

Probabilistic Robotics Course

INTRODUCTION

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- all emails you send us and concerning the course should have **[prob-rob]** as first string in the subject.

Teaching Material

- The primary source of information for the course is this web page

<https://sites.google.com/dis.uniroma1.it/probabilistic-robotics>

- The material

- Slides
- Source code for practicals

Is also available at the following repository

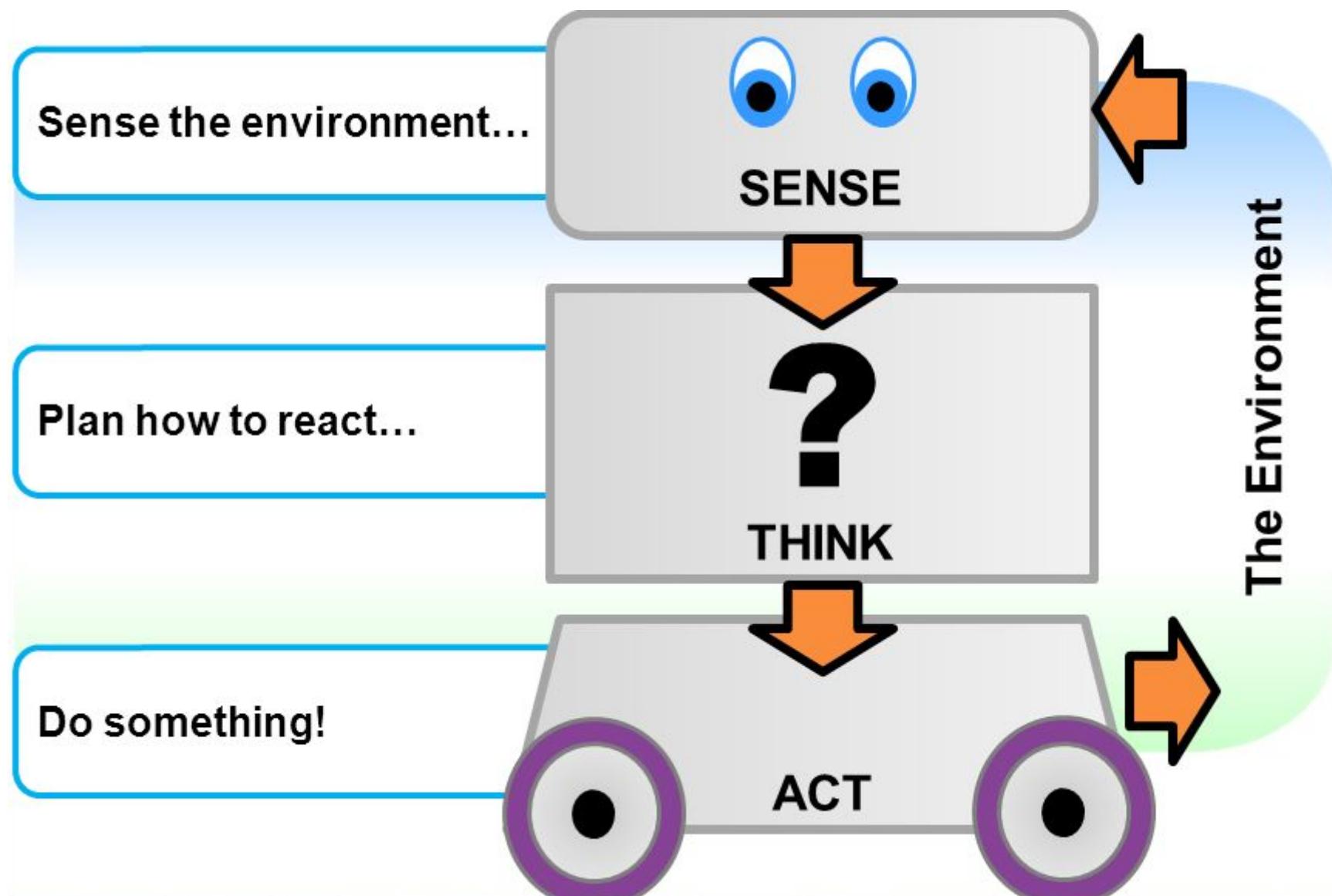
https://gitlab.com/grisetti/probabilistic_robotics_2016_17

Robots Have to Work



6:16:37 05/06/2015

Sense-Plan-Act



State in Robotics

Model of the world

- Geometry
- Traversability
- Other moving objects
- ...

Robot configuration

- Kinematics
- Dynamics
- State of batteries

...



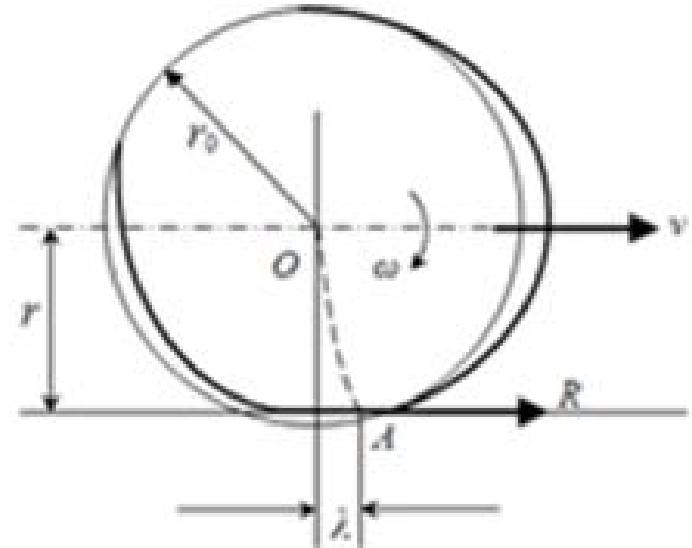
Probability and Robotics

The model of a system is typically an abstraction of a more complex real entity

Disturbances affect the measurements and the system

Measurement might be poorly informative

The predicted behavior different from the observed one



Probability and Robotics

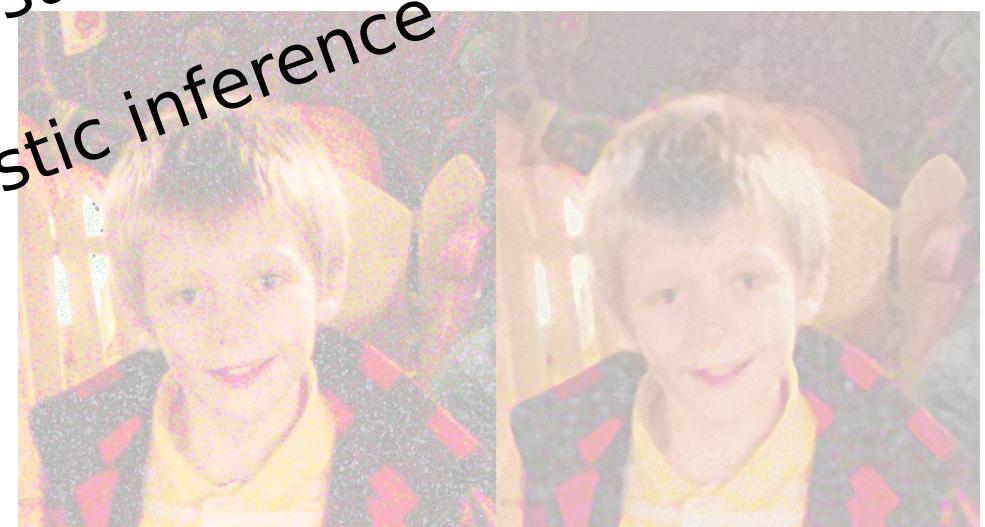
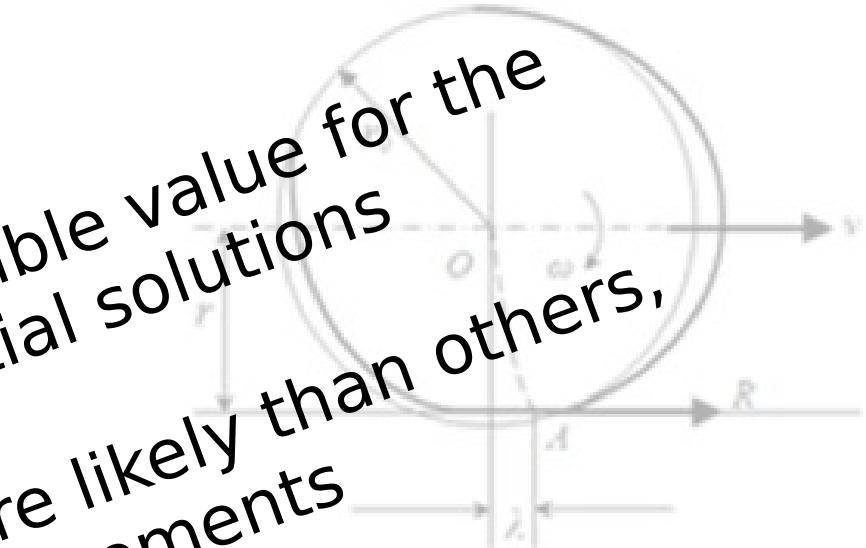
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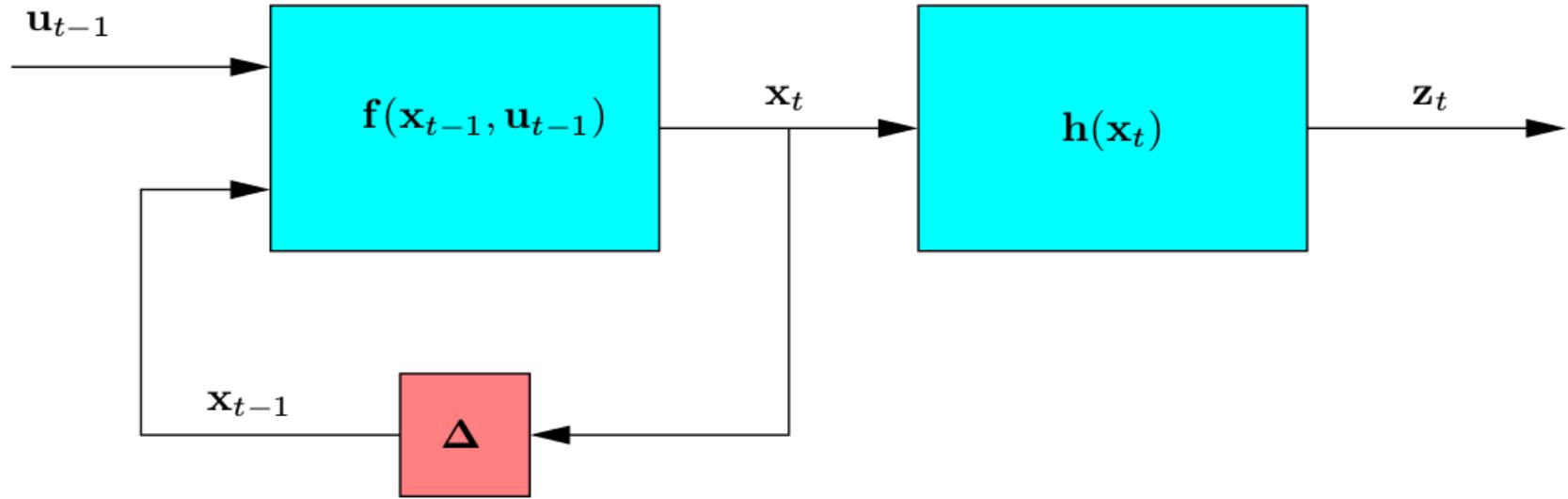
The predicted behavior different from the observed one

There is not a single possible value for the state, but a set of potential solutions



We will use probabilistic inference

System Model



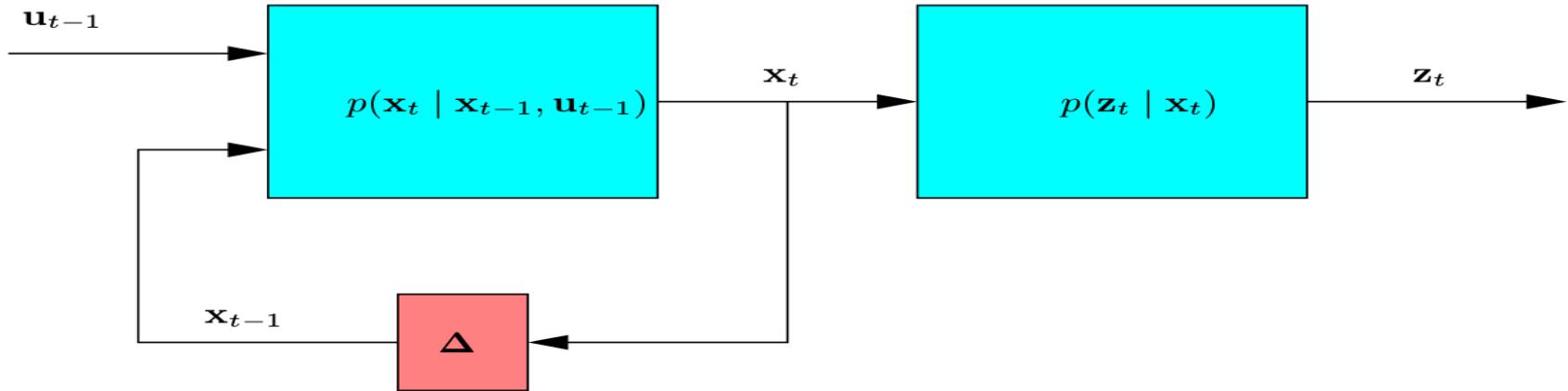
Notation:

- \mathbf{u} : controls
- \mathbf{x} : state
- \mathbf{z} : measurement
- \mathbf{f} : transition function
- \mathbf{h} : observation function

Perfect knowledge of

- inputs
- measurements
- transition model
- observation model

System Model



Probabilistic model

- The variables become stochastic (uncertain)
- The transition function is replaced by a transition model, that describes a conditional probability distribution over the next states as a function of the previous states
- The observation function is replaced by a conditional probability describing the distribution of possible observations as a function of the current state
- If no uncertainty is present the probabilistic models degenerates to the deterministic model

What will I learn?

Tools

- Filtering tools
 - Discrete
 - Gaussian
 - Particle
- Maximum Likelihood Estimation
 - Gauss-Newton
 - Sparse Least Squares
- Data Association
 - Greedy
 - Voting Schemes
 - Spectral Methods

Applications

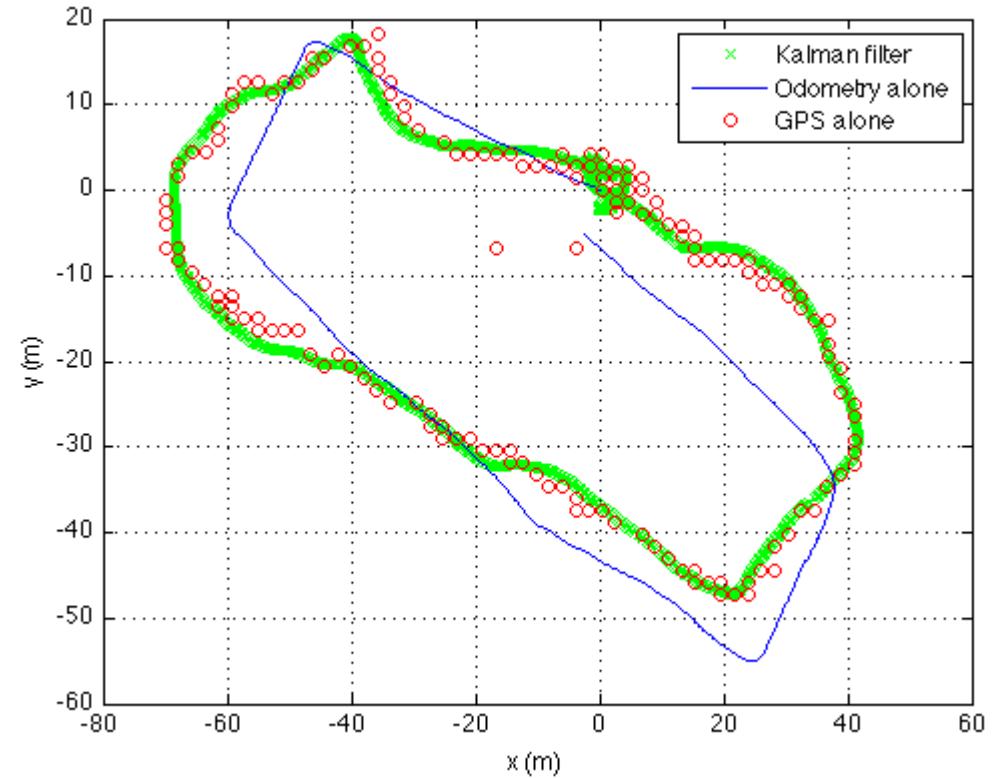
- Calibration
- Tracking
- Localization
- Mapping
- SLAM

Filtering

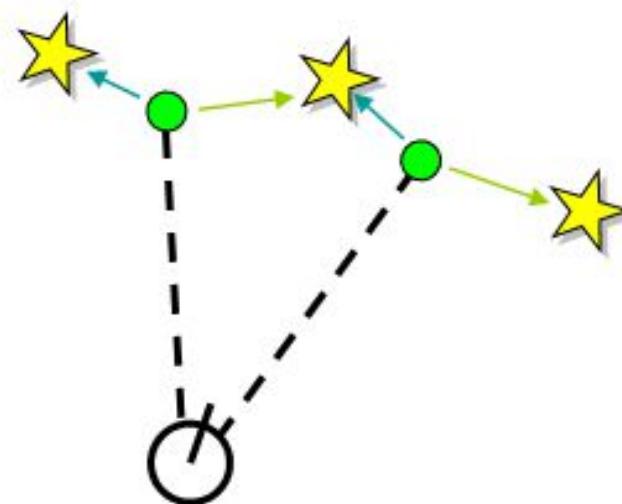
Filtering is the process of estimating the distribution over the possible **current** states of a dynamic

In doing so we have access to

- the controls
- the measurements



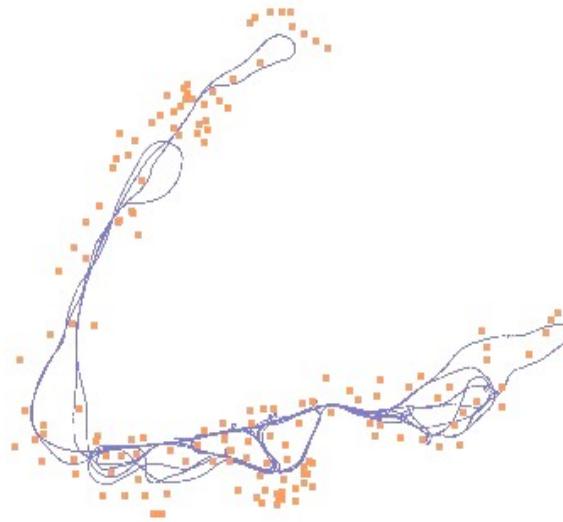
Data Association



Determine which state variable (if any) is responsible of a measurement, based on:

- the current estimate of the state
- the history of measurements

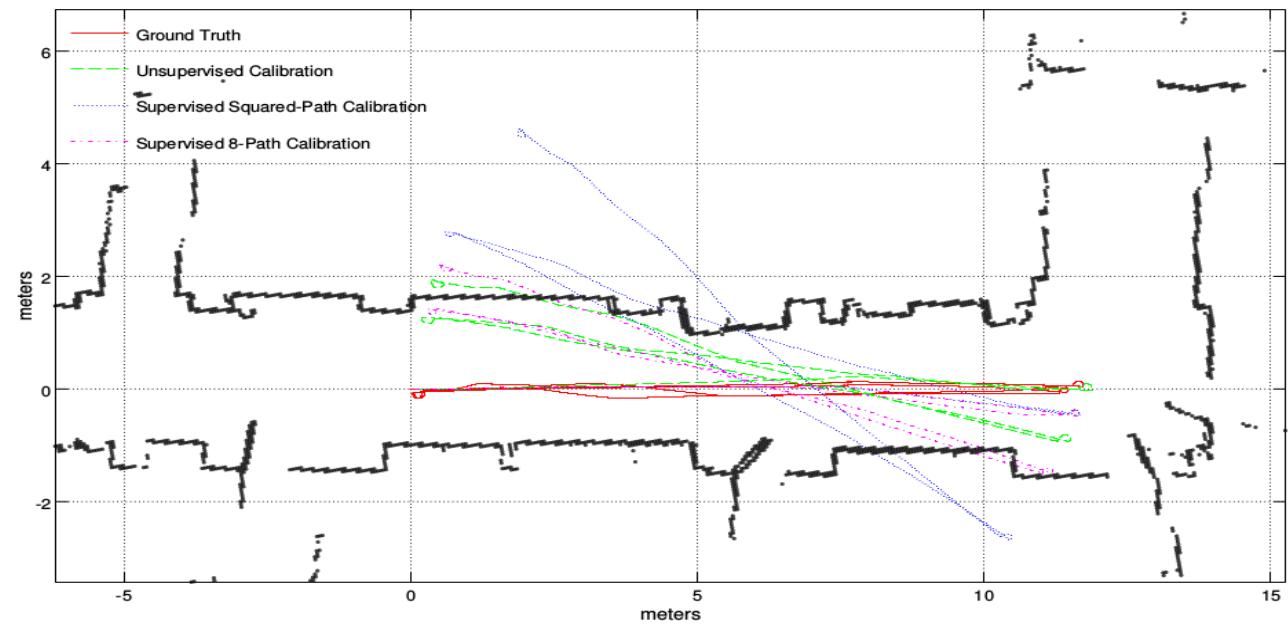
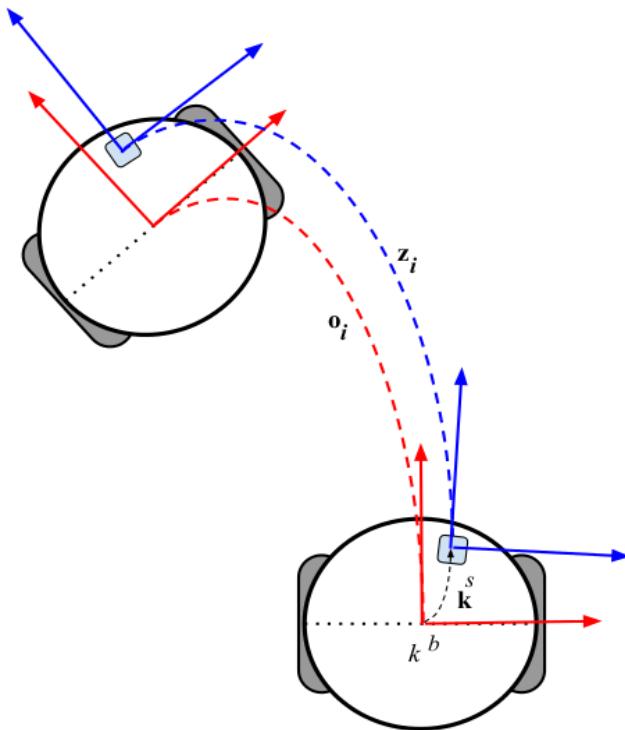
Maximum Likelihood Estimation



Estimate the most likely trajectory of the system's state given all measurement so far

In case of stationary system, the trajectory degenerates to a single state

Calibration



Determining the kinematic parameters of a robotic system given

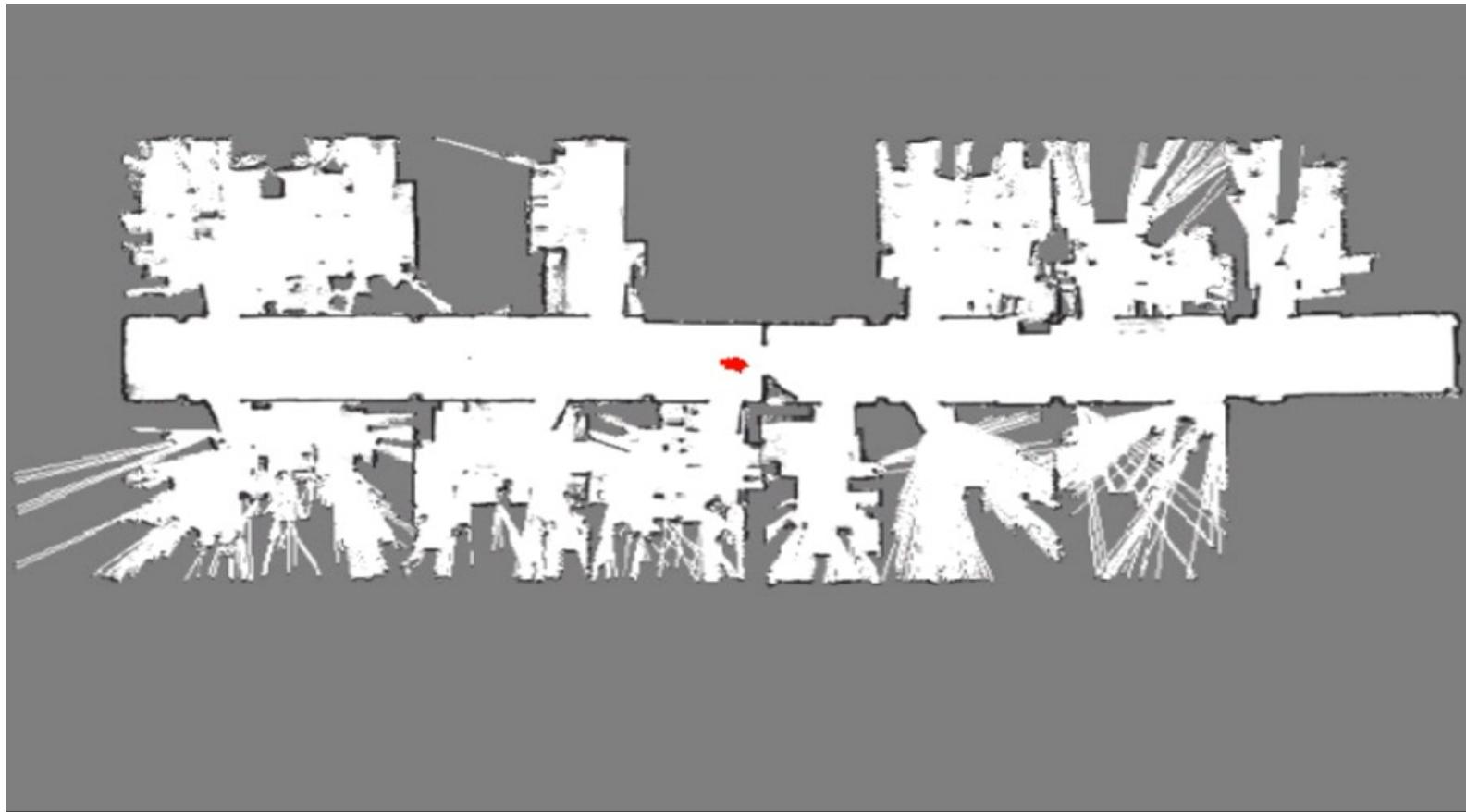
- trajectory of the sensors (externally measured)
- encoder readings

Tracking



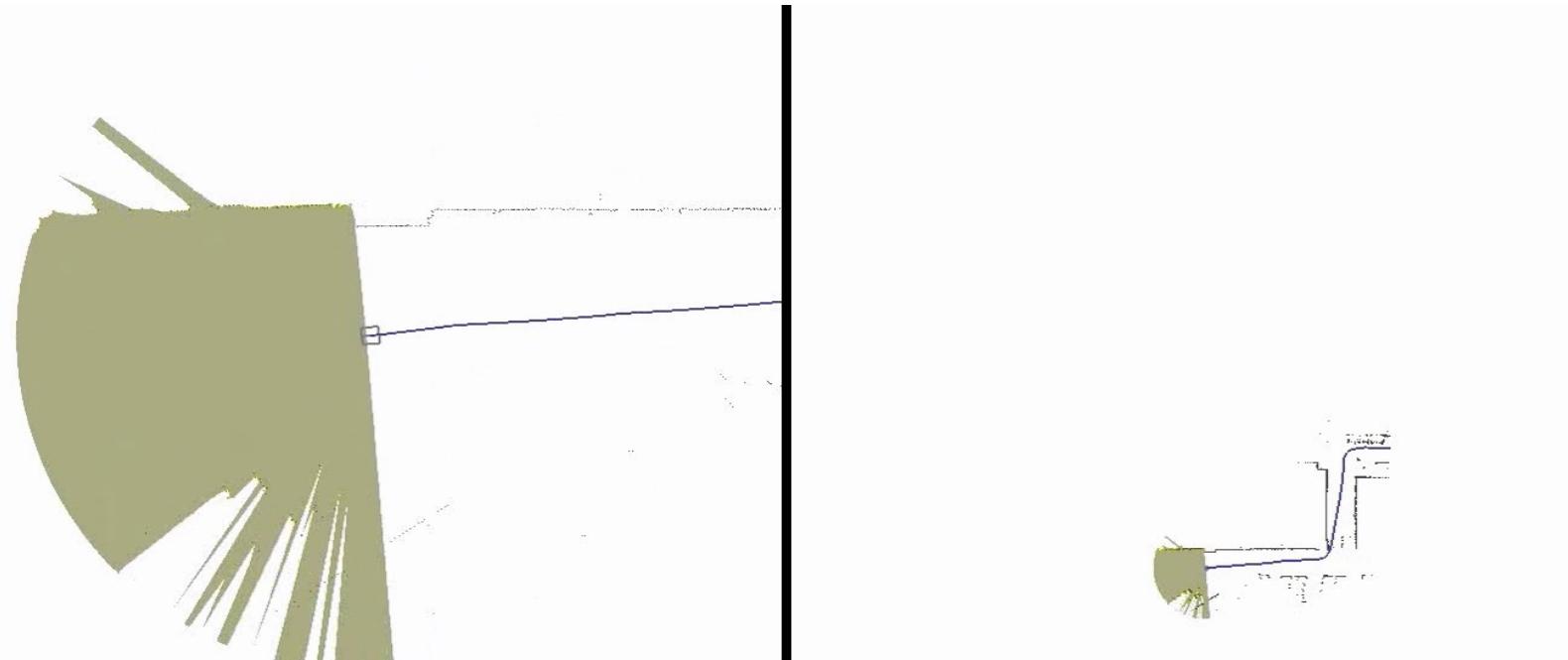
Track the position of a moving sensor by estimating the motion between the previous and the current views

Localization



- Determining the current position of a robot, given
 - The knowledge of the map
 - All sensor measurements up to the current time

SLAM



Determine the robot position AND the map,
based on the sensor measurements

Tools

- Linux (ubuntu)
- c/c++ (gcc)
- g2o (<https://github.com/RainerKuemmerle/g2o>)
- ROS (www.ros.org)
- Octave (sudo apt-get install octave)
- VREP (<http://www.coppeliarobotics.com/index.html>)

Exam

- An individual project
- Oral exam (with written exercises)
- Note
 - The students that already gave LAS or the elective in SLAM (but not both of them) might take the exam in probabilistic robotics
 - For these students there will be an extended part of the program, to be discussed with the teacher