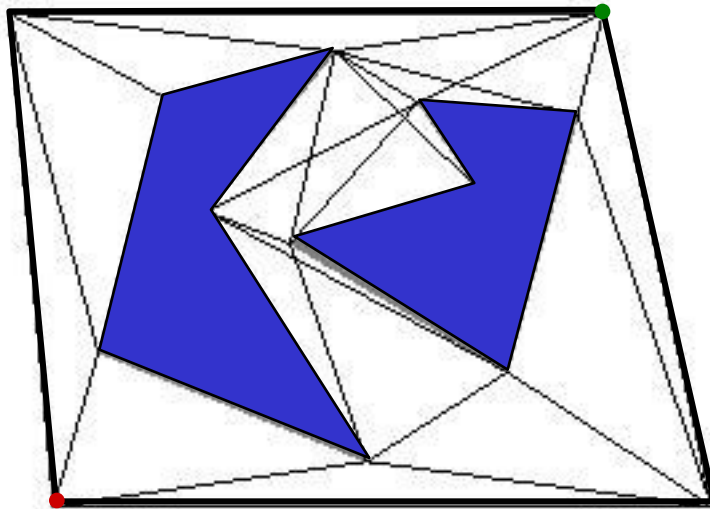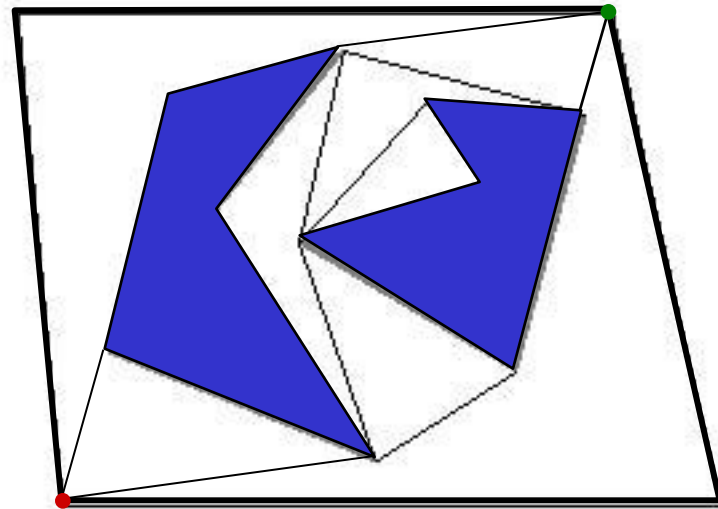# Roadmaps

Vertex Visibility Graph
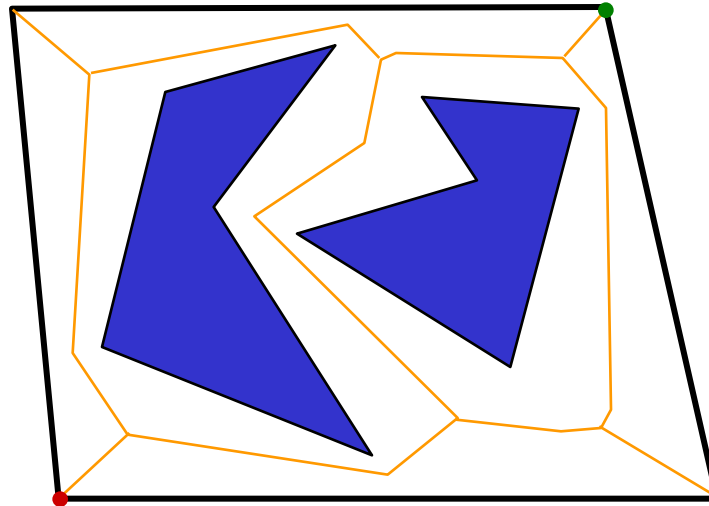

Full visibility graph

Reduced visibility graph, i.e., not including segments that extend into obstacles on either side.
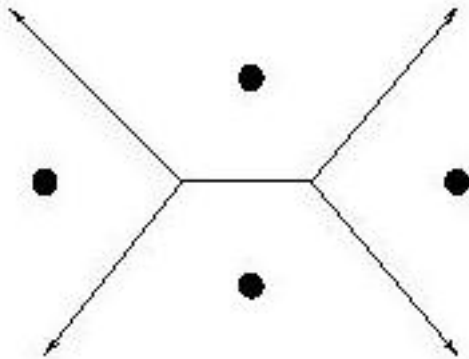
(but keeping endpoints' roads)

what else might we do ?
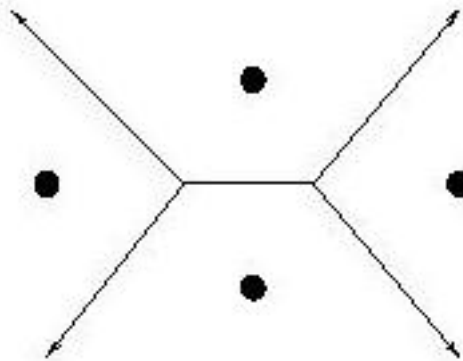
An alternative roadmap

Voronoi diagrams

These line segments make up
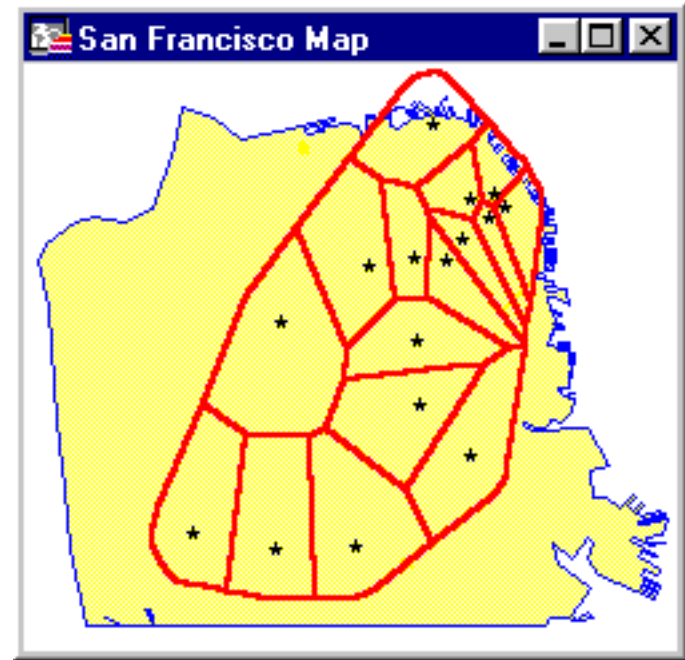the **Voronoi diagram** for the
four points shown here.

Solves the "Post Office Problem"
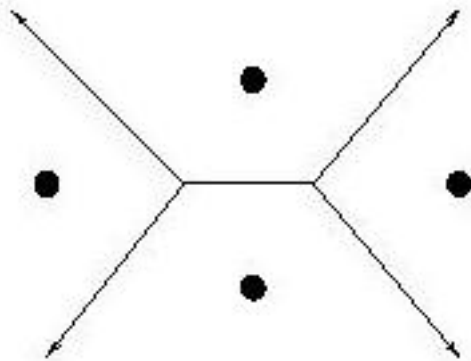
Voronoi diagrams

These line segments make up the **Voronoi diagram** for the four points shown here.

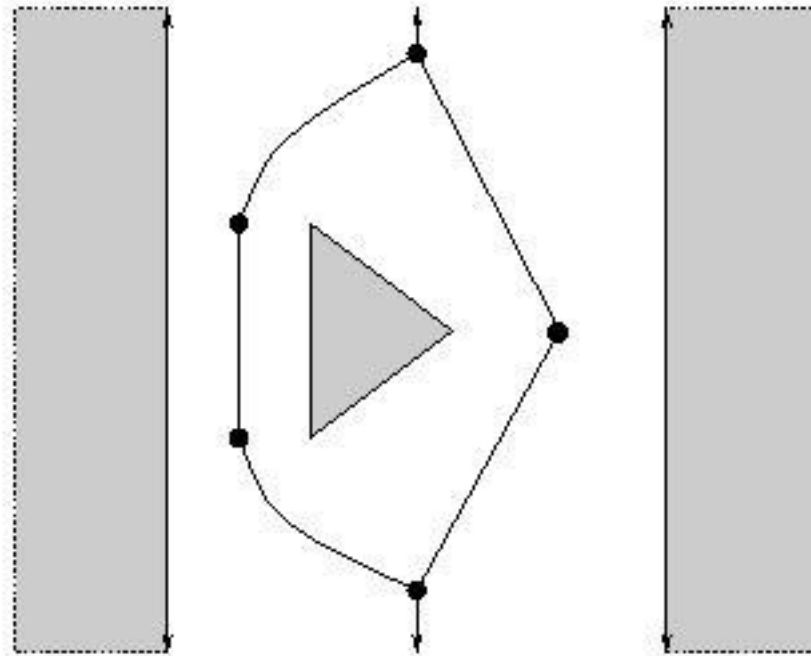Solves the "Post Office Problem"

or, perhaps, more important problems...

Voronoi diagrams
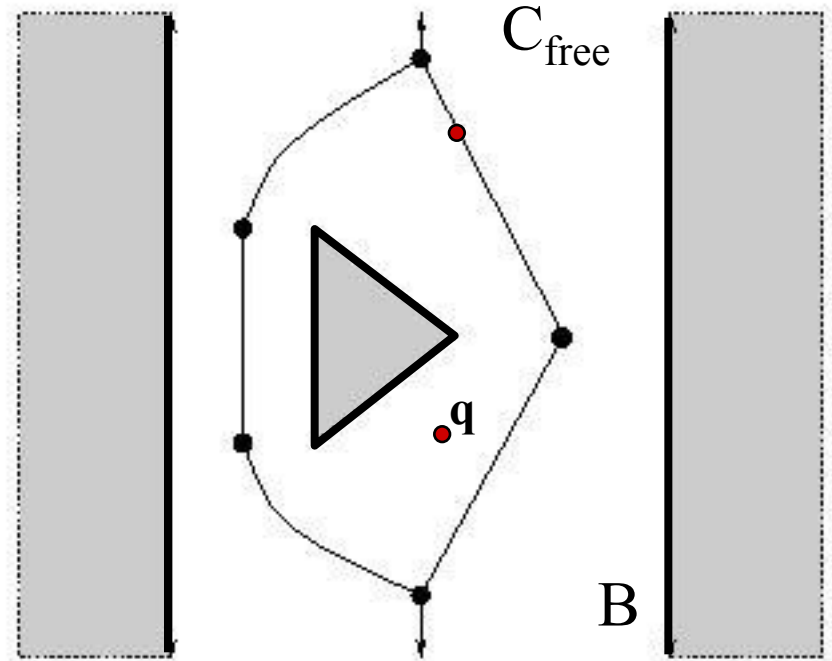
"true" Voronoi diagram

(isolates a set of points)

generalized Voronoi diagram

What is it?

Voronoi diagrams

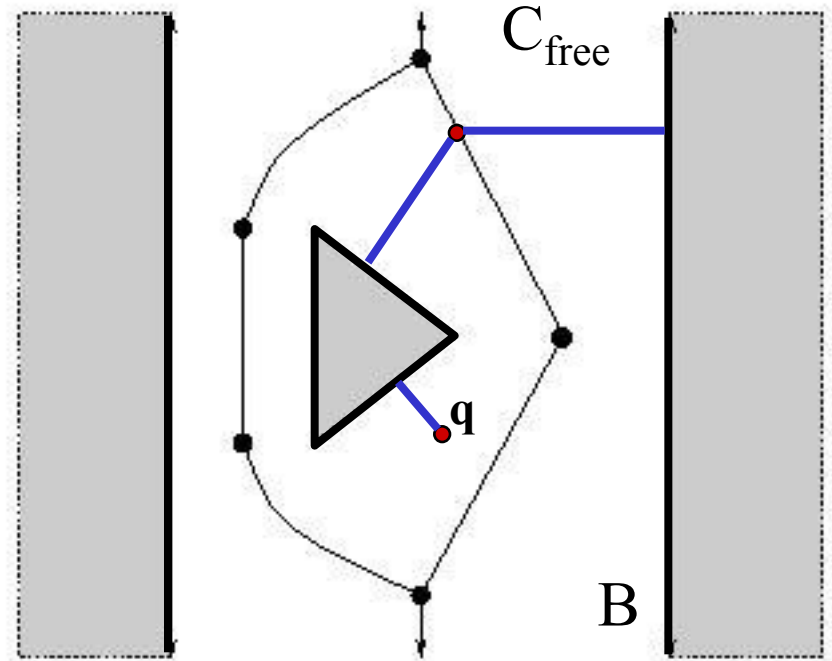

C_{free}

B

Let B = the boundary of C_{free} .

Let **q** be a point in C_{free} . (•)

Voronoi diagrams

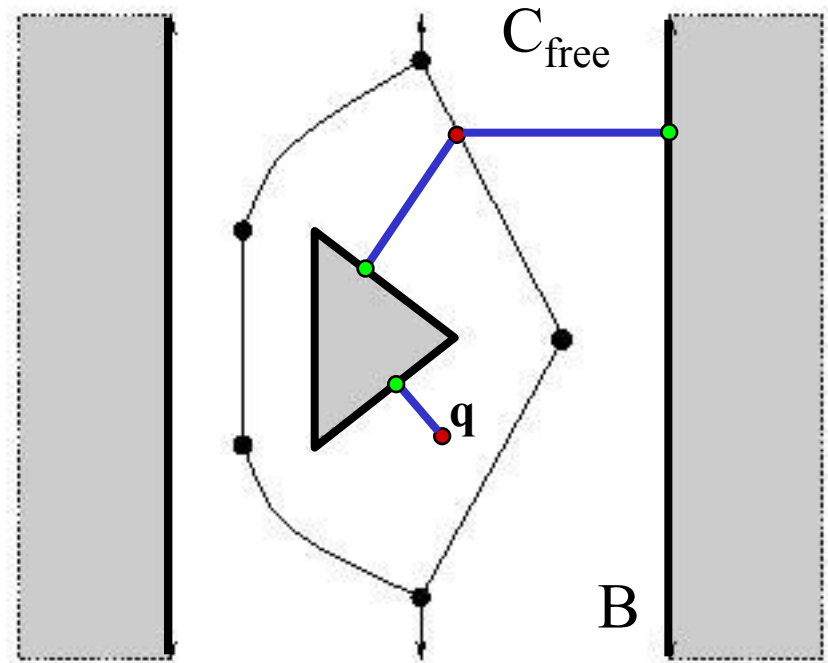Let B = the boundary of C_{free} .

Let **q** be a point in C_{free} .

Define *clearance*(q) = min { | q - p | }, for all p ∈ B

Voronoi diagrams

Let B = the boundary of C_{free} .

Let **q** be a point in C_{free} .

Define *clearance*(q) = min { | q - p | }, for all p ∈ B

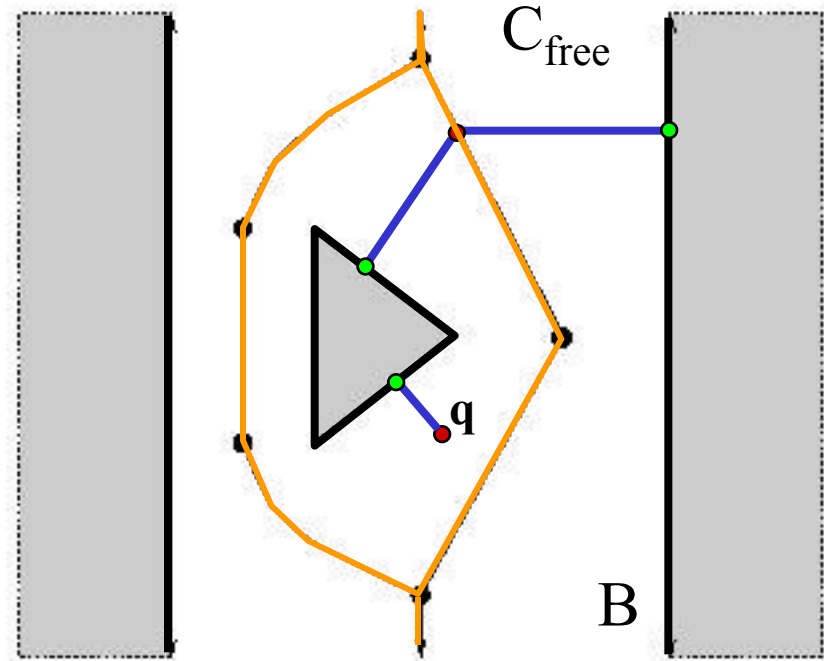Define *near*(q) = { p ∈ B such that | q - p | = *clearance*(q) }

Voronoi diagrams

Evaluation

+ maximizes distance from obstacles

+ reduces to graph search

+ can be used in higher-dimensions

- nonoptimal

- real diagrams tend to be noisy

C_{free}

B

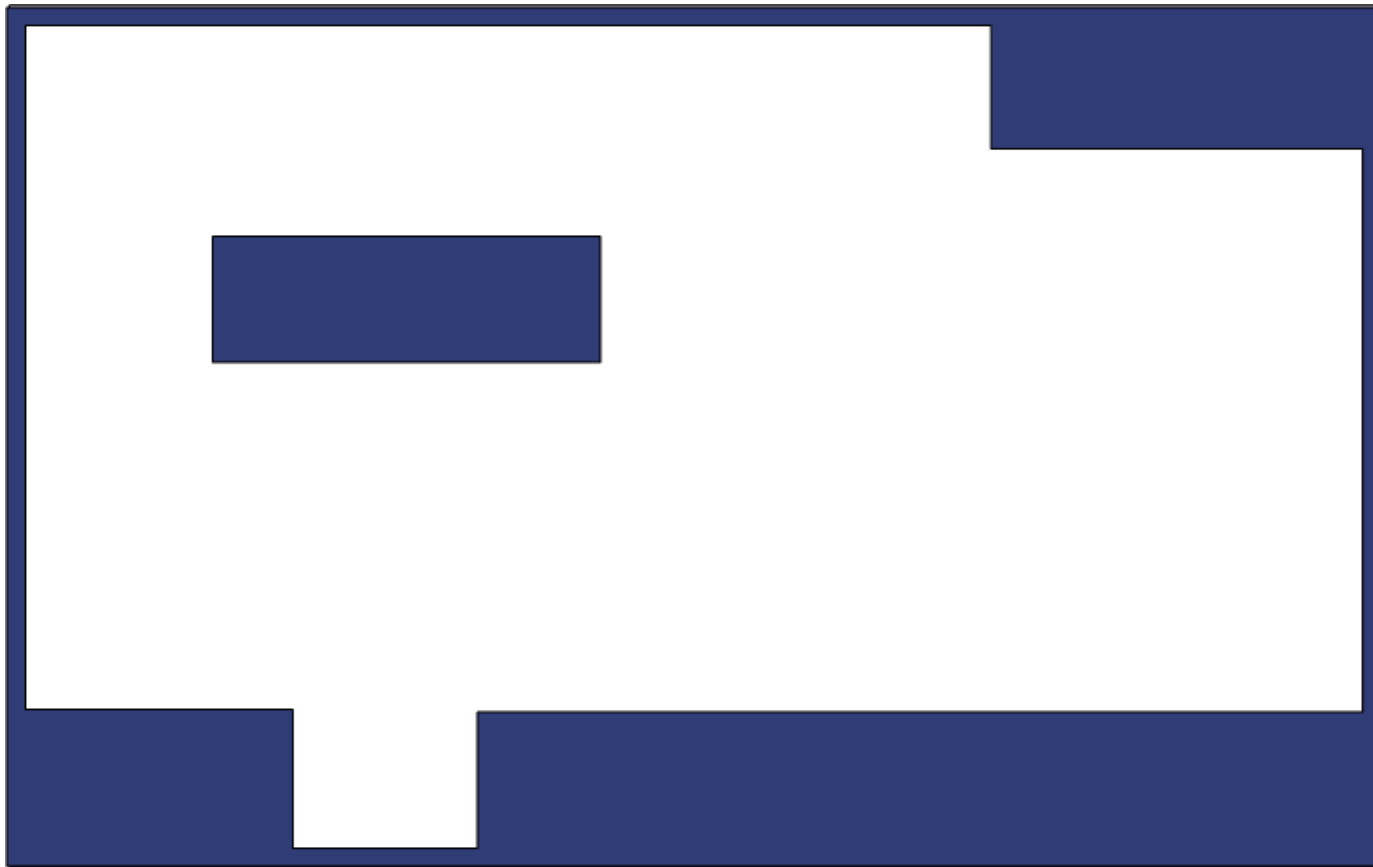Let B = the boundary of C_{free} .

Let **q** be a point in C_{free} .

Define *clearance*(q) = min { | q - p | }, for all p $\in$ B

Define *near*(q) = { p $\in$ B such that | q - p | = *clearance*(q) }

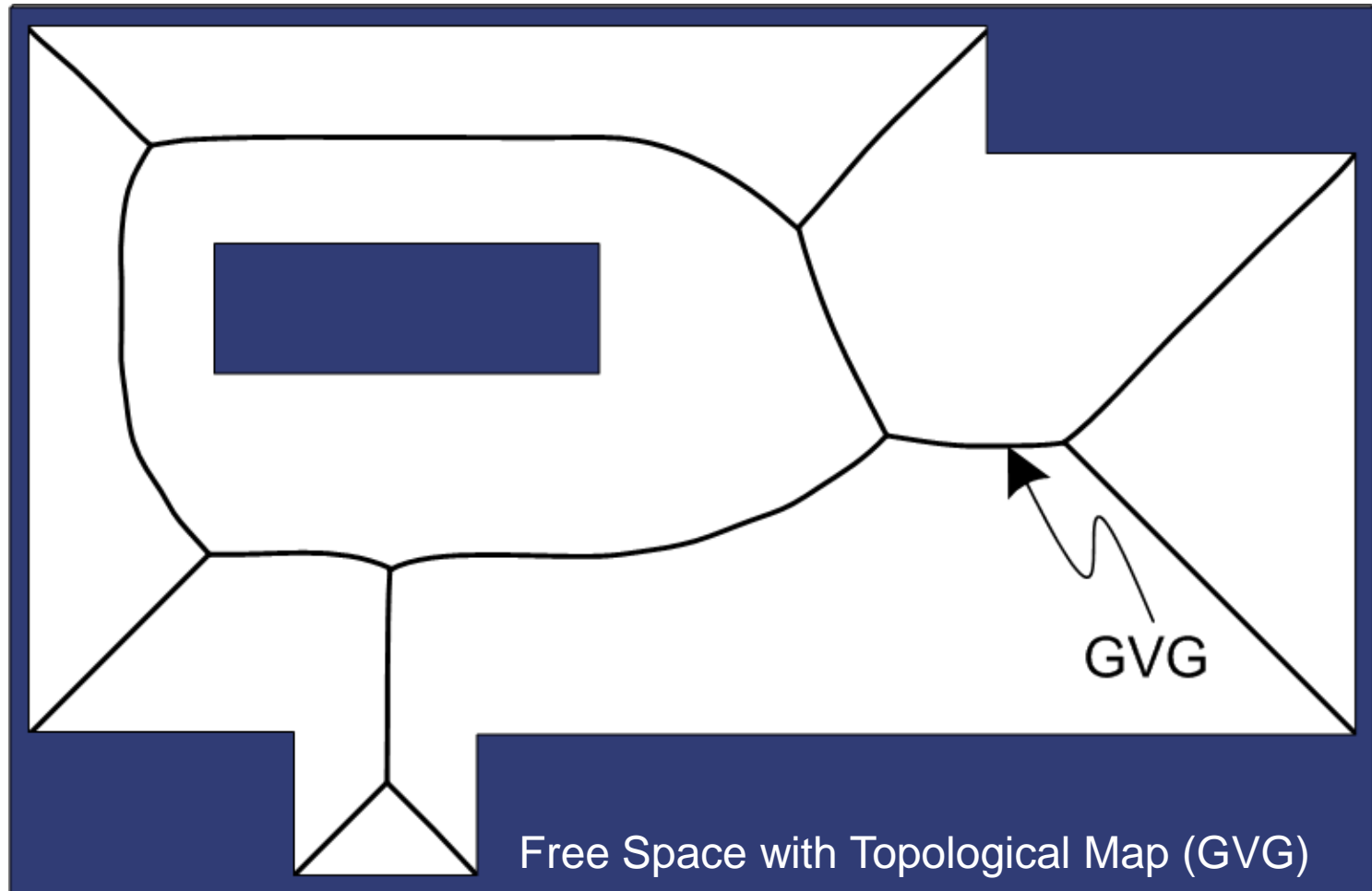q is in the *Voronoi diagram* of C_{free} if | *near*(q) | > 1

number of
set elements

Generalized Voronoi Graph (GVG)

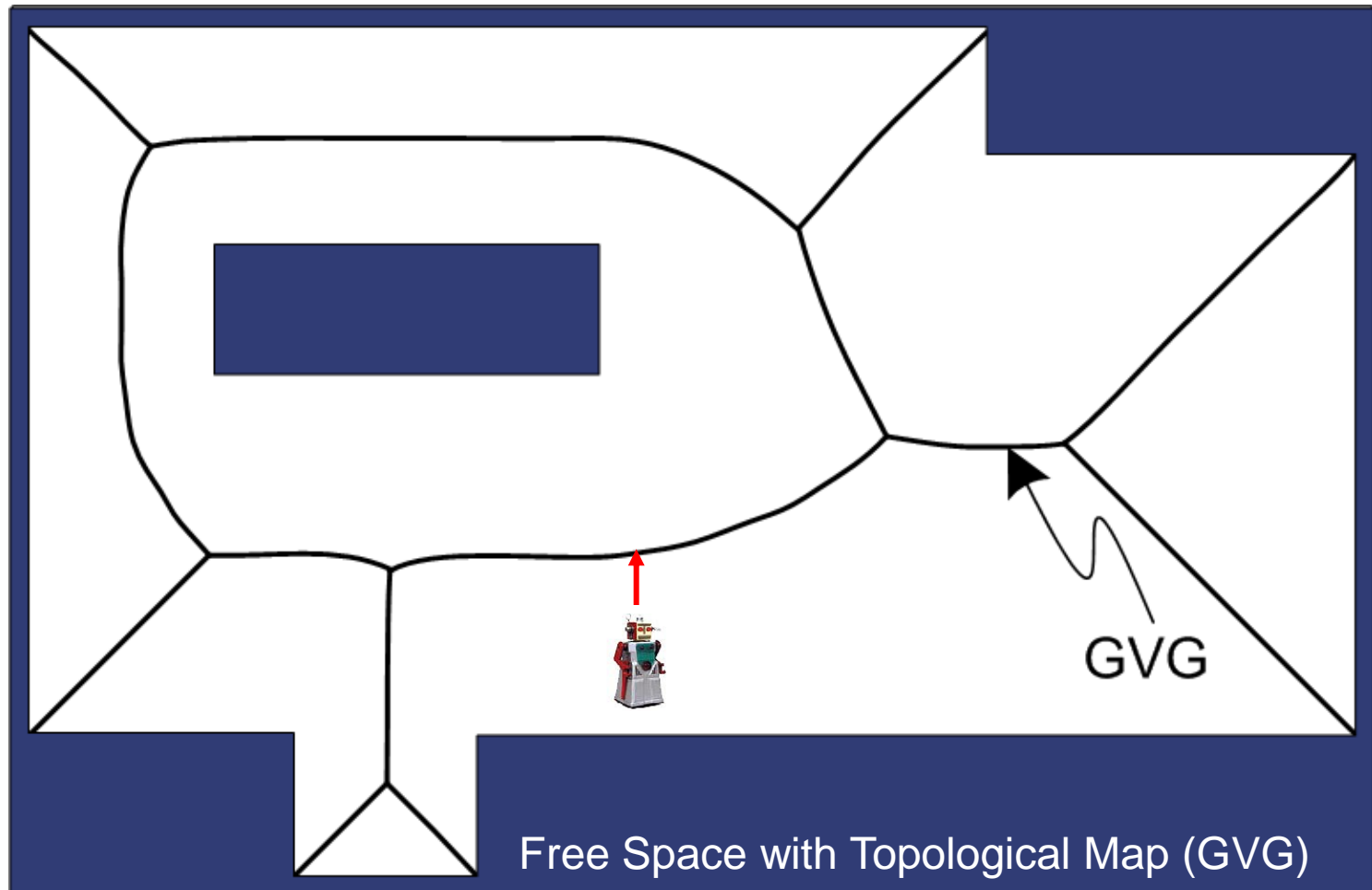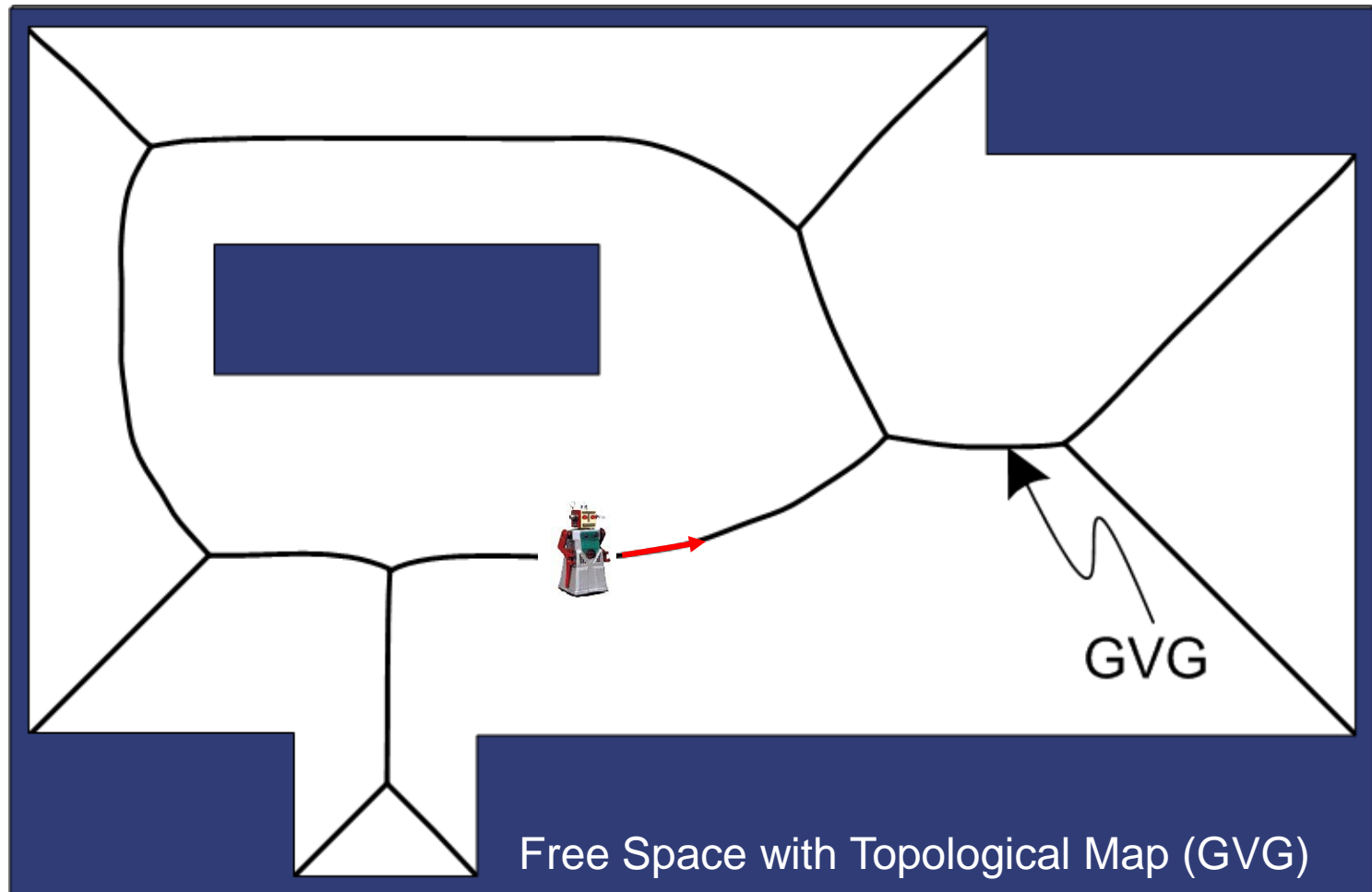# Generalized Voronoi Graph (GVG)

Free Space with Topological Map (GVG)

Generalized Voronoi Graph (GVG)

- Access GVG

Free Space with Topological Map (GVG)

Generalized Voronoi Graph (GVG)

- Access GVG
- Follow Edge

Free Space with Topological Map (GVG)

GVG

Generalized Voronoi Graph (GVG)

- Access GVG
- Home to the MeetPoint
- Follow Edge

GVG

Free Space with Topological Map (GVG)

Generalized Voronoi Graph (GVG)

- Access GVG
- Follow Edge
- Home to the MeetPoint
- Select Edge

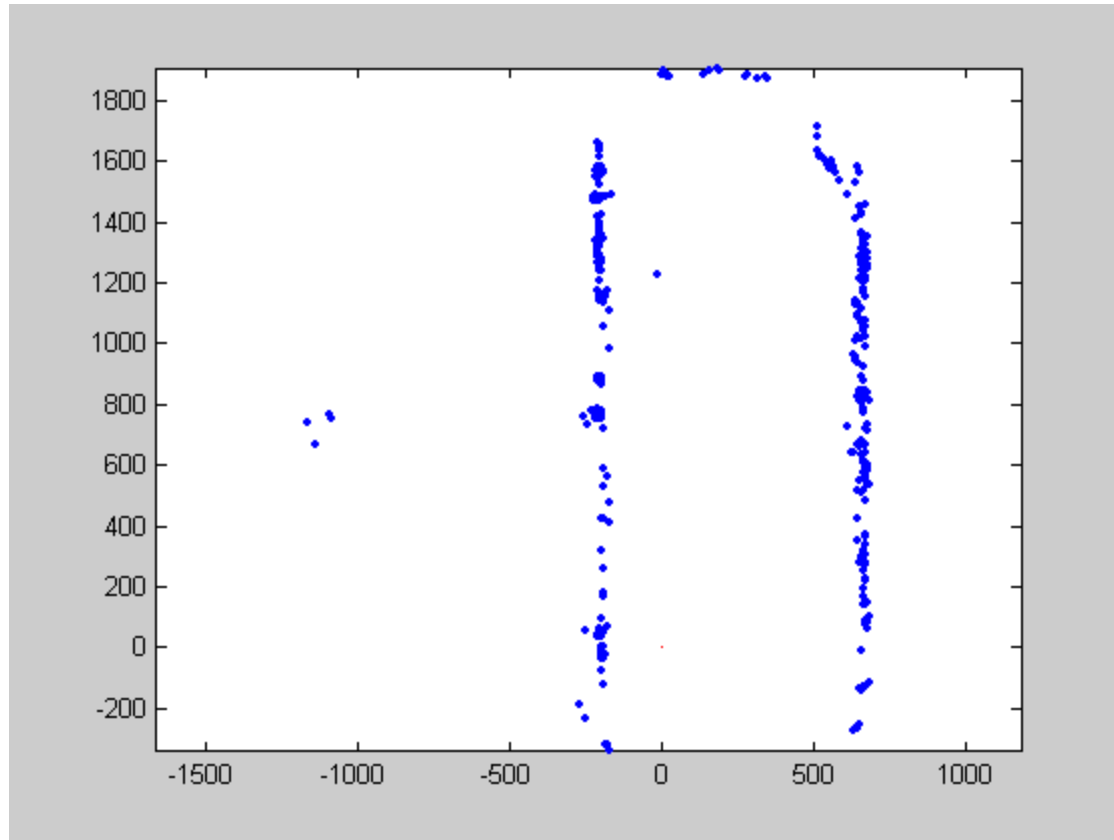Free Space with Topological Map (GVG)
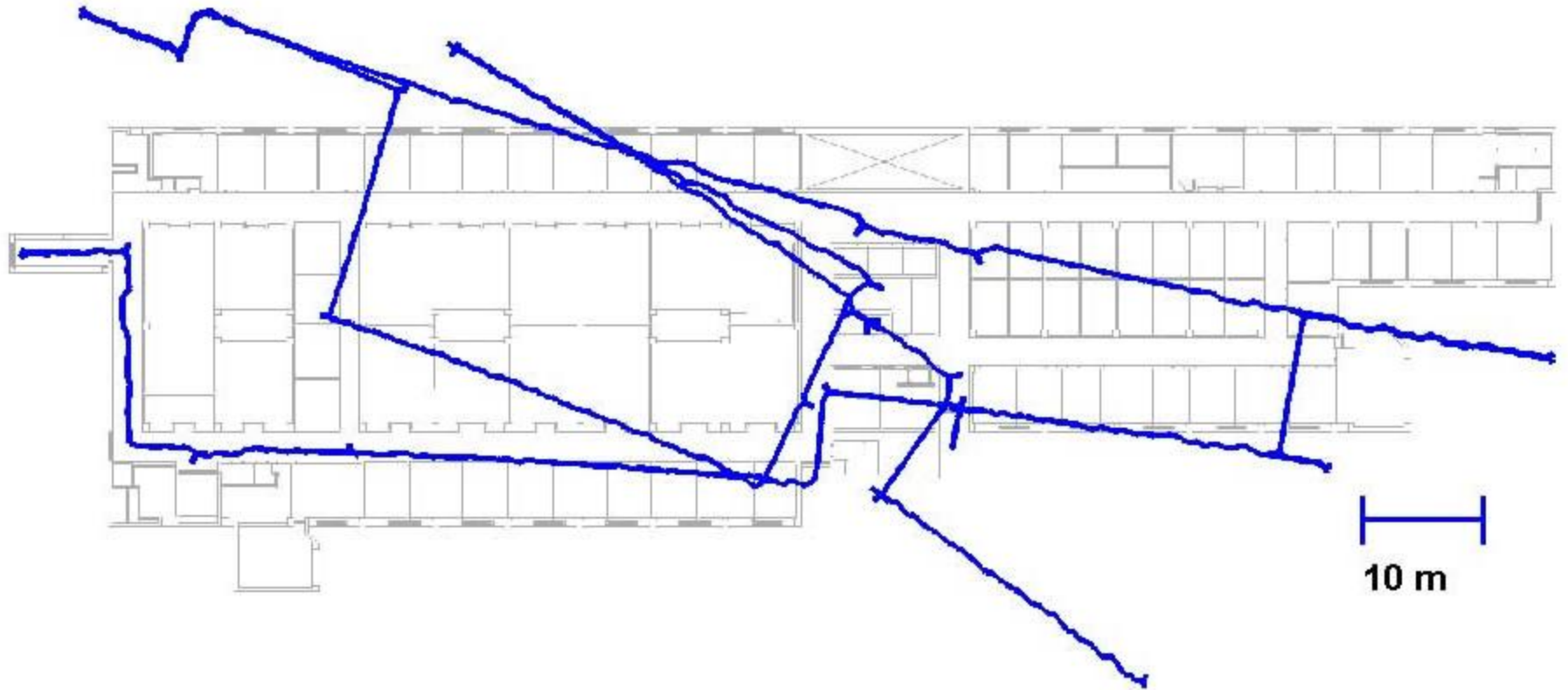
GVG
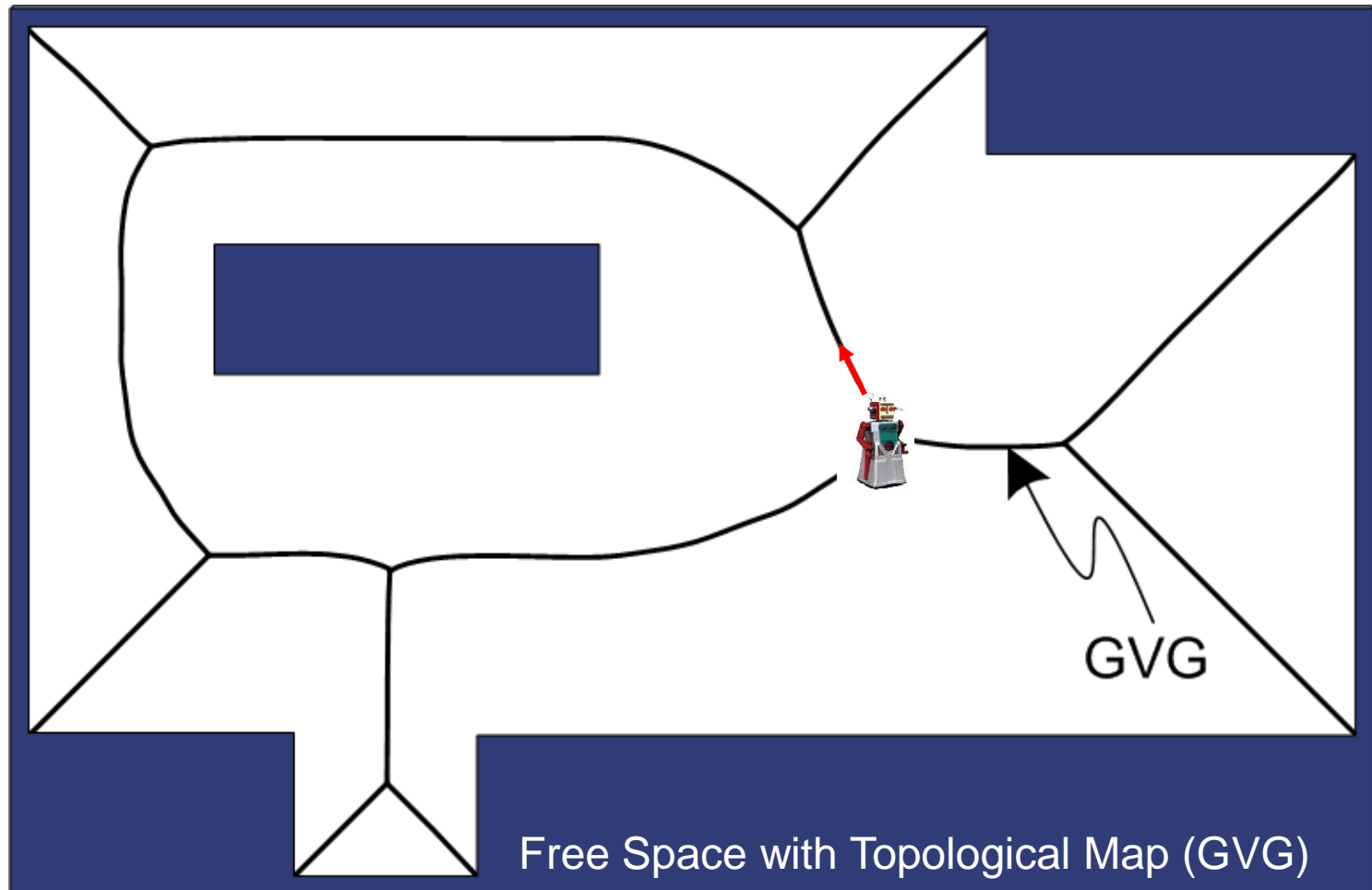
GVG construction using sonar

- Nomadic Scout

- Sonar (GVG navigation)

- Camera with omni-directional mirror (feature detection)

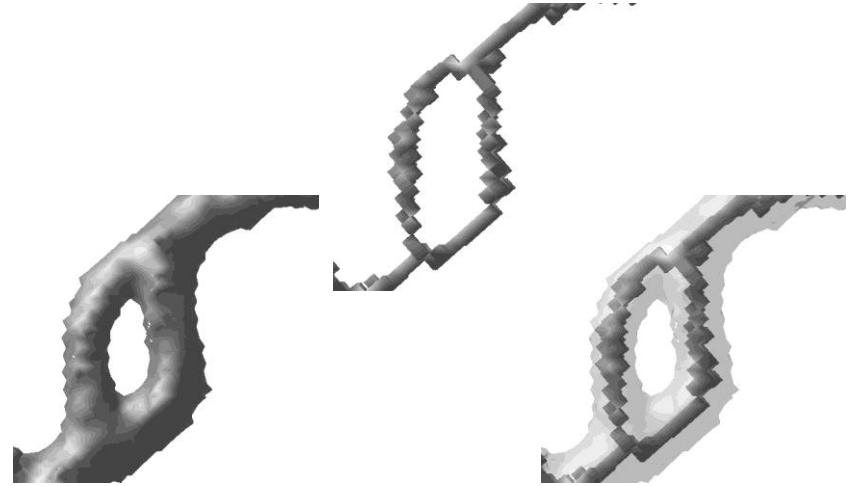- Onboard 1.2 GHz processor
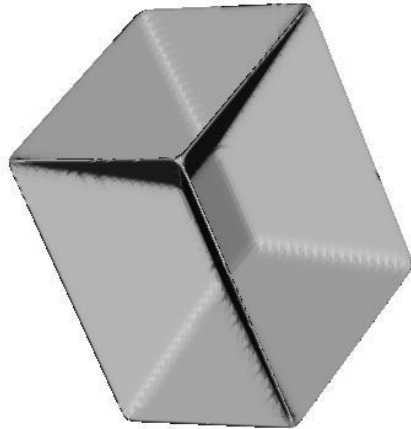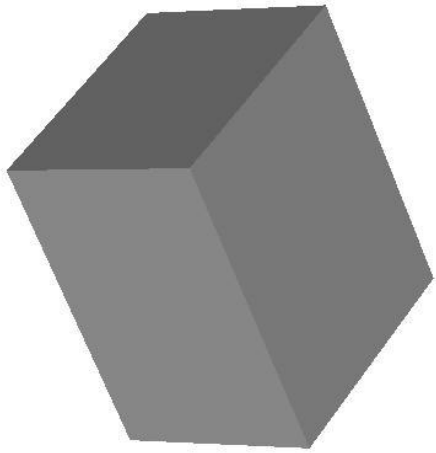
GVG construction using sonar

GVG construction using sonar
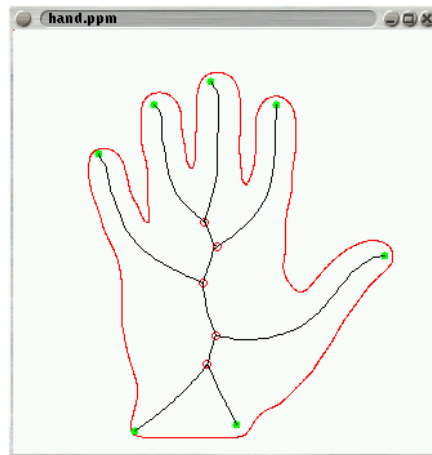

10 m

Slammer in Action

Voronoi applications
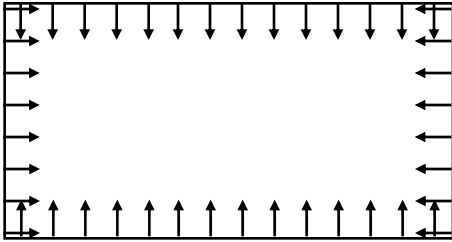

A retraction of a 3d object
== "*medial surface*"

what?

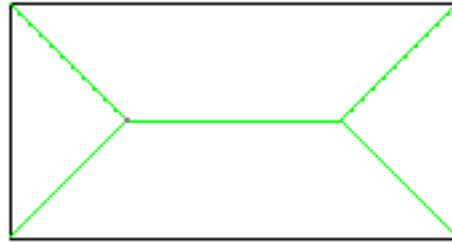Skeletonizations resulting from
constant-speed curve evolution

hand.ppm

in 2d, it's called
a *medial axis*

skeleton ⟷ shape

curve evolution   where wavefronts collide   centers of maximal disks

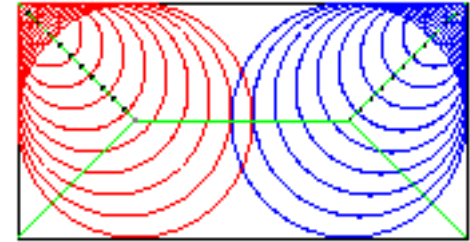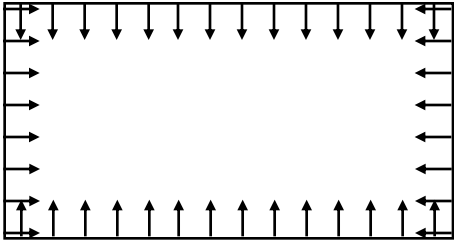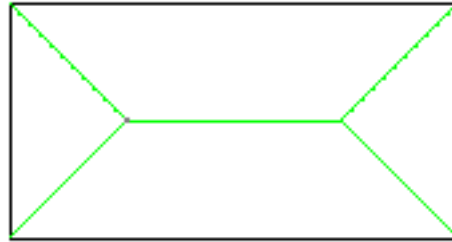again reduces a 2d (or higher) problem to a question about graphs...

skeleton ↤ shape

curve evolution

where wavefronts collide

centers of maximal disks

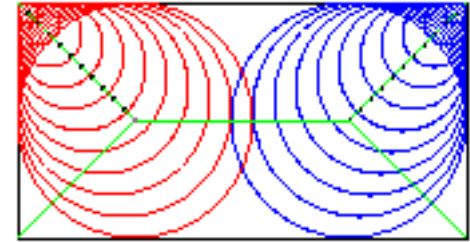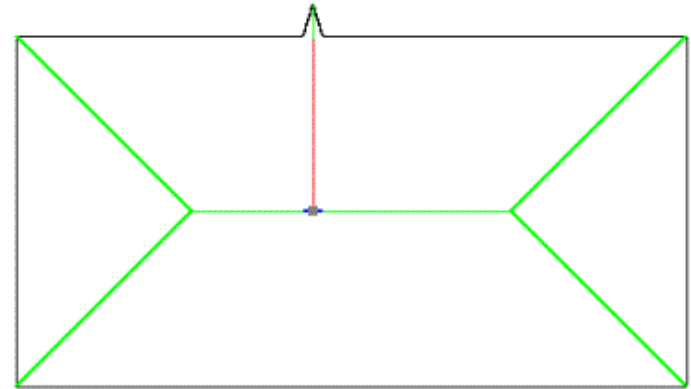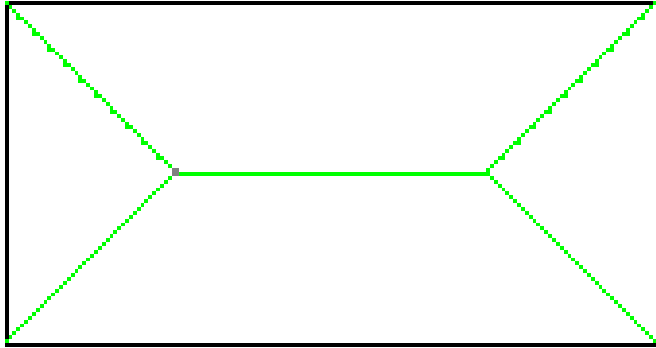again reduces a 2d (or higher) problem to a question about graphs...

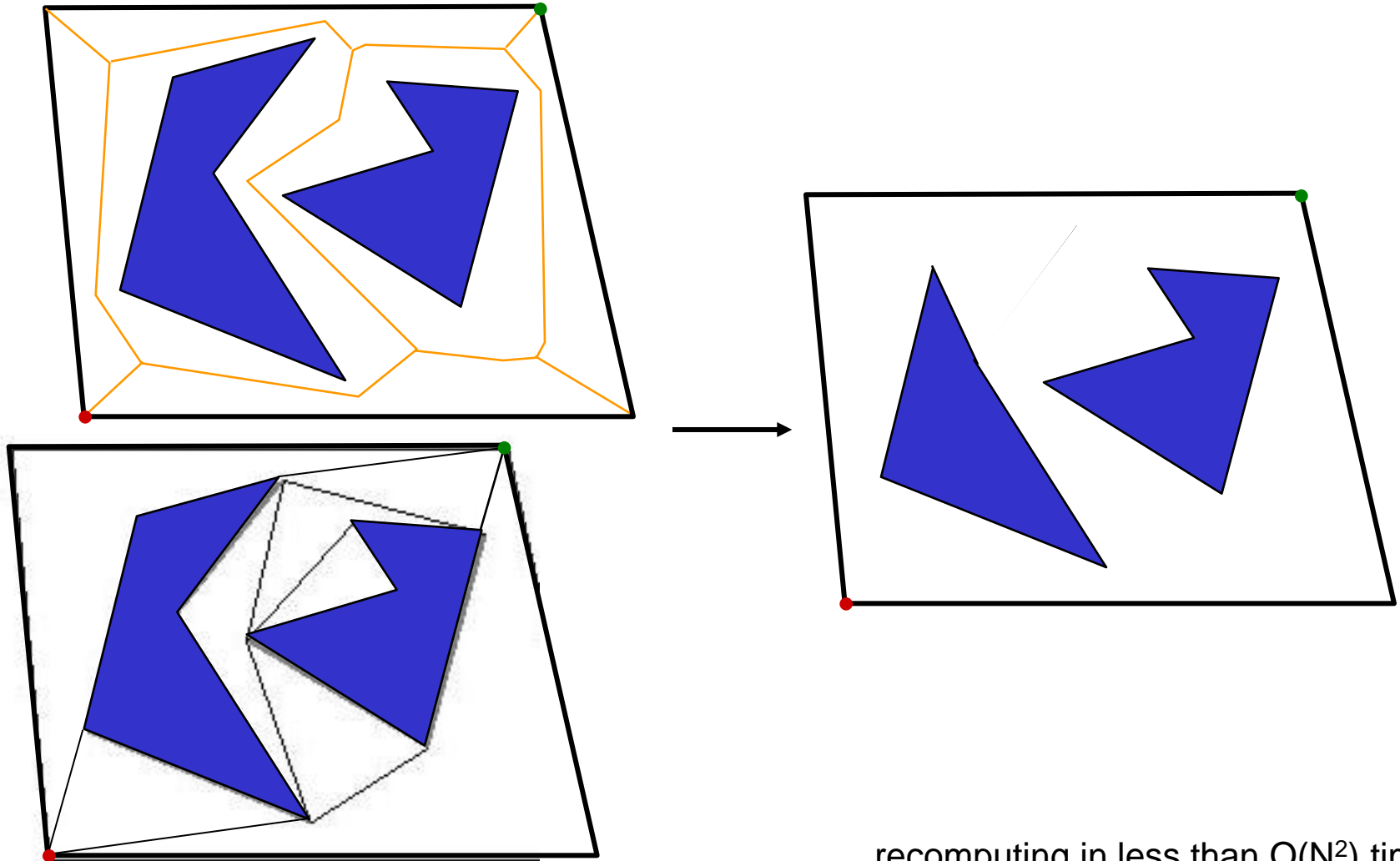

graph matching

Problems

The skeleton is sensitive to small changes in the object's boundary.

- graph isomorphism (and lots of other graph questions) : NP-complete

Roadmap problems

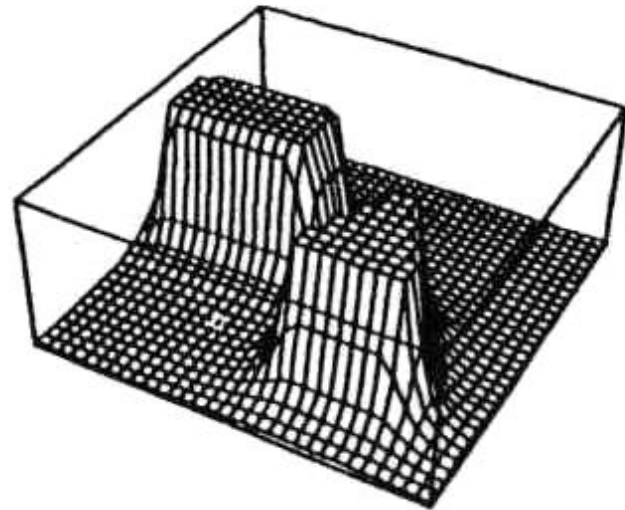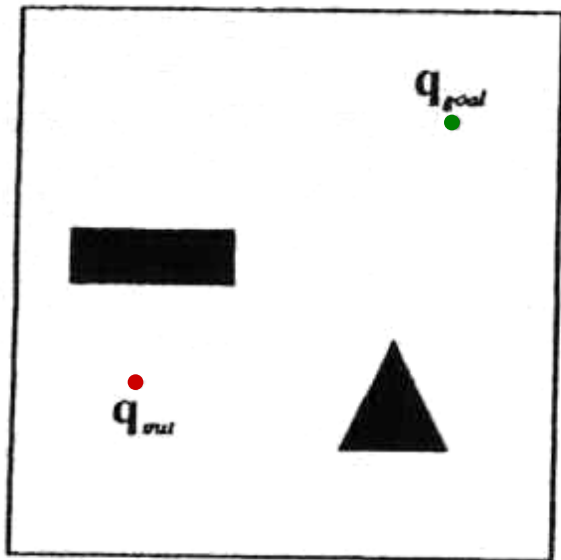If an obstacle decides to roll away...   (or wasn't there to begin with)

recomputing in less than O(N²) time?

Path Planning

Potential Field methods
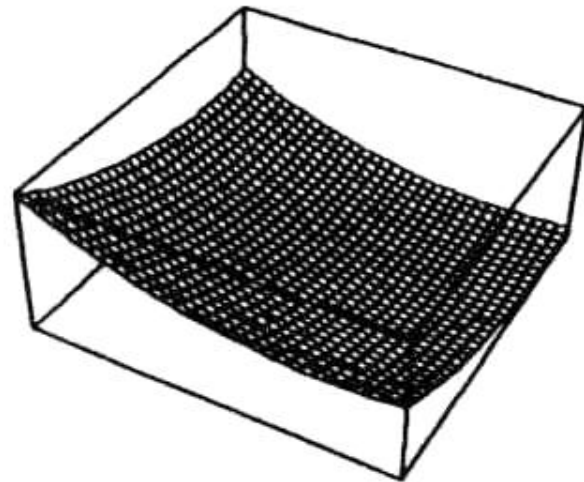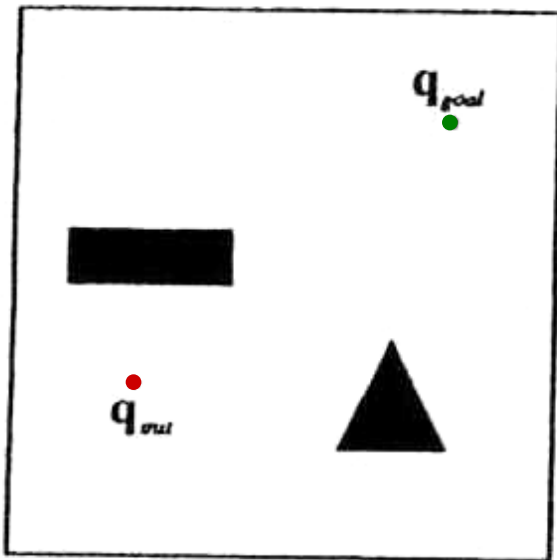
- compute a repulsive force away from obstacles

Local techniques

Potential Field methods

- compute a repulsive force away from obstacles

- compute an attractive force toward the goal

Local techniques

Potential Field methods

- compute a repulsive force away from obstacles

- compute an attractive force toward the goal

→ let the sum of the forces control the robot
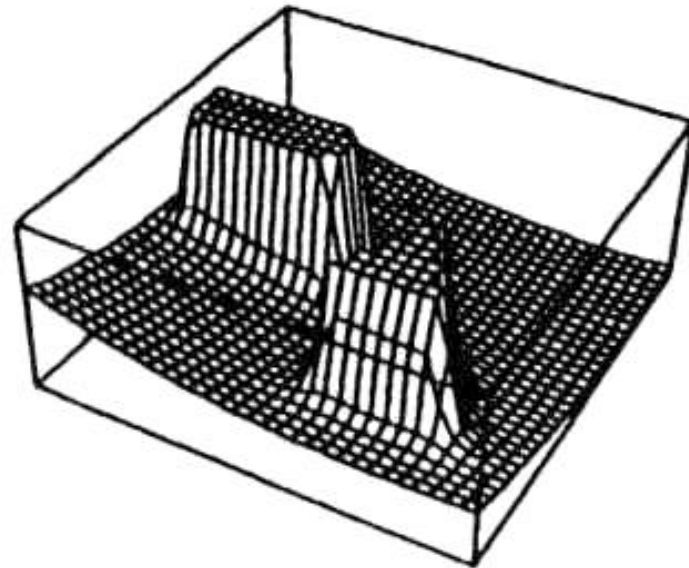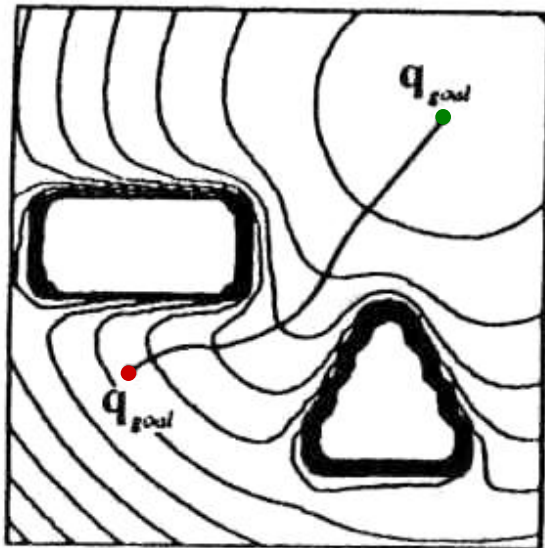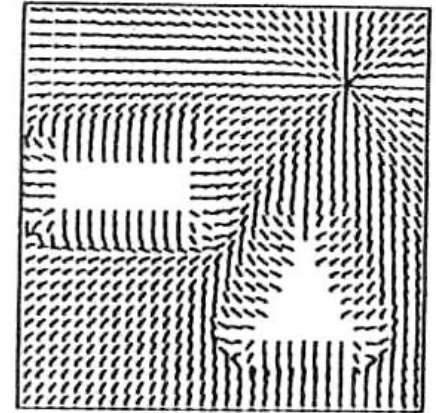
key advantages?

Local techniques

Potential Field methods

- compute a repulsive force away from obstacles

- compute an attractive force toward the goal

→ let the sum of the forces control the robot
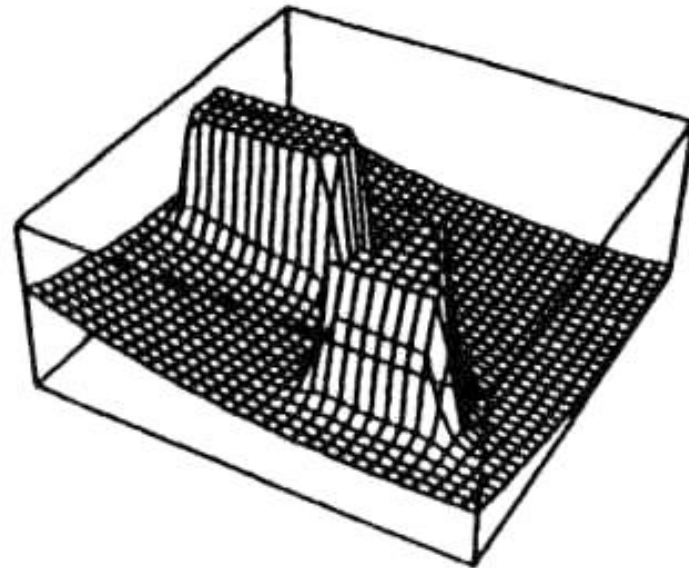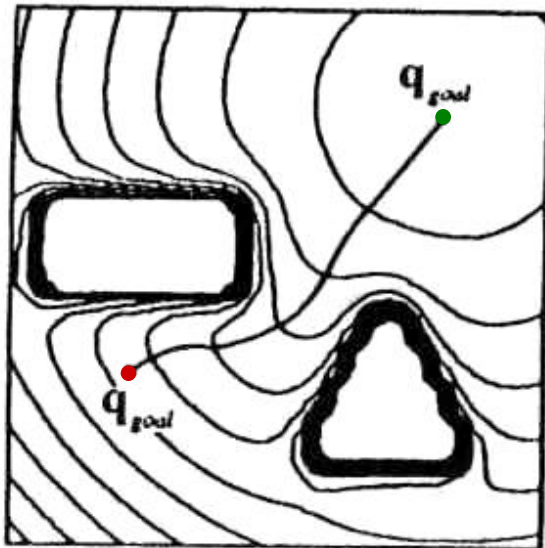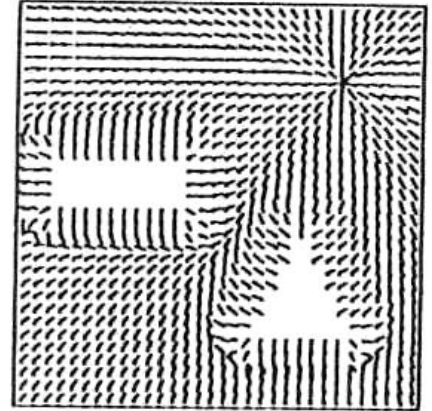
To a large extent, this is computable from sensor readings

Sensor Based Calculations
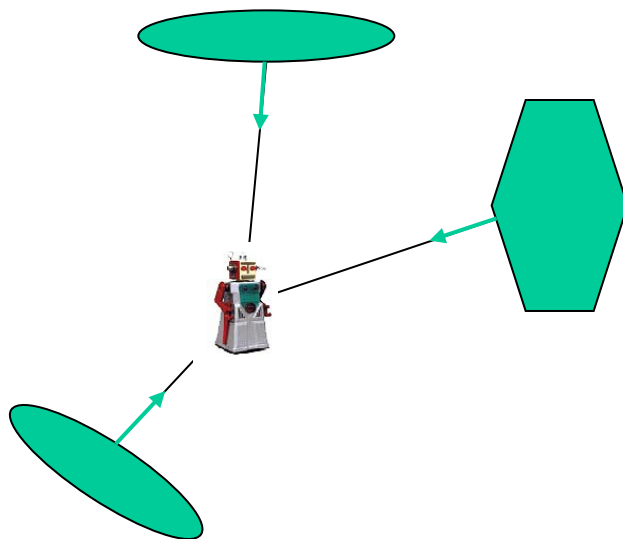
Major Problem?

Local Minima!

F_{goal}

F_{obst}
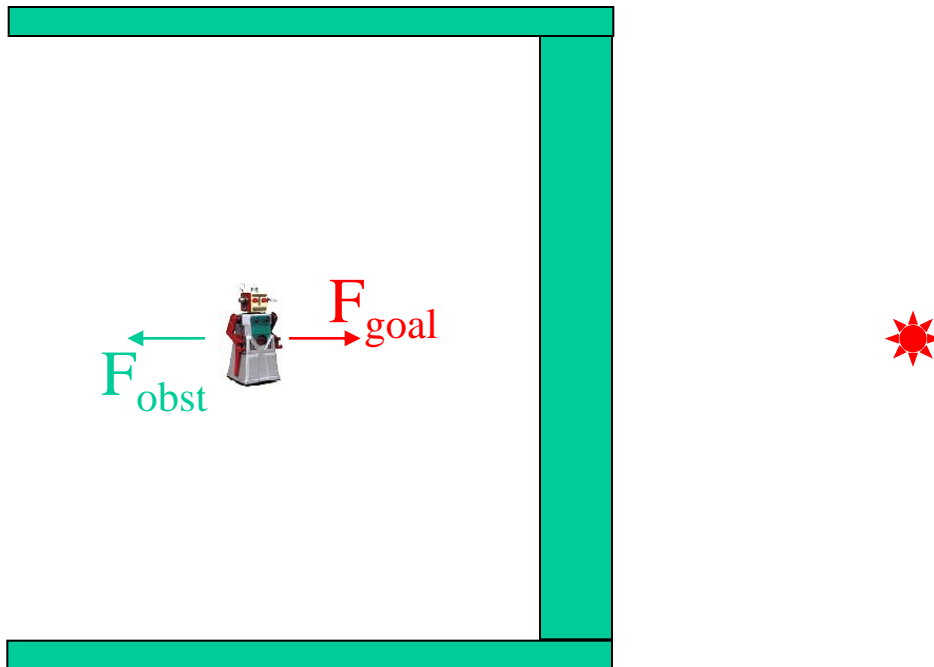
Simulated Annealing

- Every so often add some random force

Known Map

Brushfire Transform

The Wavefront Planner: Setup

The Wavefront in Action (Part 1)

- Starting with the goal, set all adjacent cells with "0" to the current cell + 1
  - 4-Point Connectivity or 8-Point Connectivity?
  - Your Choice. We'll use 8-Point Connectivity in our example

The Wavefront in Action (Part 2)

- Now repeat with the modified cells
  - This will be repeated until no 0's are adjacent to cells with values >= 2
- 0's will only remain when regions are unreachable

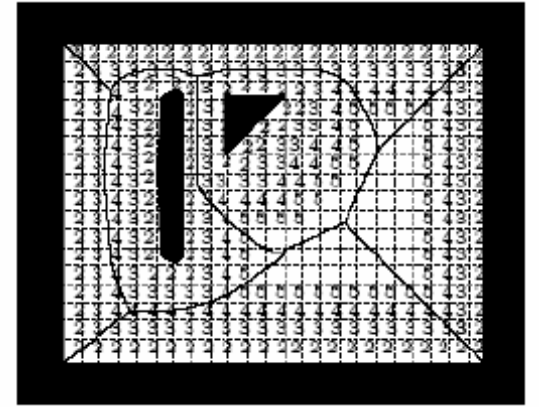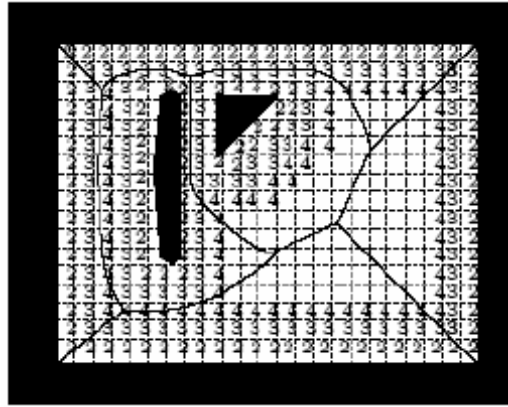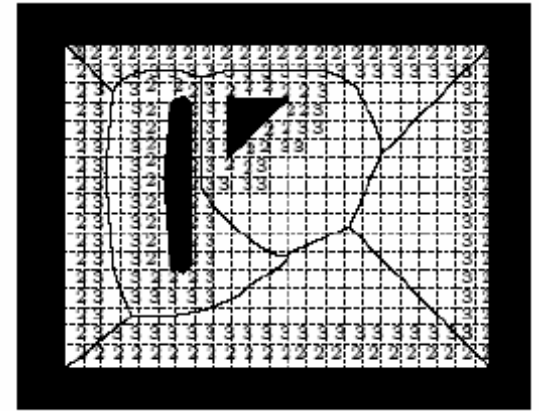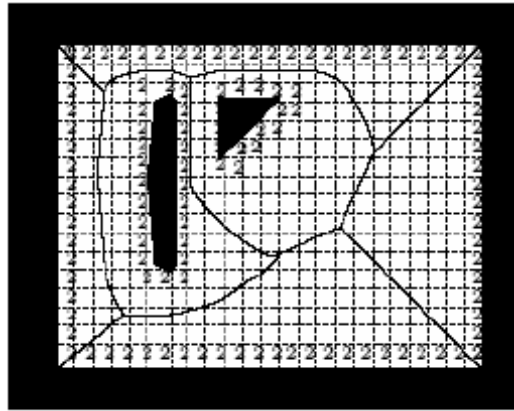|	0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15
7	**0**	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
6	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
5	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
4	0	0	0	0	**1**	**1**	**1**	**1**	**1**	**1**	**1**	**1**	0	0	0	0
3	0	0	0	0	**1**	**1**	**1**	**1**	**1**	**1**	**1**	**1**	0	0	0	0
2	0	0	0	0	0	0	0	0	0	0	0	0	0	4	4	4
1	0	0	0	0	0	0	0	0	0	0	0	0	0	4	3	3
0	0	0	0	0	0	0	0	0	0	0	0	0	0	4	3	**2**

The Wavefront in Action (Part 3)

- Repeat

	0	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15
7	**0**	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
6	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
5	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
4	0	0	0	0	1	1	1	1	1	1	1	1	0	0	0	0
3	0	0	0	0	1	1	1	1	1	1	1	1	5	5	5	5
2	0	0	0	0	0	0	0	0	0	0	0	0	5	4	4	4
1	0	0	0	0	0	0	0	0	0	0	0	0	5	4	3	3
0	0	0	0	0	0	0	0	0	0	0	0	0	5	4	3	**2**

The Wavefront in Action (Part 3)

- Repeat

The Wavefront in Action (Part 3)

- Until Done
  - 0's would only remain in the unreachable areas

The Wavefront in Action

- To find the shortest path, according to your metric, simply always move toward a cell with a lower number
  - The numbers generated by the Wavefront planner are roughly proportional to their distance from the goal
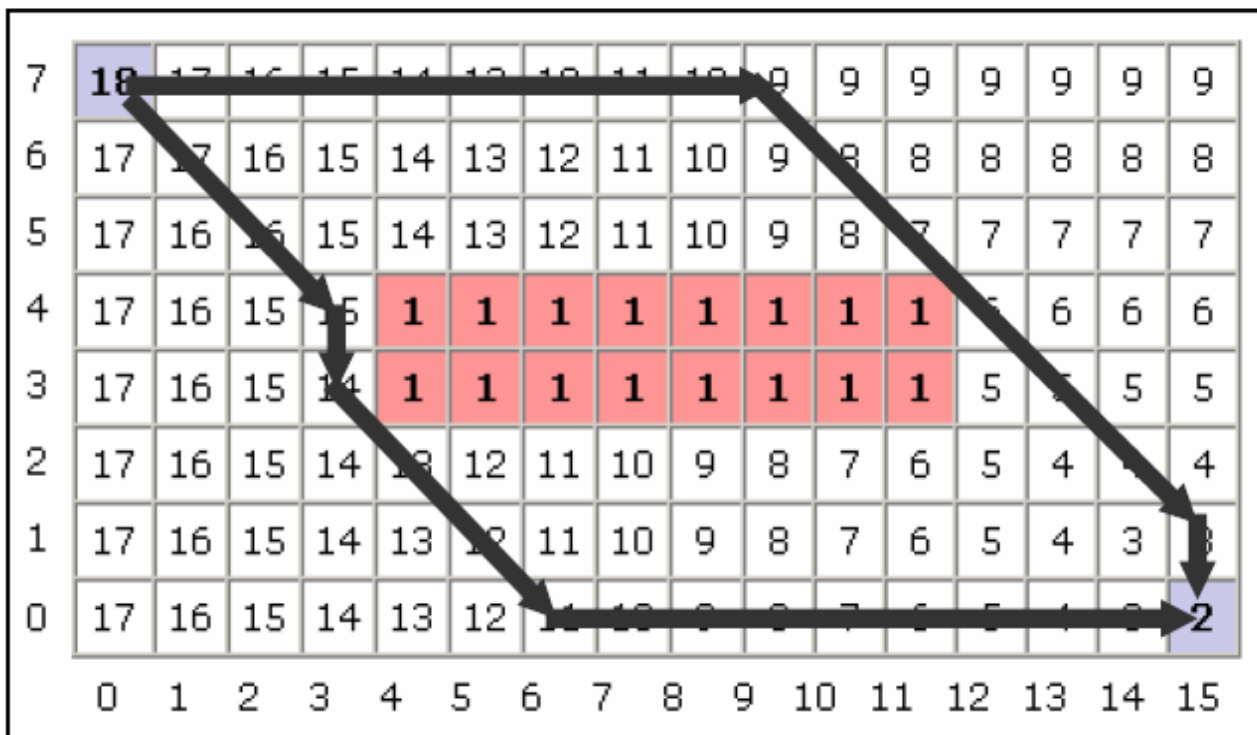
Two possible shortest paths shown