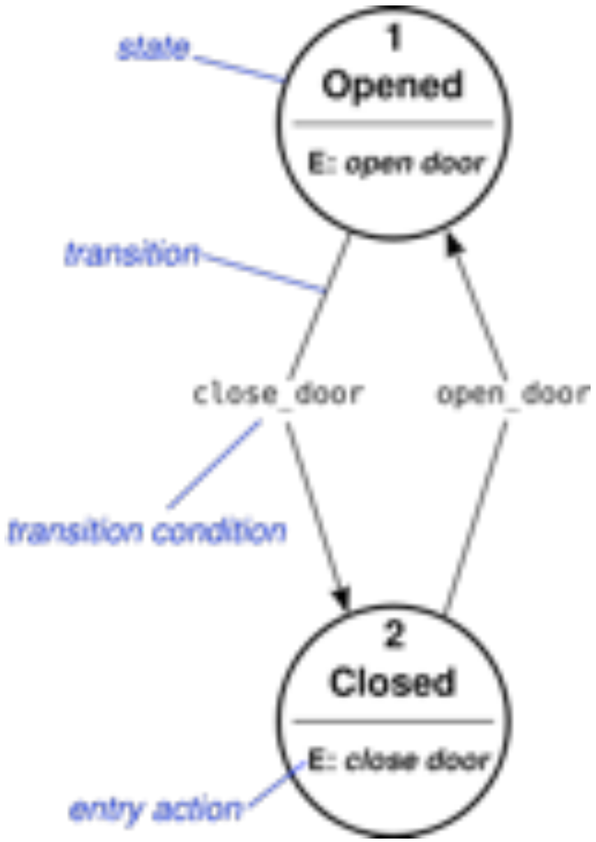
Finite State Machines

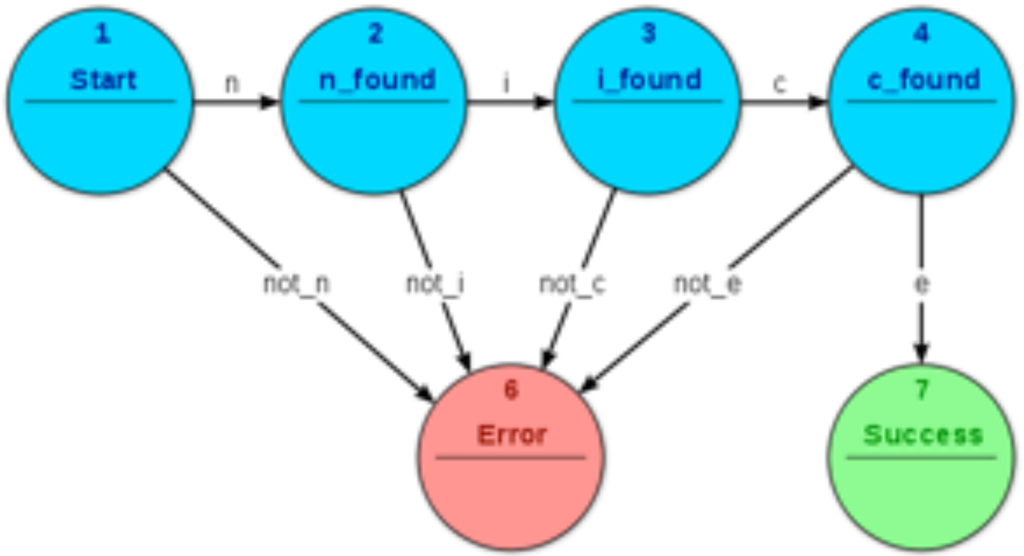
- Components
  - alphabet (or inputs)
    - “observations” in robotics
  - states (some robot action)
  - transitions (between states)
  - stopping condition
- Commonly, implemented as switch-case or if-else within a while loop



http://en.wikipedia.org/wiki/Switch_statement

“nice” recognizer

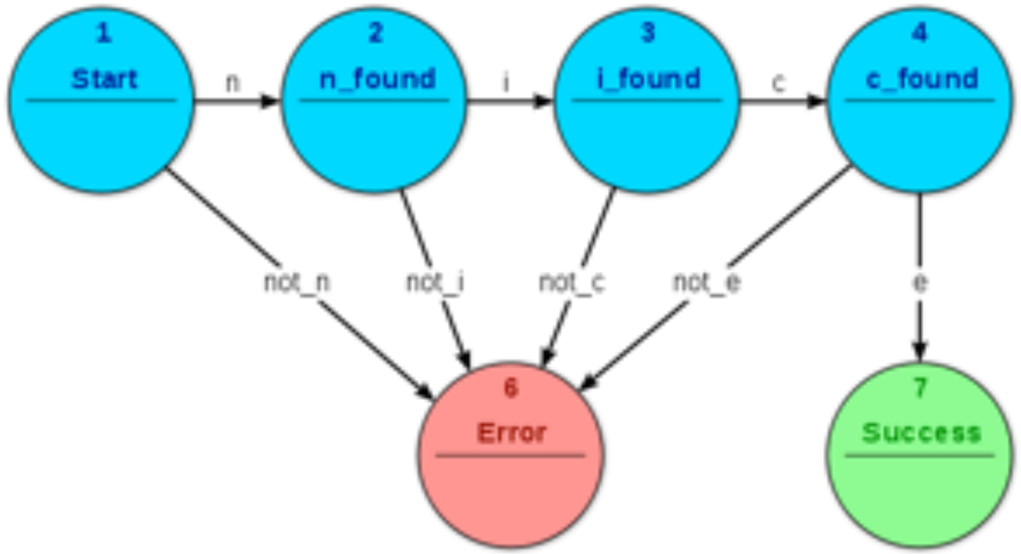
- recognize the string “nice” from input
  - if input is “nice”
    - output **success**
  - if input not “nice”
    - output **error**



- robotics uses
  - preconditions (enter state)
  - postconditions (exit state)

```
state ← start
while state != success and state != error
  token ← <next string character from input>
  switch (state):
    case start:
      if token = “n” then state ← n_found
      else state ← error
      break
    case n_found:
      if token = “i” then state ← i_found
      else state ← error
      break
    case i_found:
      if token = “c” then state ← c_found
      else state ← error
      break
    case c_found:
      if token = “e” then state ← success
      else state ← error
      break
end while loop
output ← state
```

“nice” recognizer



Consider input: “nice”

Consider input: “robotics”

Consider input: “niece”

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Move to objects in sequence?

- How to move a mobile robot to a given sequence of objects?
  - yellow ball
  - green/orange landmark
  - pink landmark
  - orange/green landmark

Object Seeking

http://www.youtube.com/watch?v=-hOA0jMUggg

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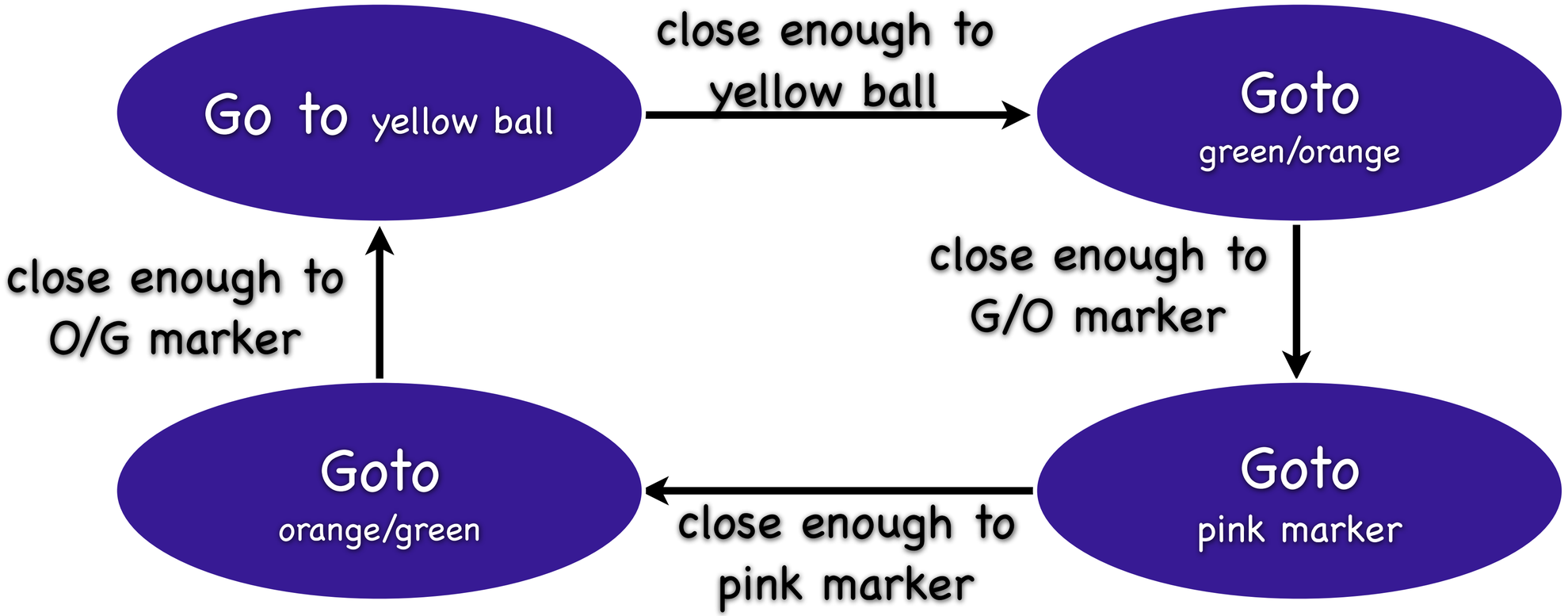
Move to objects in sequence?

- What are the states?
- What are the transitions?
- Preconditions for states?
- Postconditions for states?

Object seeking FSM



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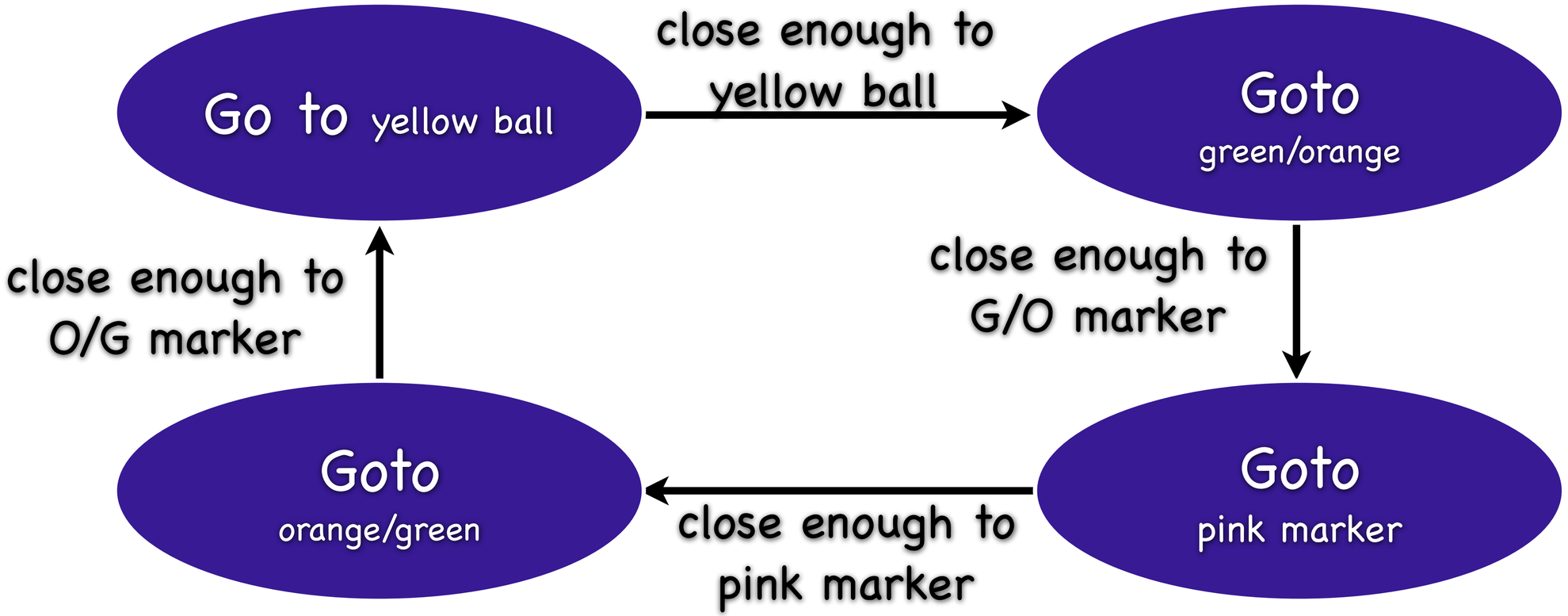
Object seeking FSM

How to implement state?

How to detect "close enough"?



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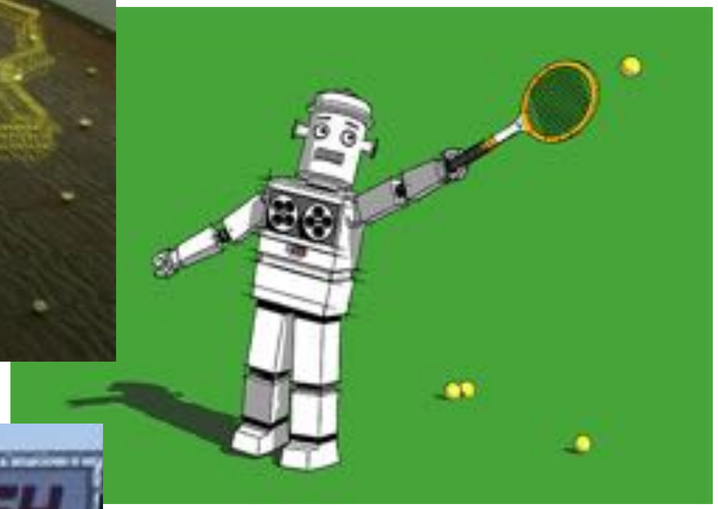
FSMs for Other Tasks

- Robot foraging?
- Robot tennis/pong?
- Pushing a ball into a goal?
- Vacuuming a room
- Driving a car?
- Robot dancing!



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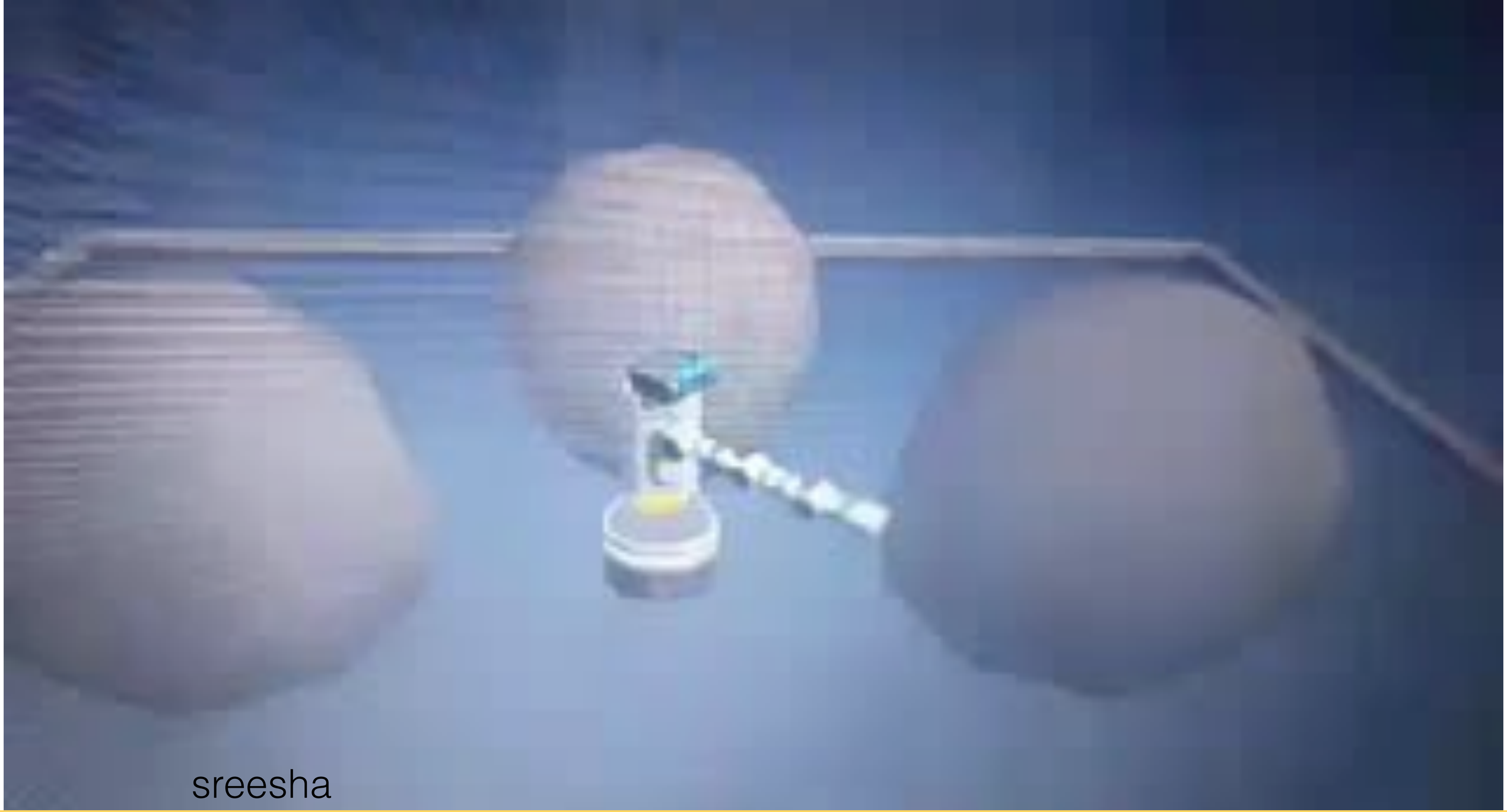
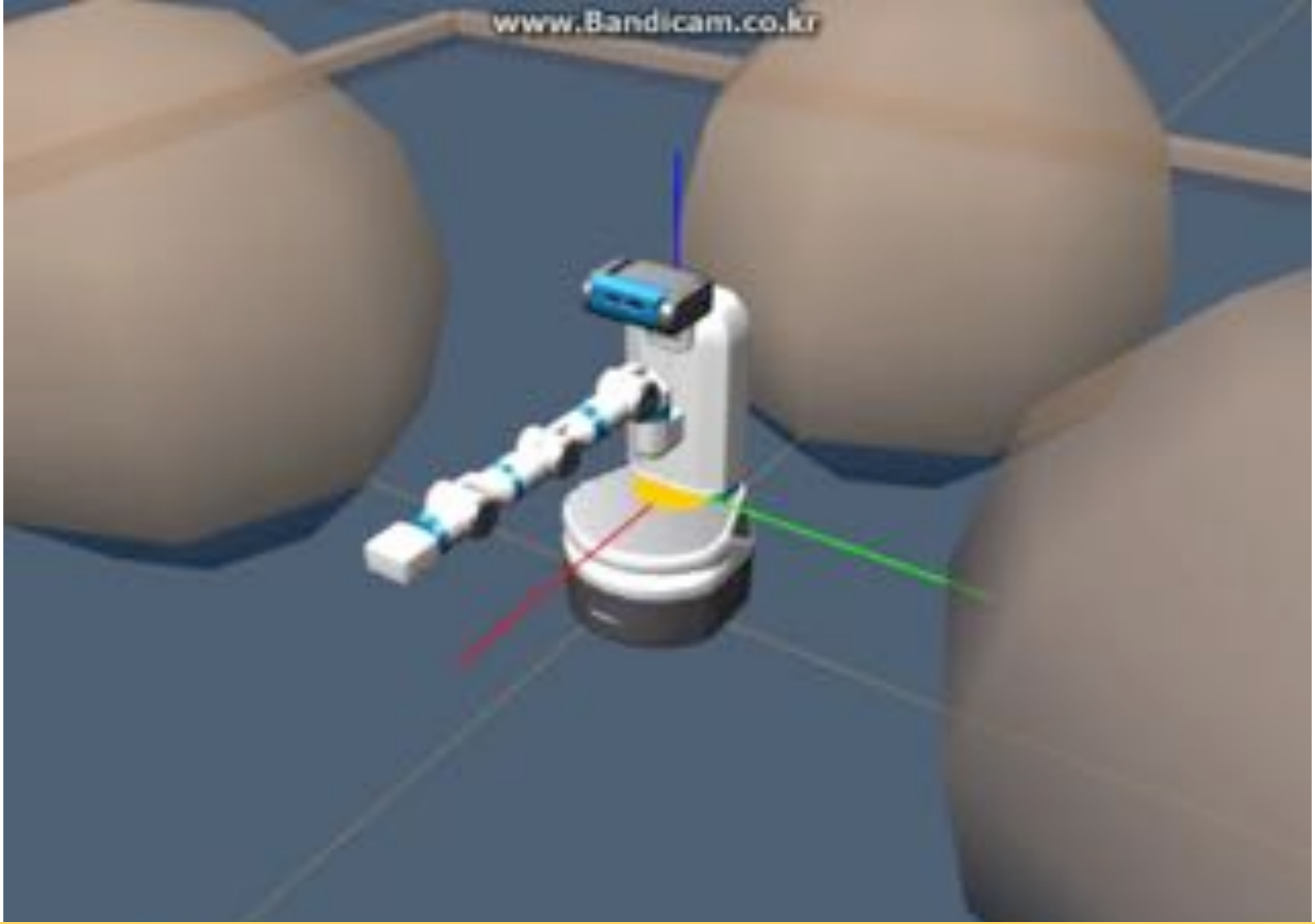
Assignment 4 robot dance (ohseejay)

https://www.youtube.com/watch?v=WyQ9aoB3bpI


sreesha



heostar

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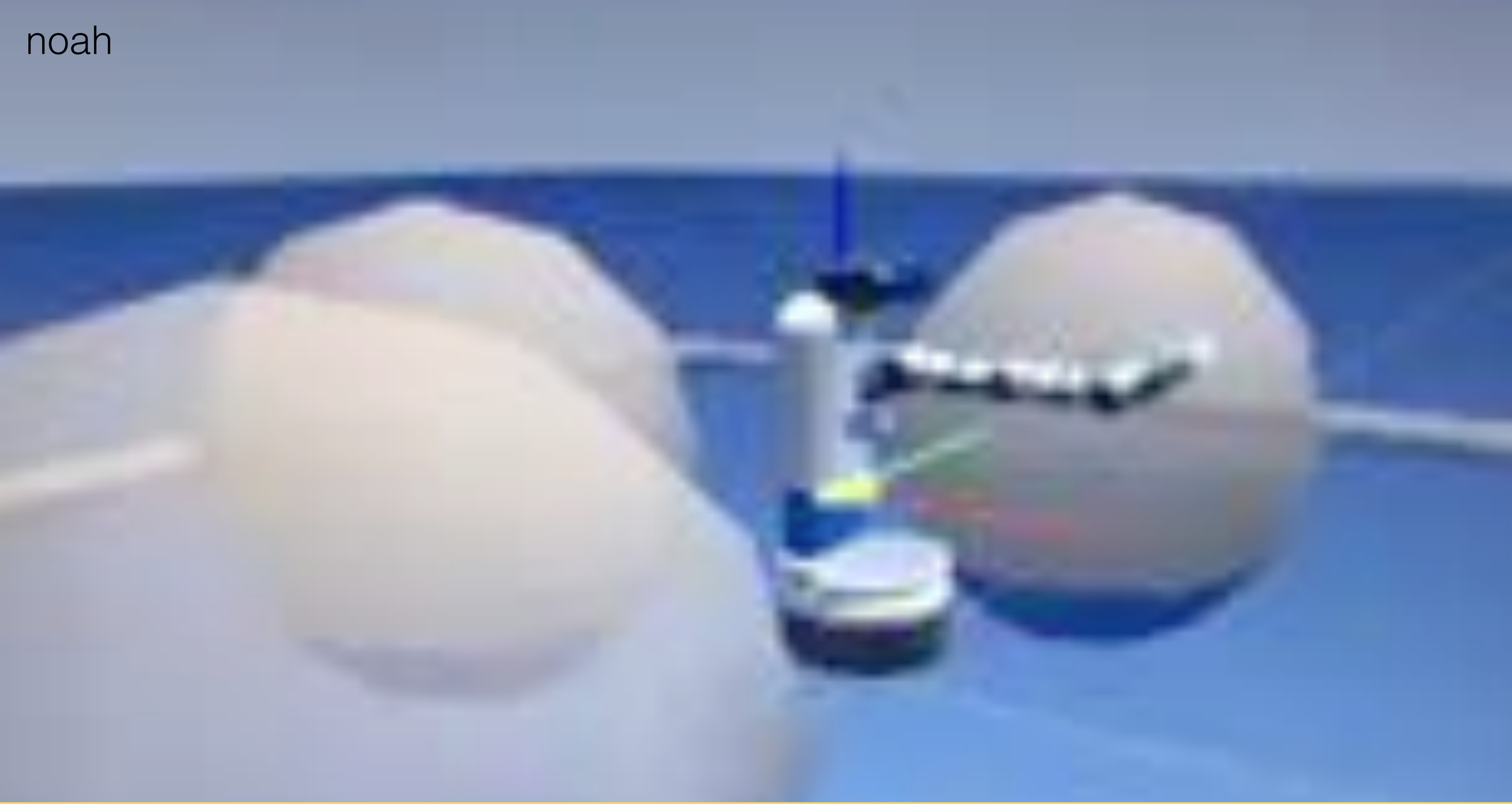
noah



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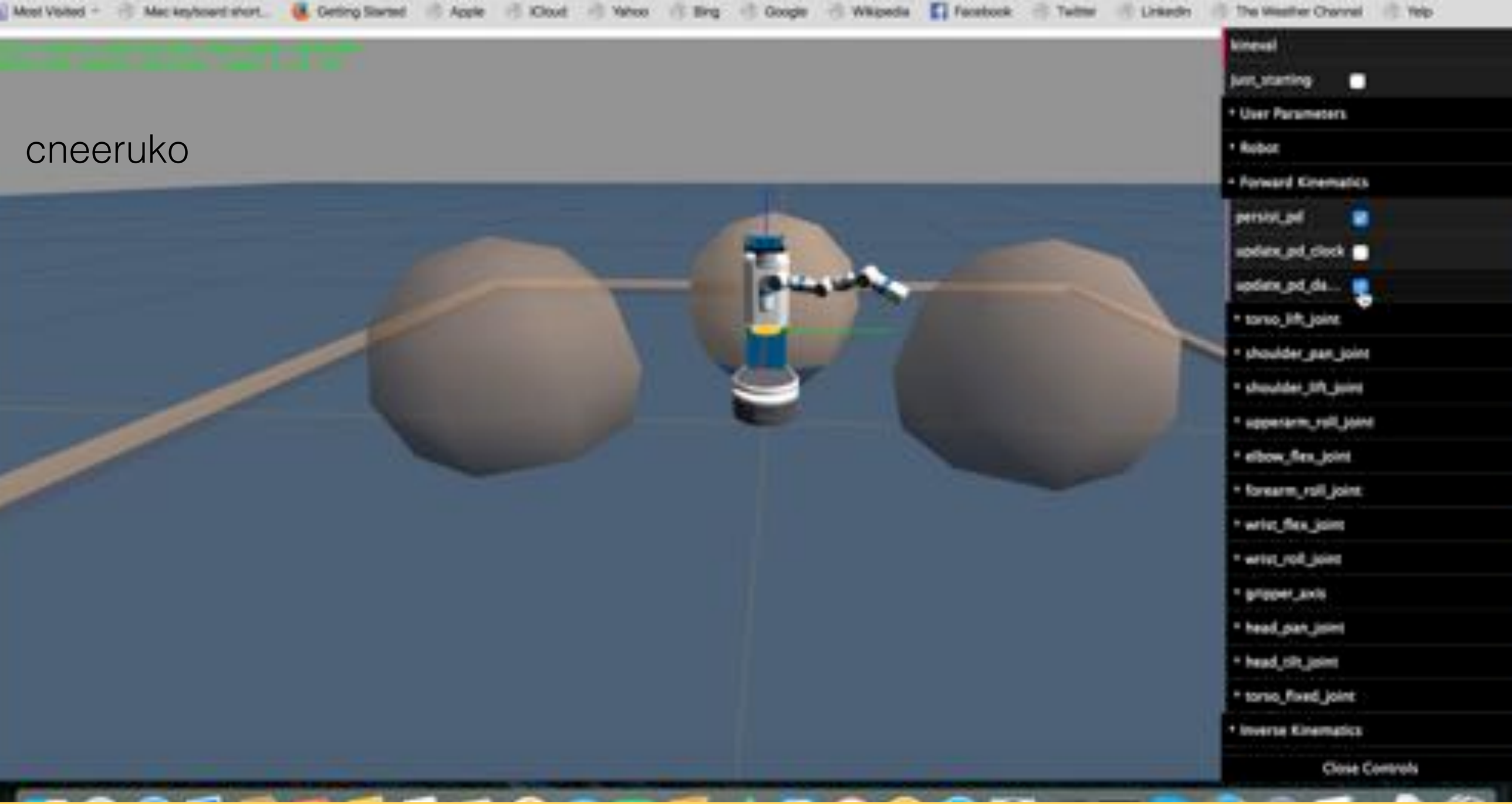

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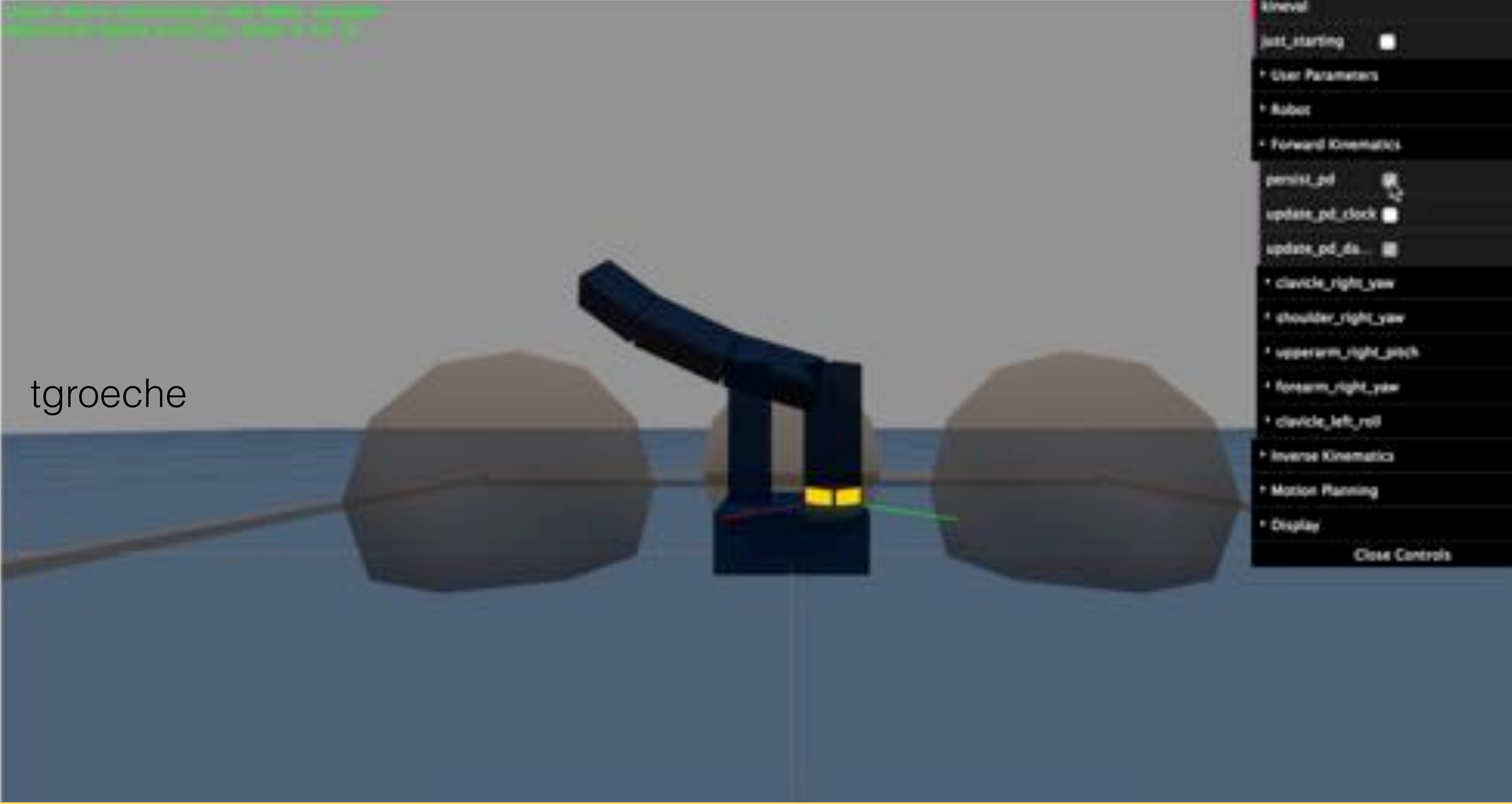

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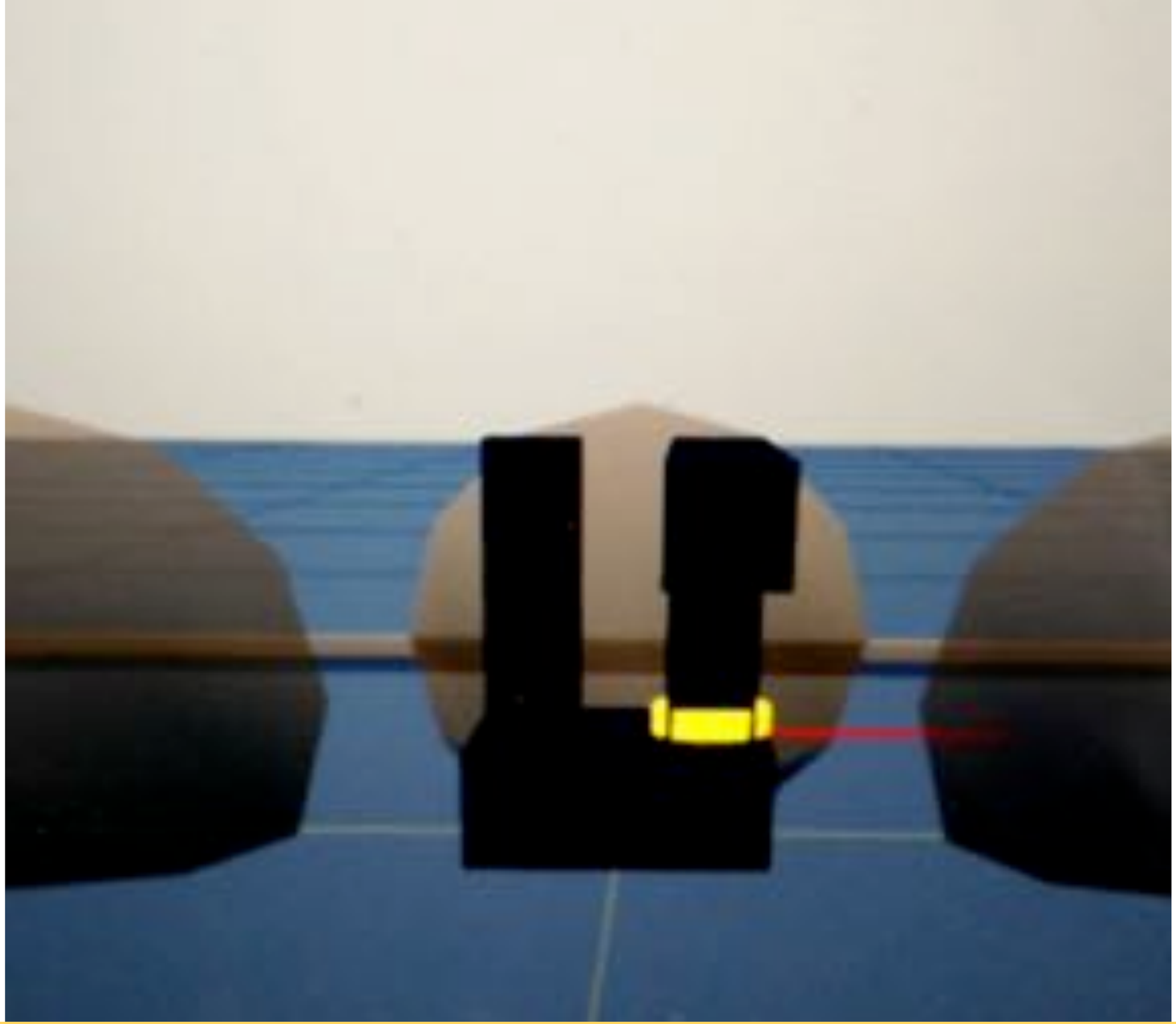
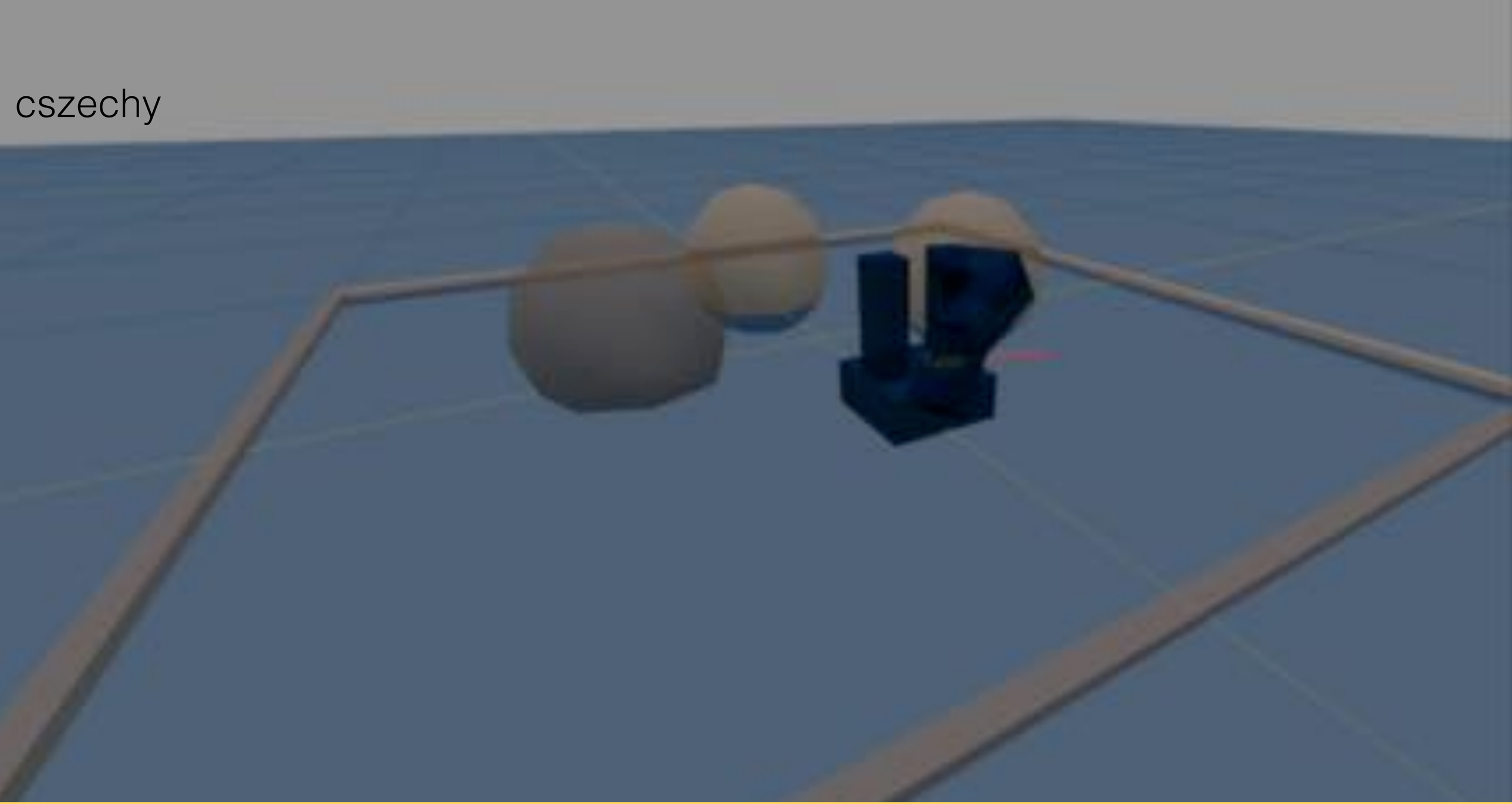


ankit

cszechy



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cszechy
ohseejay

Let’s generalize FSMs for robot control

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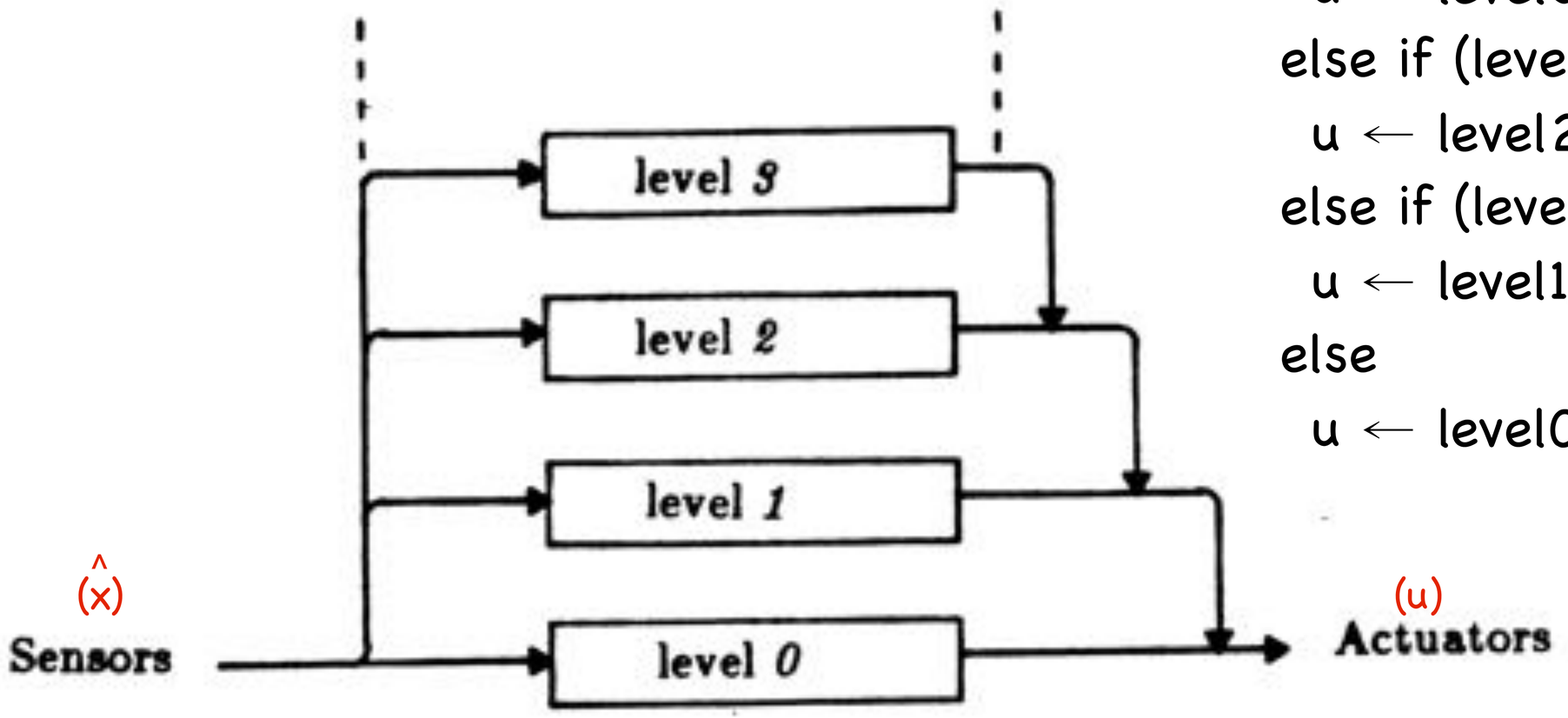
Subsumption Architecture

[Brooks 1986]

- Generalization of FSM-based control
- Collection of modular reactive controllers in a priority hierarchy
- Controllers can be FSMs
- Large nested if-else statement
- Most robots are controlled by some form of subsumption

Subsumption Architecture




```
if (level3_condition)
  u ← level3_control
else if (level2_condition)
  u ← level2_control
else if (level1_condition)
  u ← level1_control
else
  u ← level0_control
```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Subsumption Design Process

1. Divide your problem into basic competencies ordered simple to more complex. Designate a level for each basic competency.

2. Subdivide each level into multiple simple components that interact through shared variables. Limit the sharing of variables among levels to avoid incomprehensible code.

3. Implement each module as a separate light-weight thread. You might think of setting the priorities for these threads s.t. modules in a given level have the same priority.

4. Implement "arbitration" processes for suppression and inhibition as one or more separate that serve to control access to shared variables. You might want to control access using semaphores.

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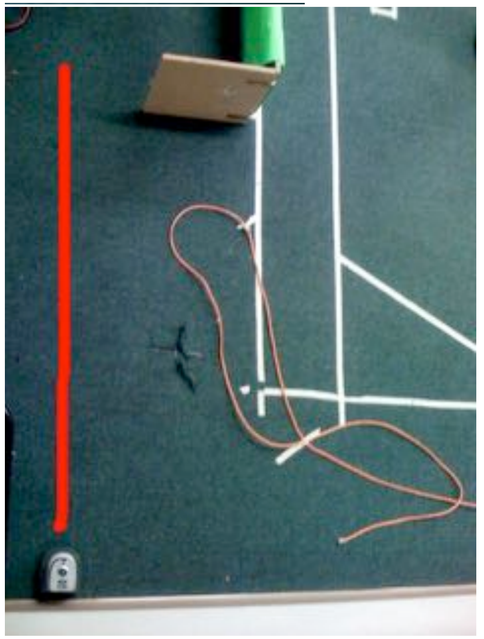
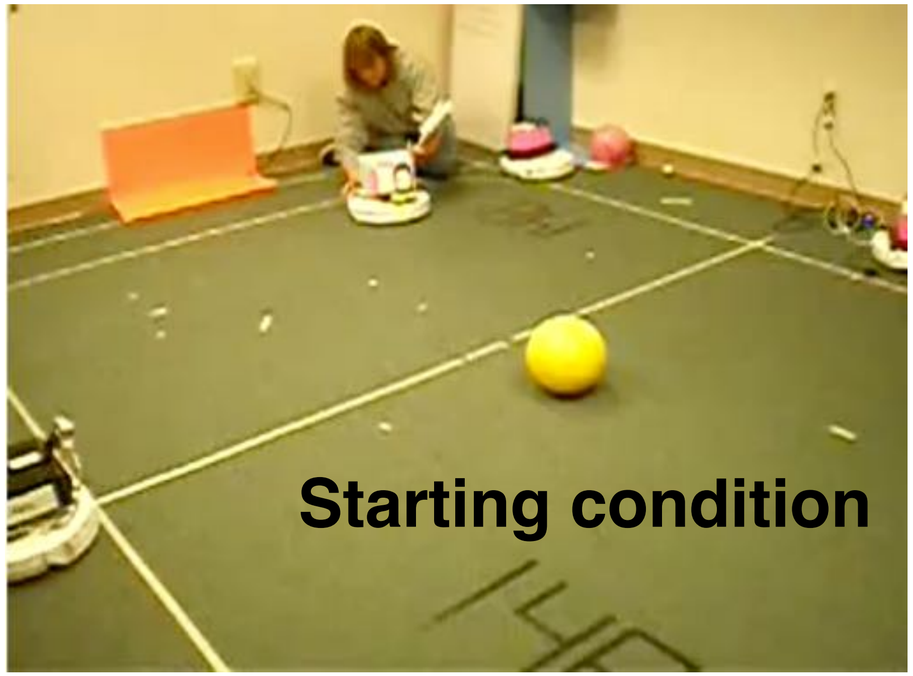
Subsumption for robot soccer

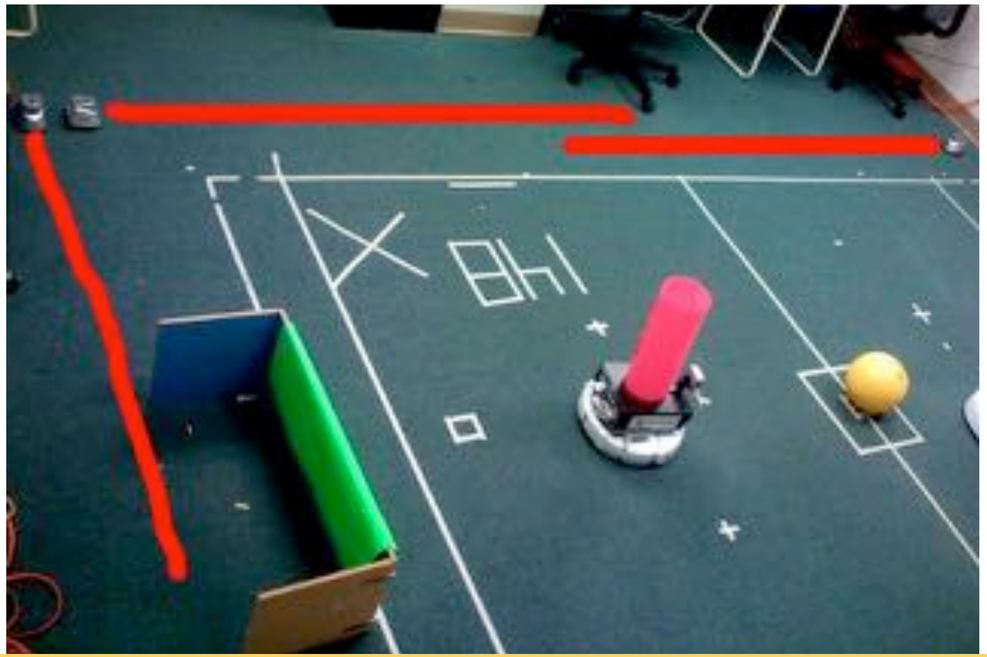
- Propose modules and priority?



What behavior will result?

1. Avoid IR Wall
2. Avoid Robot
3. Avoid Fiducial
4. Bumper Hit
5. Go To Opposite Goal
6. Go To Any Goal
7. Line Up On Ball
8. Go To Ball
9. Score Goal
10. At Ball
11. Look For Ball





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Snappy's Subsumption: Goal Scoring

1. Avoid IR Wall
2. Avoid Robot
3. Avoid Fiducial
4. Bumper Hit
5. Go To Opposite Goal
6. Go To Any Goal
7. Line Up On Ball
8. Go To Ball
9. Score Goal
10. At Ball
11. Look For Ball

Goal Scoring Challenge - Put ball on orange

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Snappy's Subsumption: Navigate to Ball

1. Avoid IR Wall
2. Avoid Robot
3. Avoid Fiducial
4. Bumper Hit
5. Go To Opposite Goal
6. Go To Any Goal
7. Line Up On Ball
8. Go To Ball
9. Score Goal
10. At Ball
11. Look For Ball

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Snappy in competition

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Are there other methods of decision making?

Types of Decision Making

- Deliberative (Planner-based) Control
  - "Think hard, act later."
- Reactive Control
  - "Don't think, (re)act."
- Hybrid Control
  - "Think and act separately & concurrently."
- Behavior-Based Control
  - "Think the way you act."

Next lecture:
Inverse Kinematics