CS-417 INTRODUCTION TO ROBOTICS AND INTELLIGENT SYSTEMS

Exploration

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Three Main Challenges in Robotics

1. Where am I? (Localization)
   - Sense
   - relate sensor readings to a world model
   - compute location relative to model
   - assumes a perfect world model
2. What the world looks like? (Mapping)
   - sense from various positions
   - integrate measurements to produce map
   - assumes perfect knowledge of position

- Together 1 and 2 form the problem of *Simultaneous Localization and Mapping* (SLAM)

3. How do I go from **A** to **B**? (Path Planning)
   - More general: Which action should I pick next?

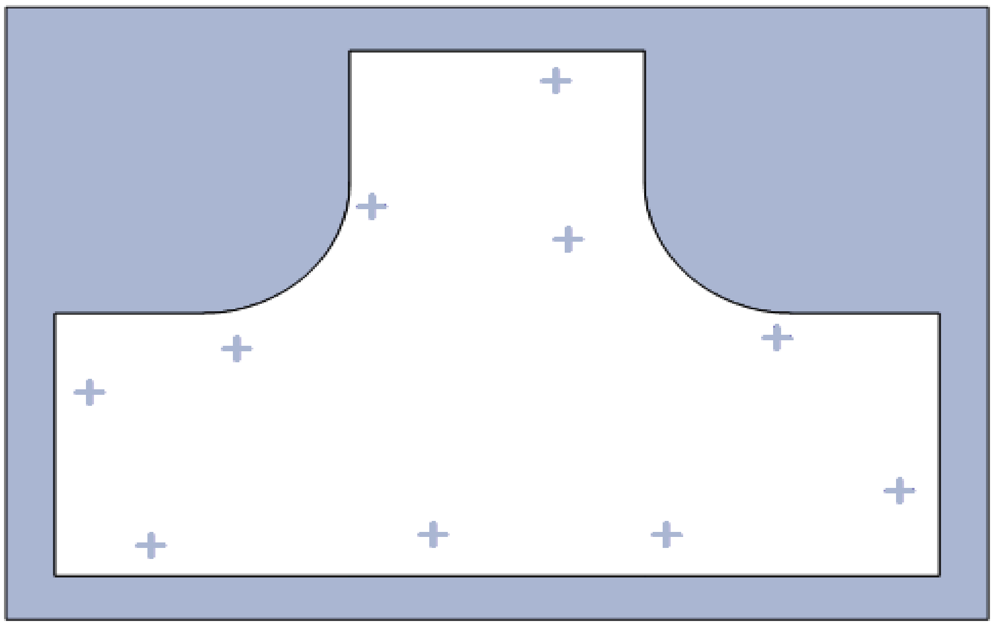
Mapping

- What the world looks like
- Improve the accuracy of the map
- Ensure that all the important parts of the environment are mapped – Exploration!

Environment Representation (Map)

- Grid Based Maps
- Feature Based Maps
- Topological Maps
- Hybrid Maps

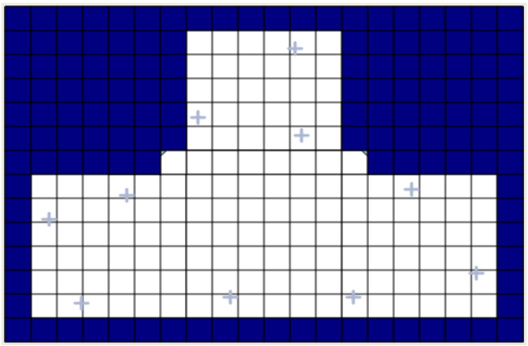
Consider this Environment:



Three Basic Map Types

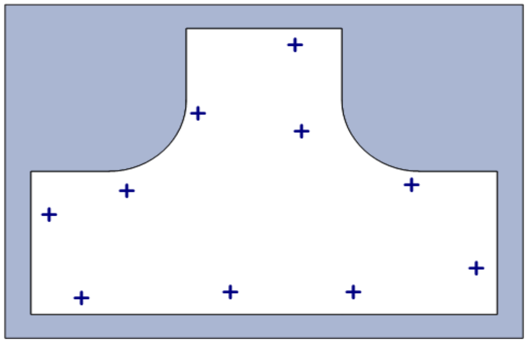
Grid-Based:

Collection of discretized obstacle/free-space pixels



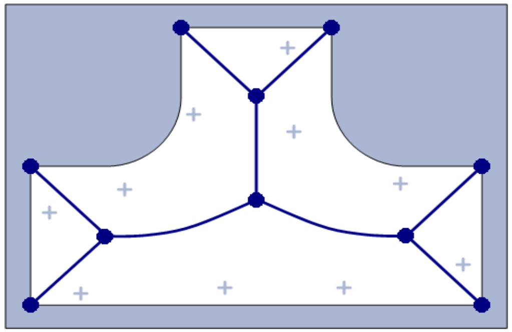
Feature-Based:

Collection of landmark locations and correlated uncertainty

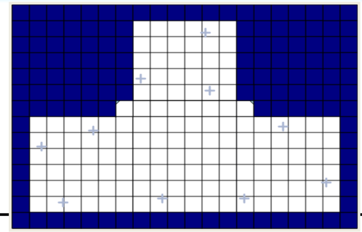


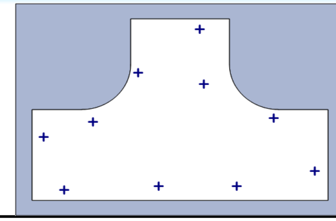
Topological:

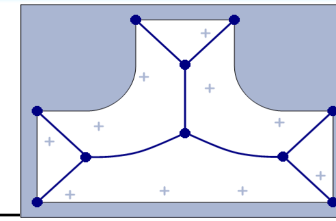
Collection of nodes and their interconnections



Three Basic Map Types



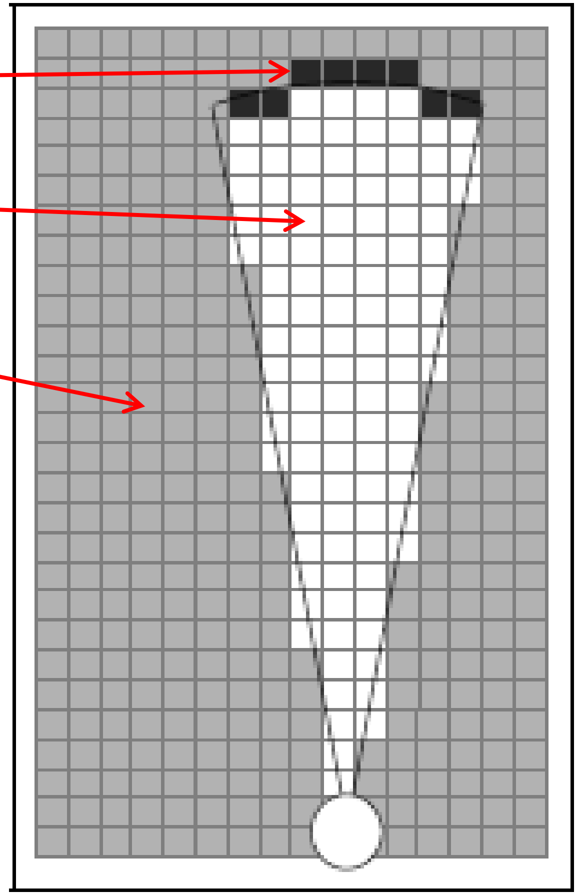




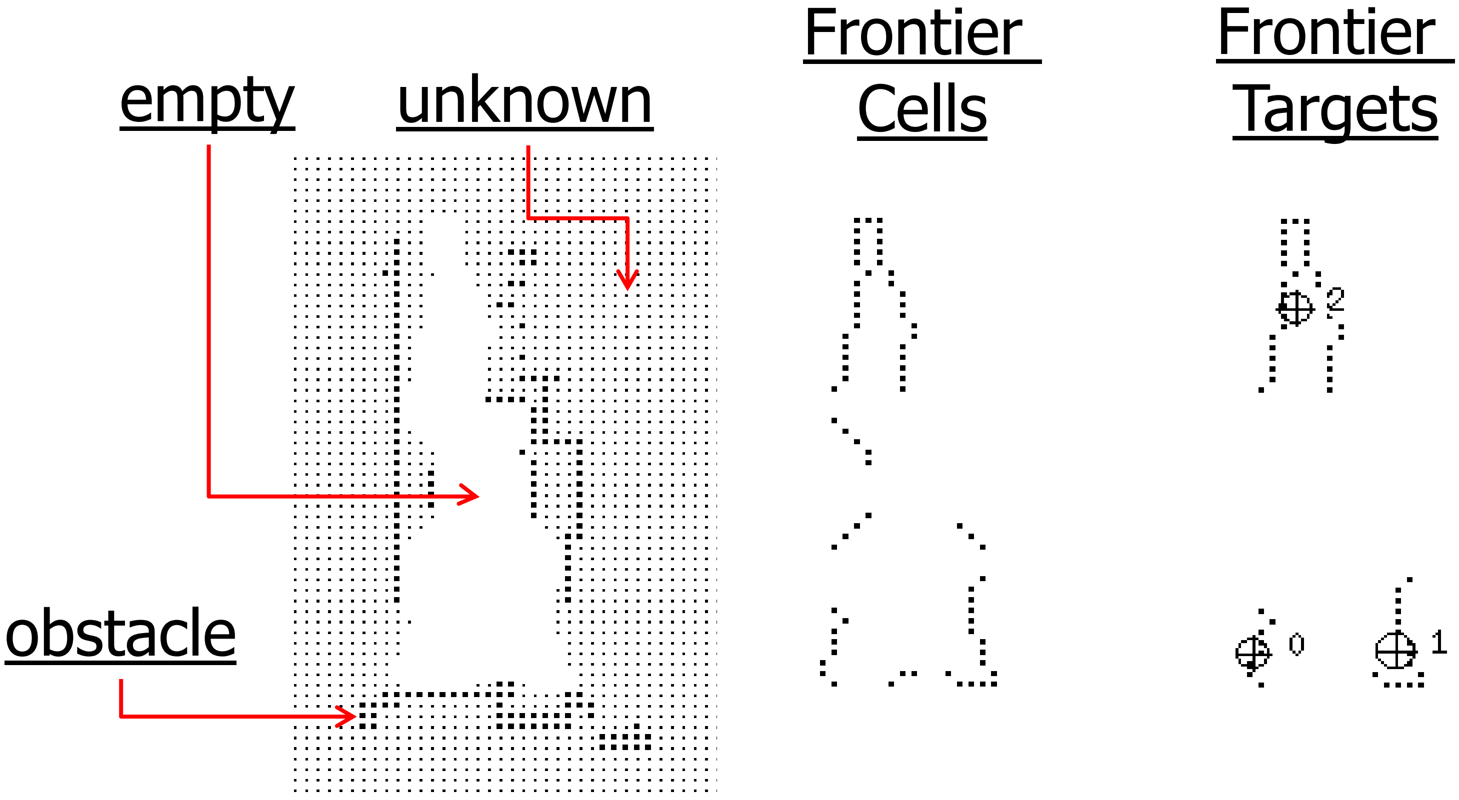
	Grid-Based	Feature-Based	Topological
Construction	Occupancy grids	Kalman Filter	Navigation control laws
Complexity	Grid size and resolution	Landmark covariance (N^3)	Minimal complexity
Obstacles	Discretized obstacles	Only structured obstacles	GVG defined by the safest path
Localization	Discrete localization	Arbitrary localization	Localize to nodes
Exploration	**Frontier-based exploration**	**No inherent exploration**	**Graph exploration**

Grid Based Maps

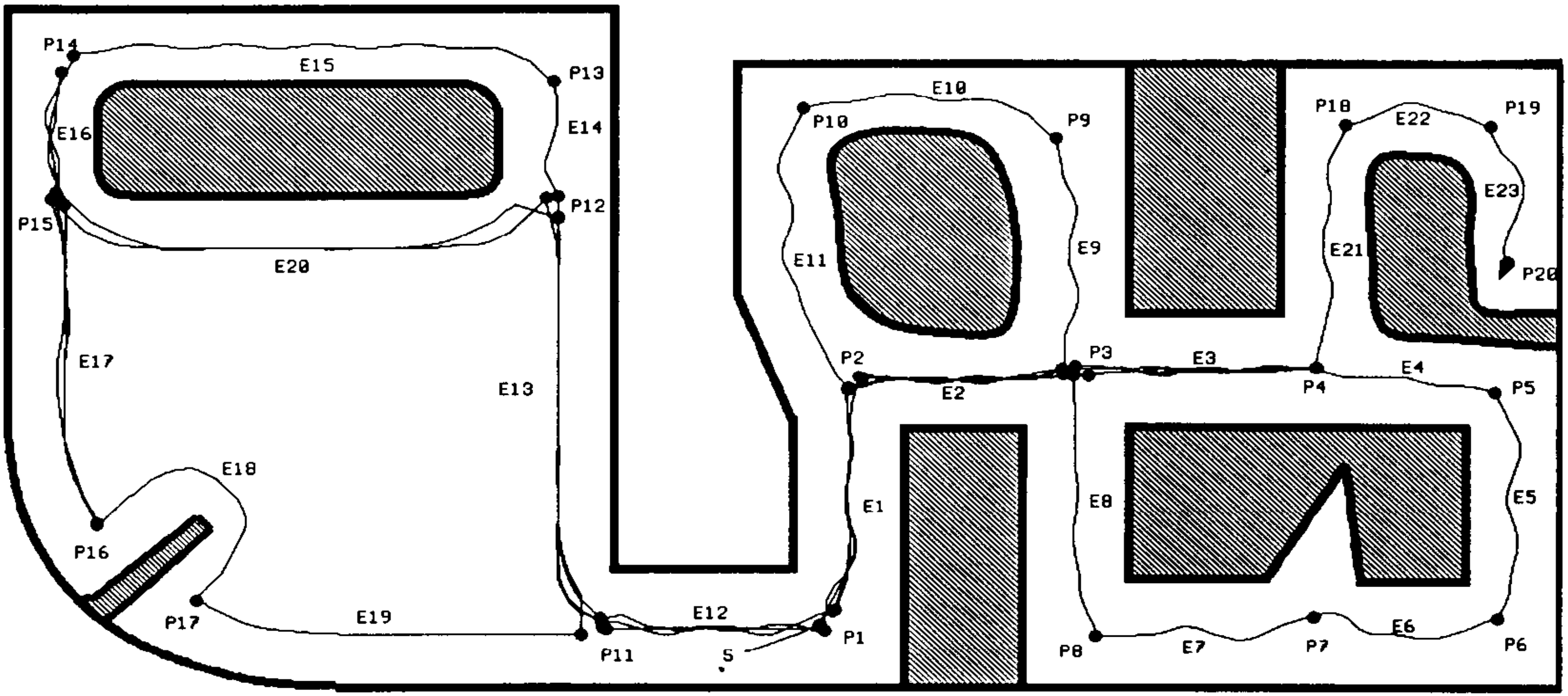
- Occupied cells
- Free cells
- Unknown cells



Frontier based Exploration (Grid Maps)

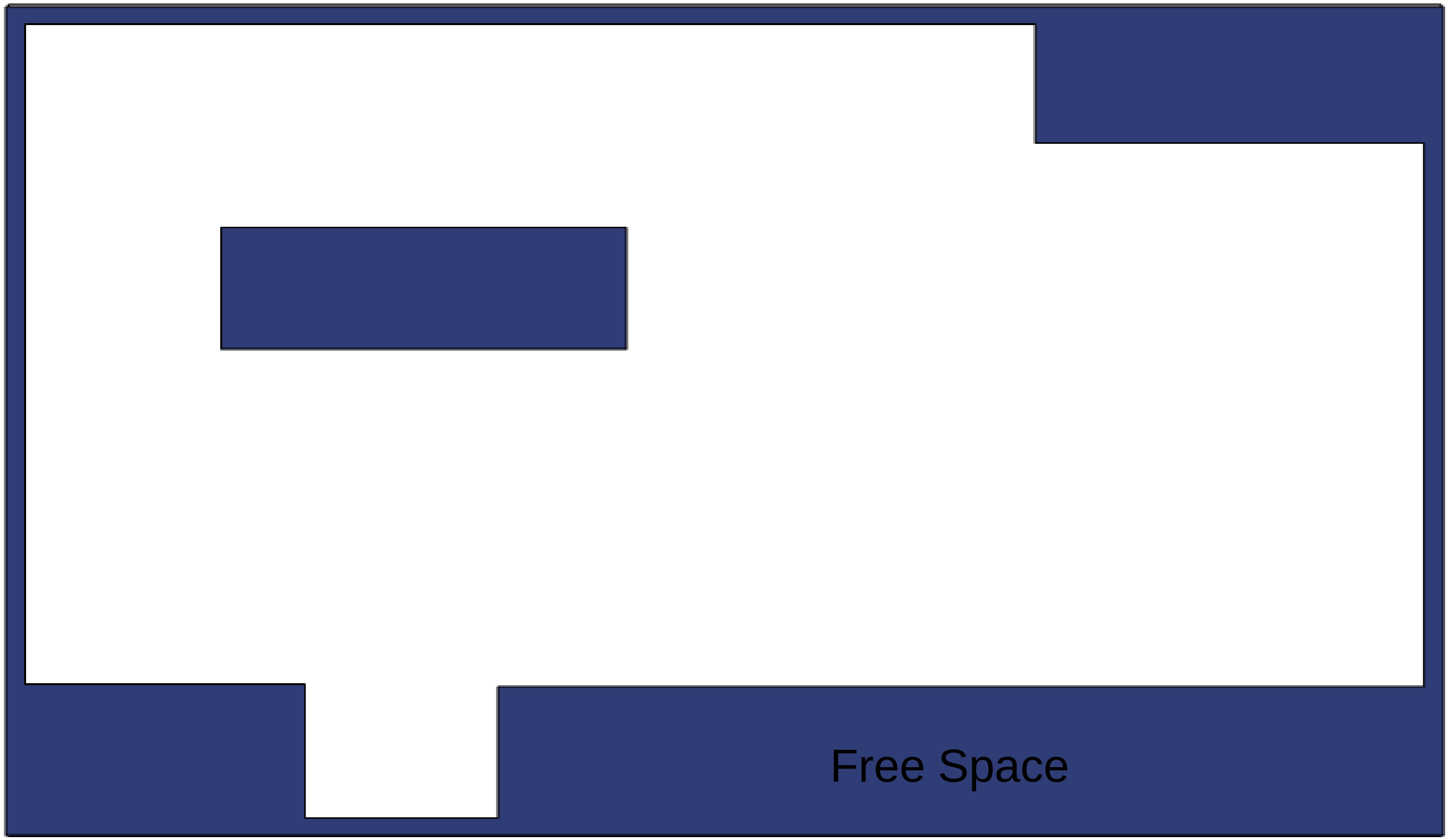


Topological Representations



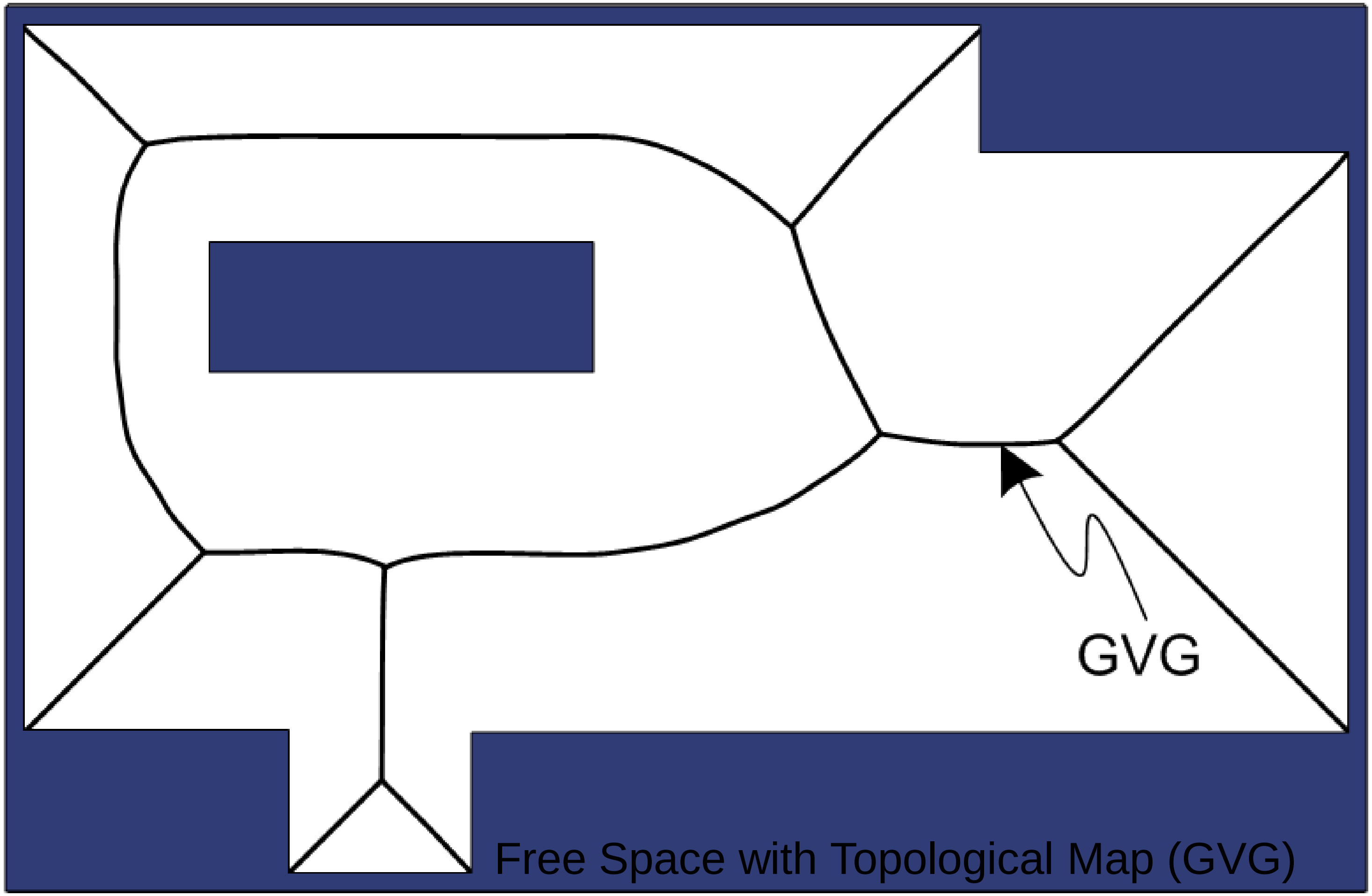
- B. J. Kuipers and Y.-T. Byun. “A robot exploration and mapping strategy based on a semantic hierarchy of spatial representations”. In *Journal of Robotics and Autonomous Systems*, 8: 47-63, 1991.

Generalized Voronoi Graph (GVG)



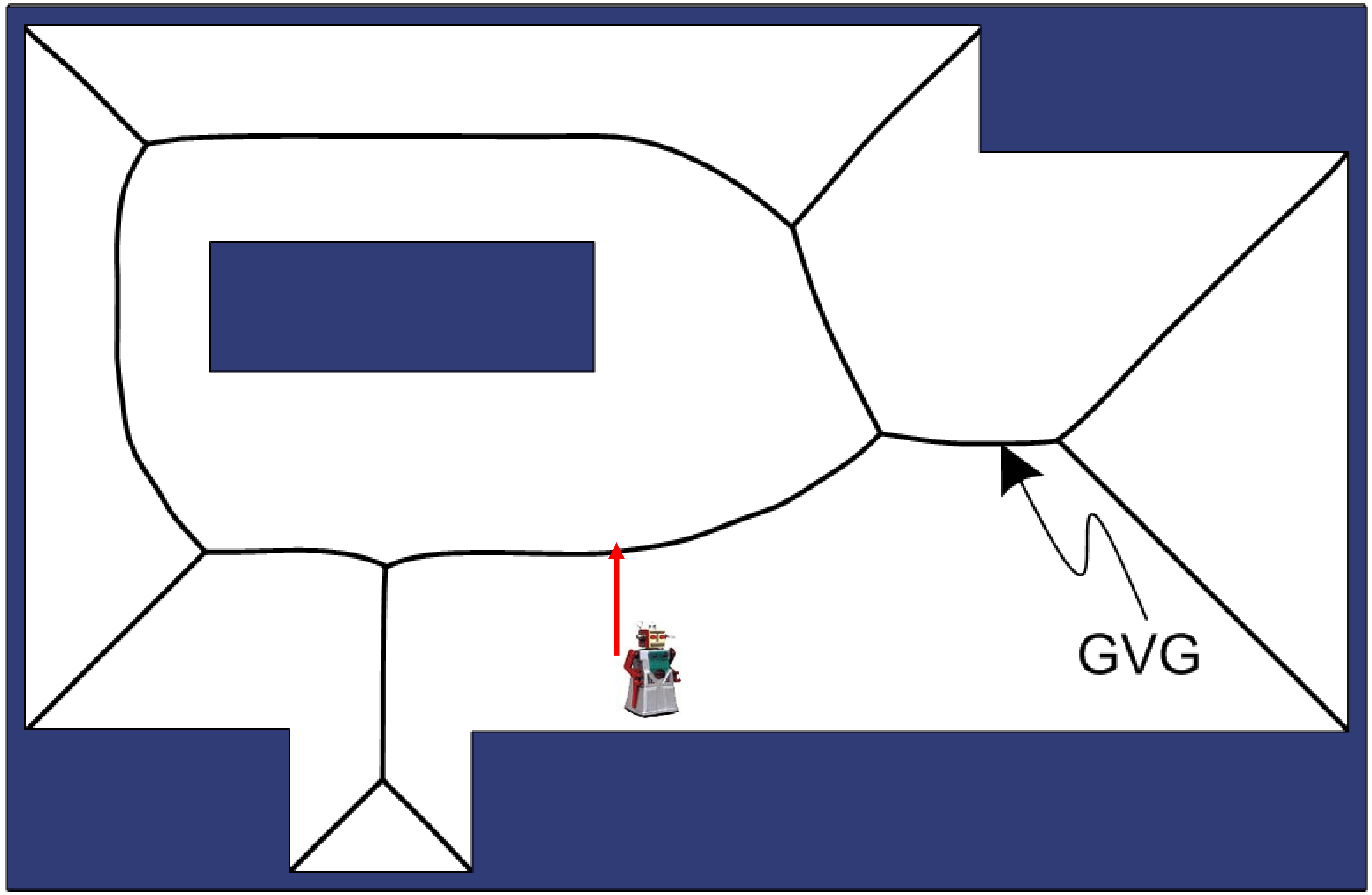
H. Choset, J. Burdick, “Sensor based planning, part ii: Incremental construction of the generalized voronoi graph”. In IEEE Conference on Robotics and Automation, pp. 1643 – 1648, 1995.

Generalized Voronoi Graph (GVG)



Generalized Voronoi Graph (GVG)

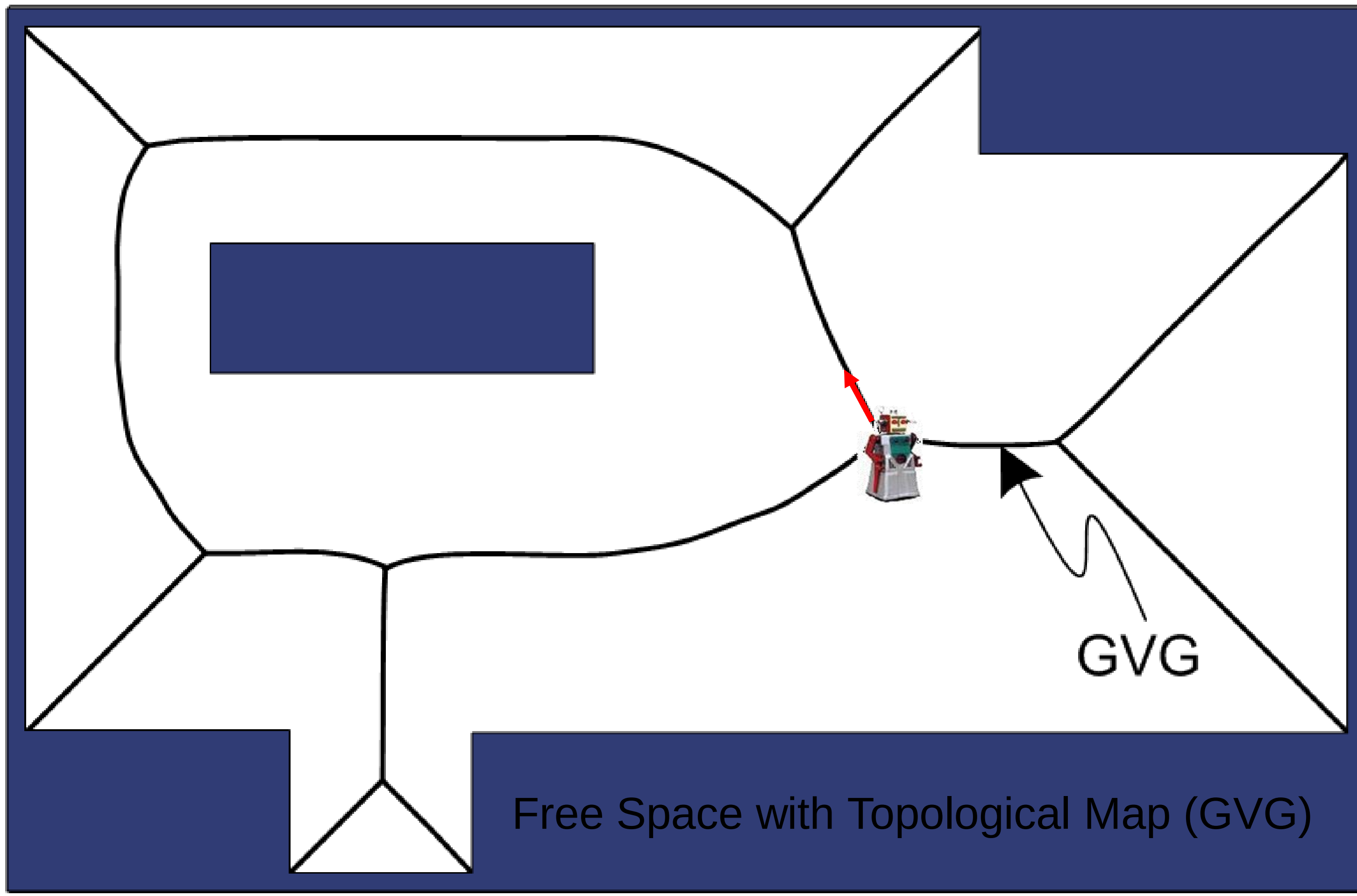
- Access GVG



Free Space with Topological Map (GVG)

Generalized Voronoi Graph (GVG)

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

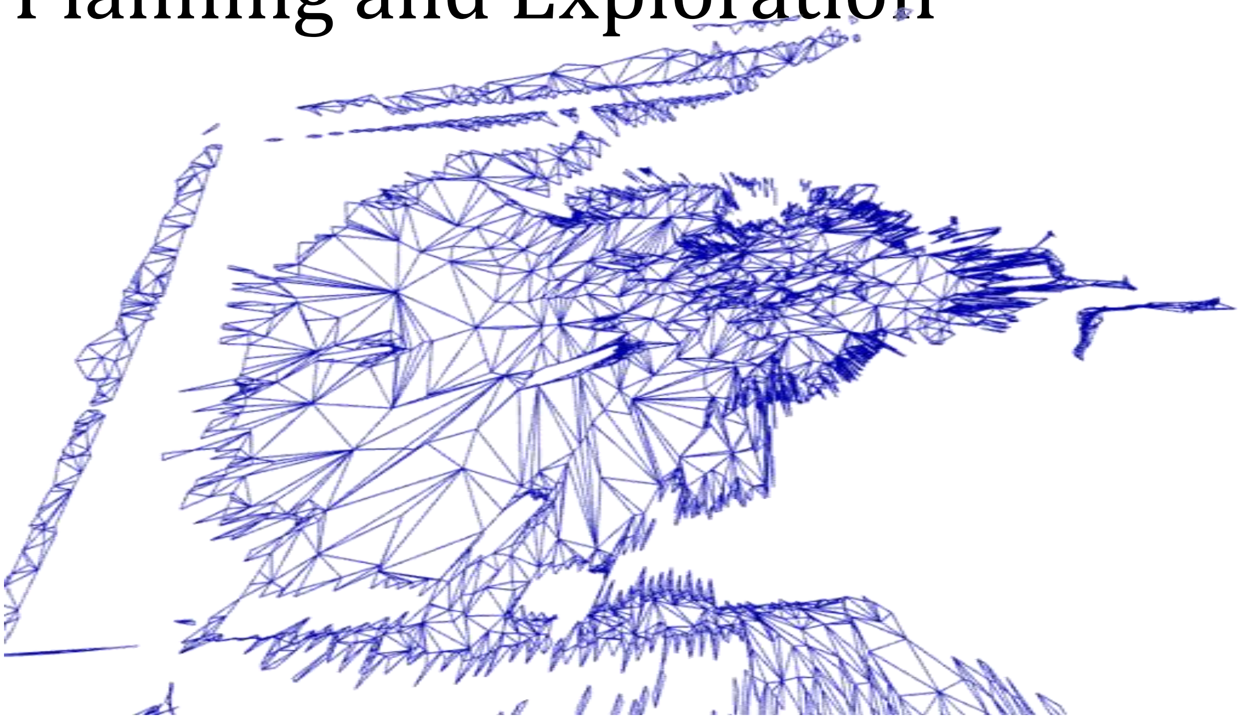


Exploration via Graph Search

- Exhaustive Depth First Search
- Breadth-First Search
- Heuristics

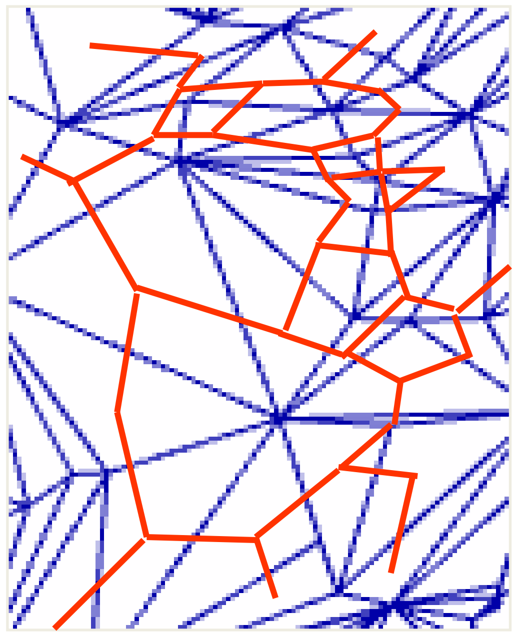
Irregular Triangular Mesh (ITM)

- Terrain Representation
- Underlying Topological Structure
- Path Planning and Exploration



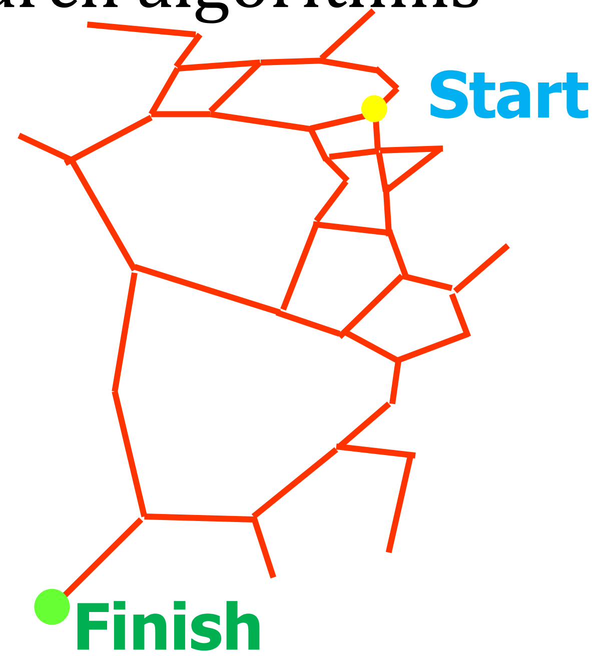
From 2.5D Representation to Topological

- Convert ITM into Connected Graph



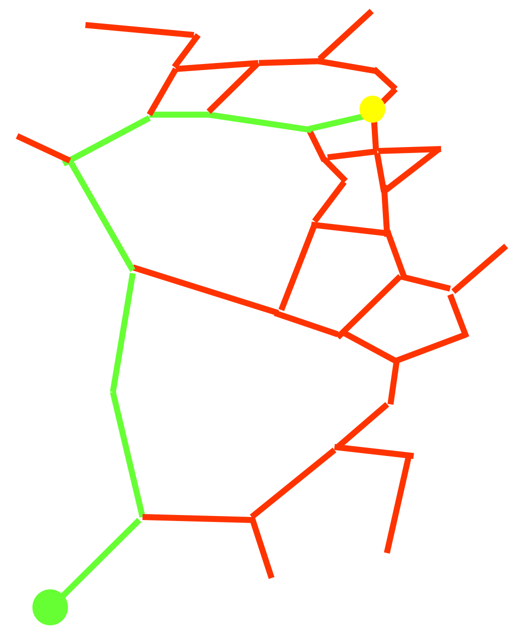
Planning

- Convert ITM into Connected Graph
- Planning using Graph Search Algorithms:
  – Dijkstra, A* search algorithms



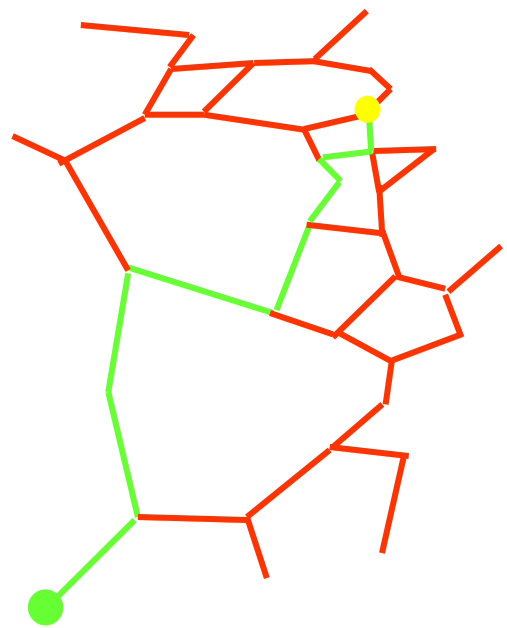
Planning

- Convert ITM into Connected Graph
- Path Planning using Graph Search Algorithms:
  - Dijkstra, A* search algorithms
- Different Cost Functions Q
  - Number of triangles $Q = 1$



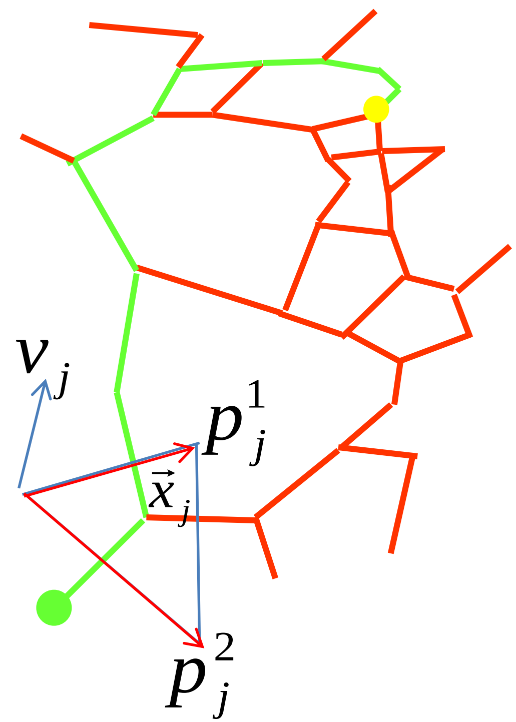
Planning

- Convert ITM into Connected Graph
- Path Planning using Graph Search Algorithms:
  - Dijkstra, A*
- Different Cost Functions Q
  - Number of triangles
  - Euclidian distance $Q = \left\| \vec{x}_i - \vec{x}_j \right\|$



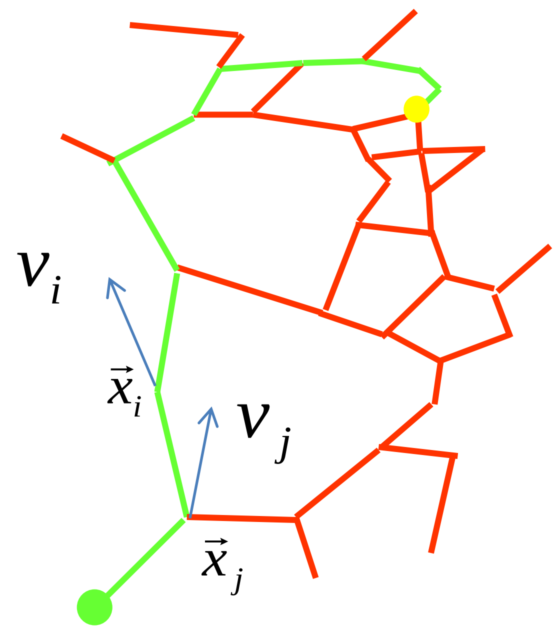
Planning

- Convert ITM into Connected Graph
- Path Planning using Graph Search Algorithms:
  - Dijkstra, A*
- Different Cost Functions Q
  - Number of triangles
  - Euclidian distance
  - Slope of each triangle $v_j = \dfrac{p_j^1 \times p_i^2}{\left\| p_j^1 \right\| \left\| p_j^2 \right\|}$



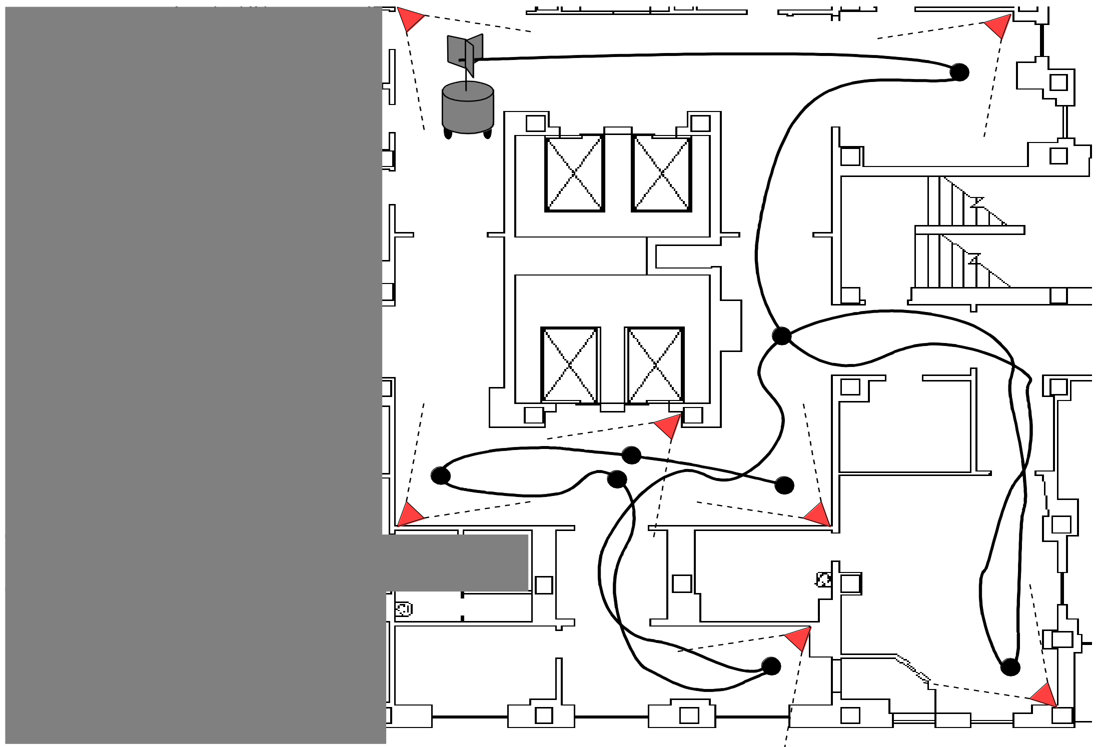
Planning

- Convert ITM into Connected Graph
- Path Planning using Graph Search Algorithms:
  - Dijkstra, A*
- Different Cost Functions Q
  - Number of triangles
  - Euclidian distance
  - Slope of each triangle
  - Cross triangle slope



Exploration Planning Problem

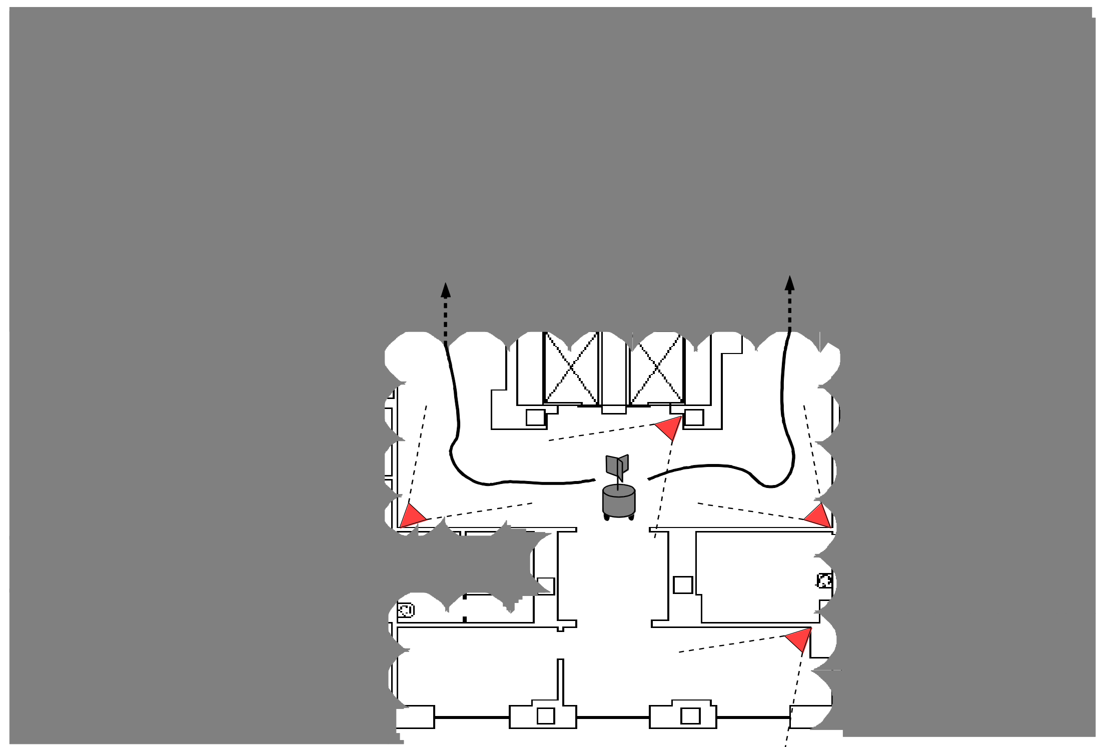
Two fundamental problems for path planning during exploration and mapping:



Exploration Planning Problem

Two fundamental problems for path planning during exploration and mapping:

- – Planning for re-localization
- – Planning the exploration of new territory



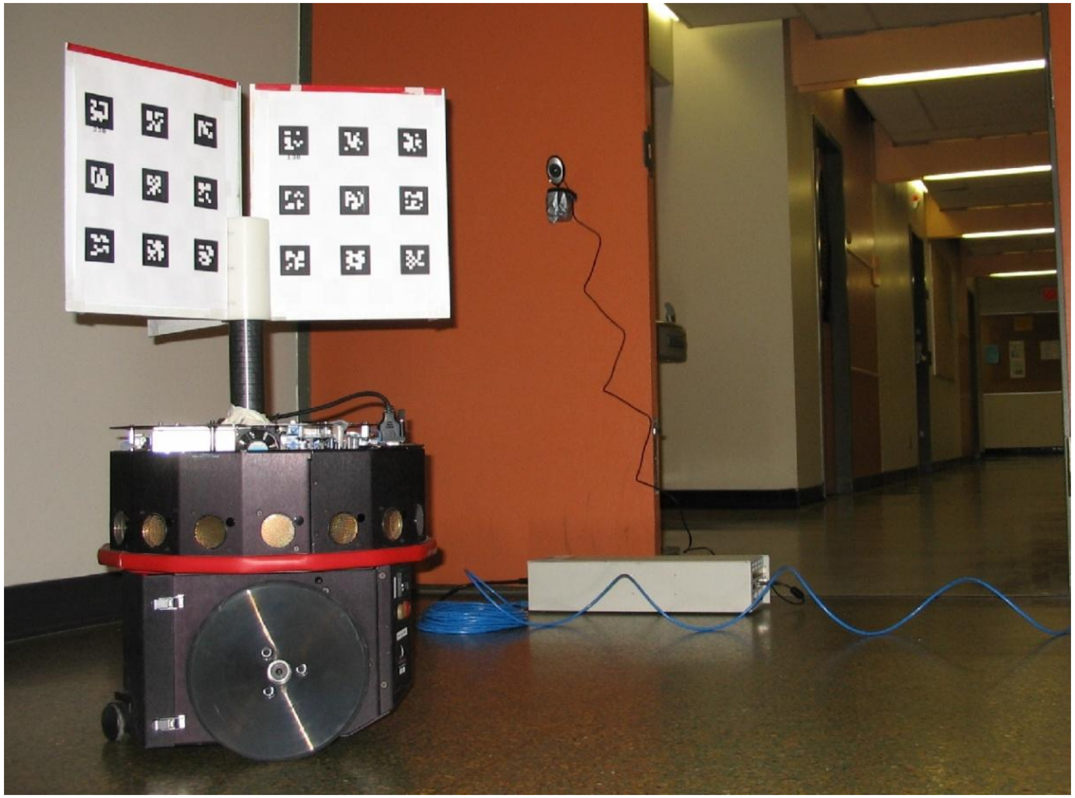
Previous Localization Planning

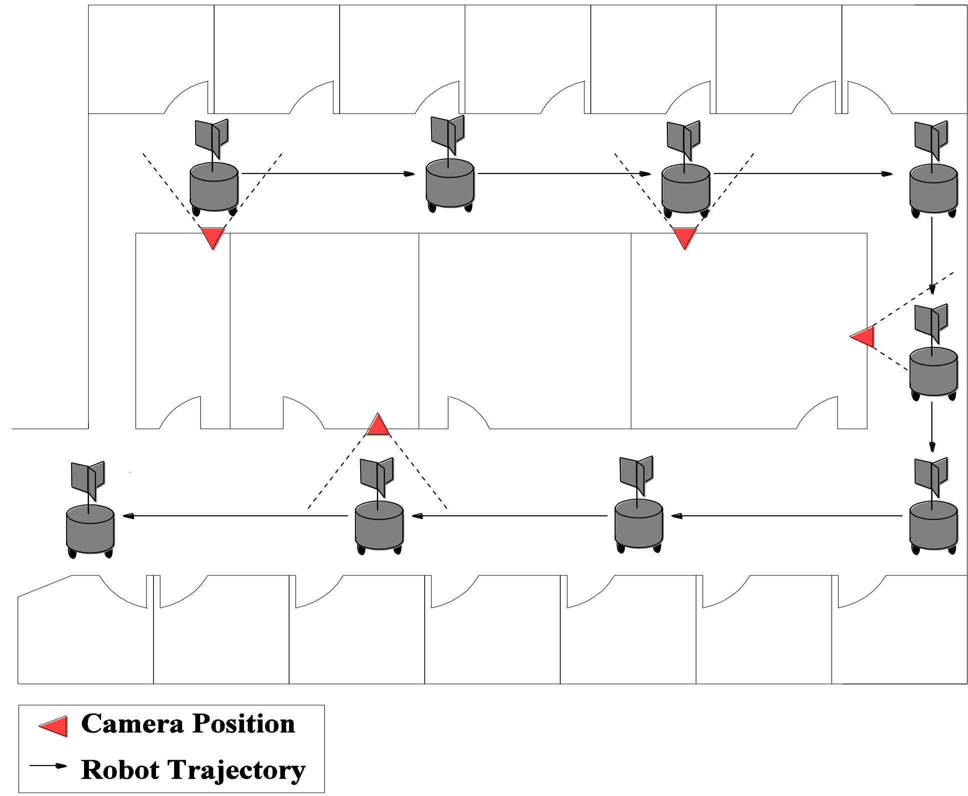
- Reduce measure of map or position entropy
- Variety of graph search planning algorithms (breadth first, A*-search, RRT)
- Evaluate paths with simulation, or Cramer-Rao bounds for expected uncertainty
- e.g. [Fox et al RAS 1998], [Sim and Roy ICRA 2005], [He et al ICRA 2008], [Censi et al ICRA 2008]

Previous Exploration Planning

- Includes motion into unexplored regions
- Typically requires prior knowledge of environment properties or rough layout
- Computation of exploration effects is a challenge
- e.g. [Bourque and Dudek IROS 1999], [Bourgault et al IROS 2002], [Kollar and Roy IJRR 2008]

Exploring a Camera Sensor Network





D. Meger, I. Rekleitis, and G. Dudek. "Heuristic Search Planning to Reduce Exploration Uncertainty", IROS 2008.

Heuristic Search Planning Method

- Solution to exploration planning for camera sensor networks
  - Composed of two alternated steps: exploration and re-localization
  - Combined distance and uncertainty cost function
  - Heuristic search for good paths

Re-localization Trajectories

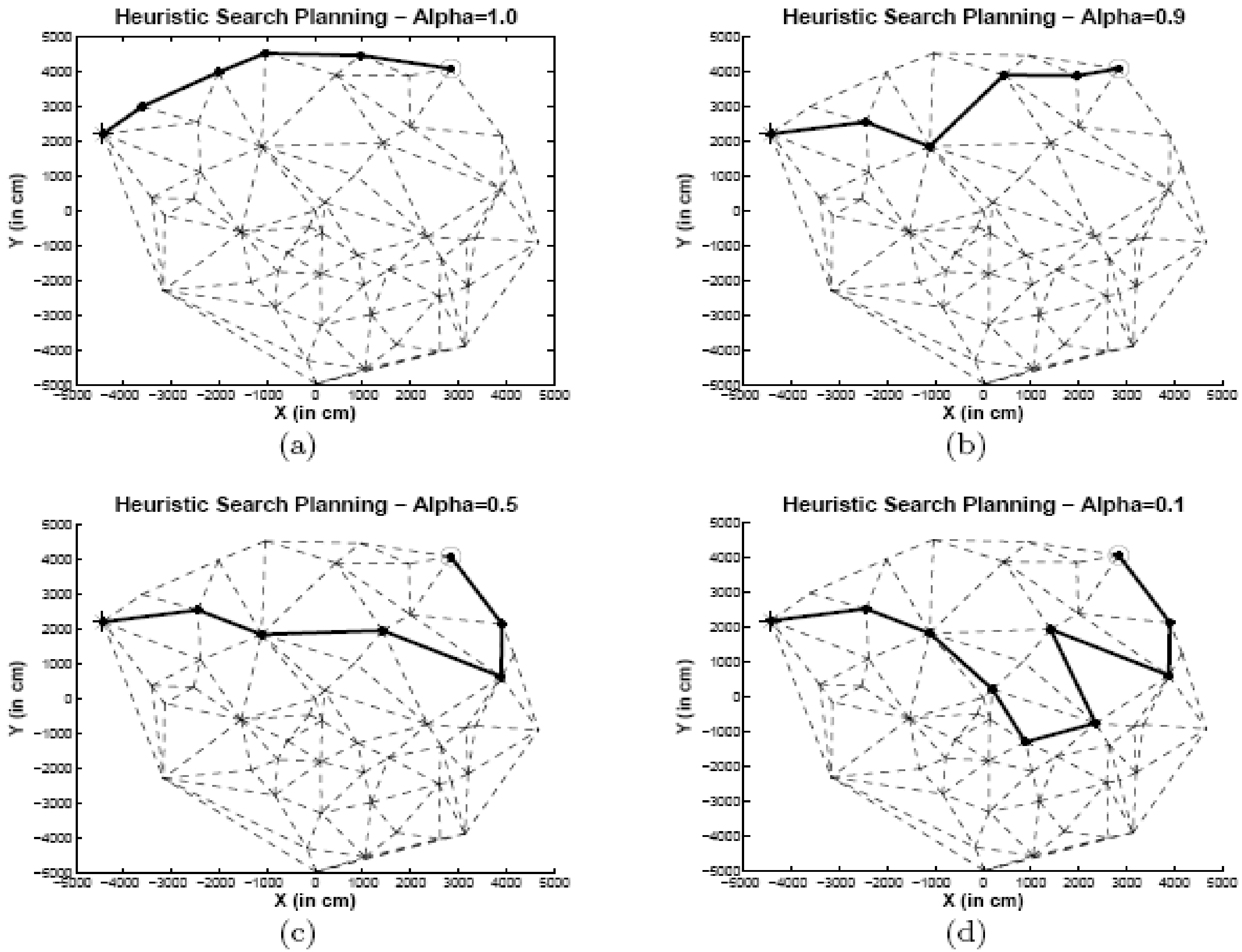
- Find a path p which optimizes a weighted cost function between distance and uncertainty:

$$C(p) = \omega_d \; length(p) + \omega_u \; trace(\Sigma \, (p))$$

$$\omega_d = \frac{\alpha}{maxdist} \quad , \quad \omega_u = \frac{1-\alpha}{maxuncert}$$

- Evaluate possible paths by simulation, approximating measurements with expected values

Effect of α Parameter for Relocalization



Heuristic Search

- Graph search to optimize cost function

$$C(p) = \omega_d length(p) + \omega_u trace(\Sigma(p))$$

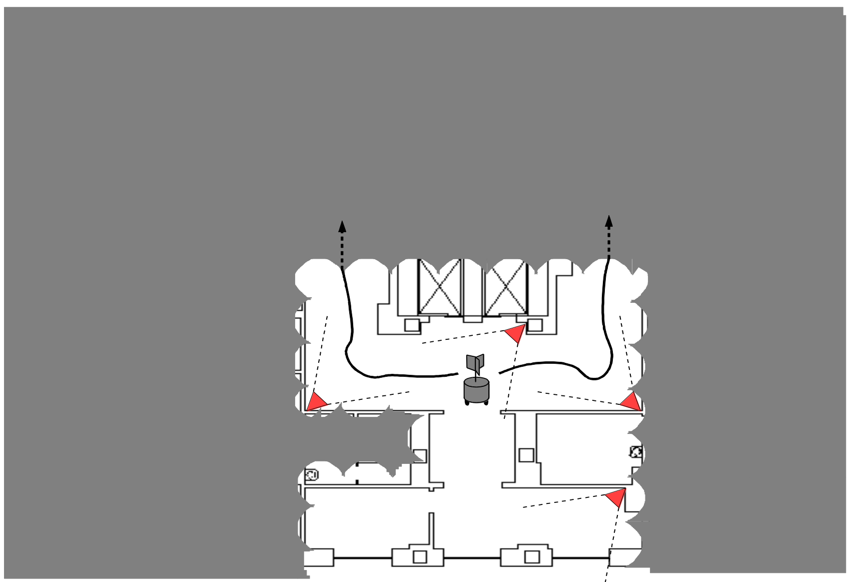
- Heuristic search allows considering only a fraction of the paths, ordered by expected cost
- Distance-based "cost-to-go" heuristic function *h* used to compute estimated cost

$$C(n) = f(n) + h(n)$$

Estimated cost through n — Cost so far — Estimated cost to go

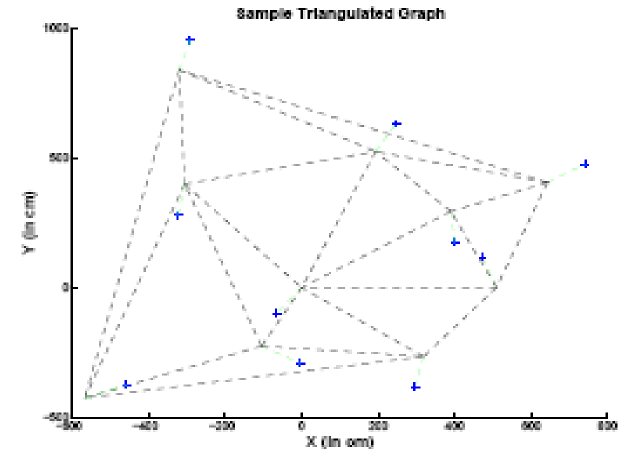
Planning Exploratory Steps

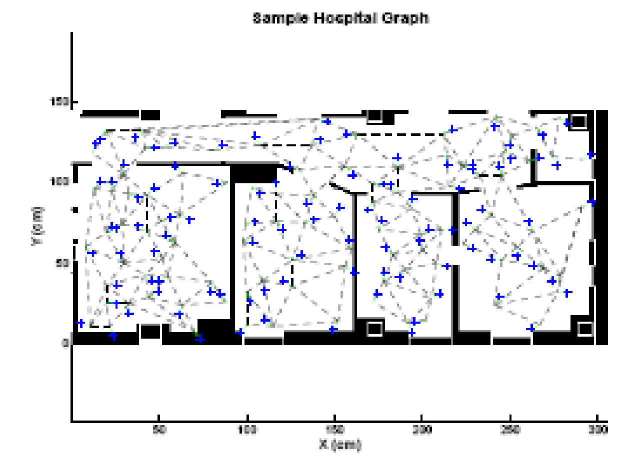
- Choose motion in unexplored space to locate additional camera nodes
- Planner cannot simulate these paths
- Evaluated 2 strategies: 1) nearest camera and 2) a randomly selected camera



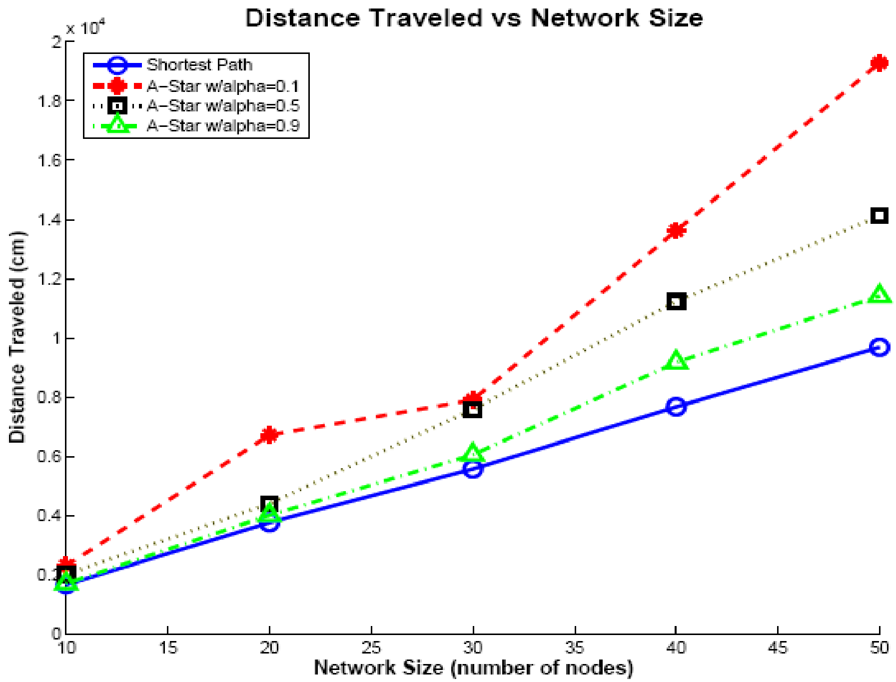
Simulation Results

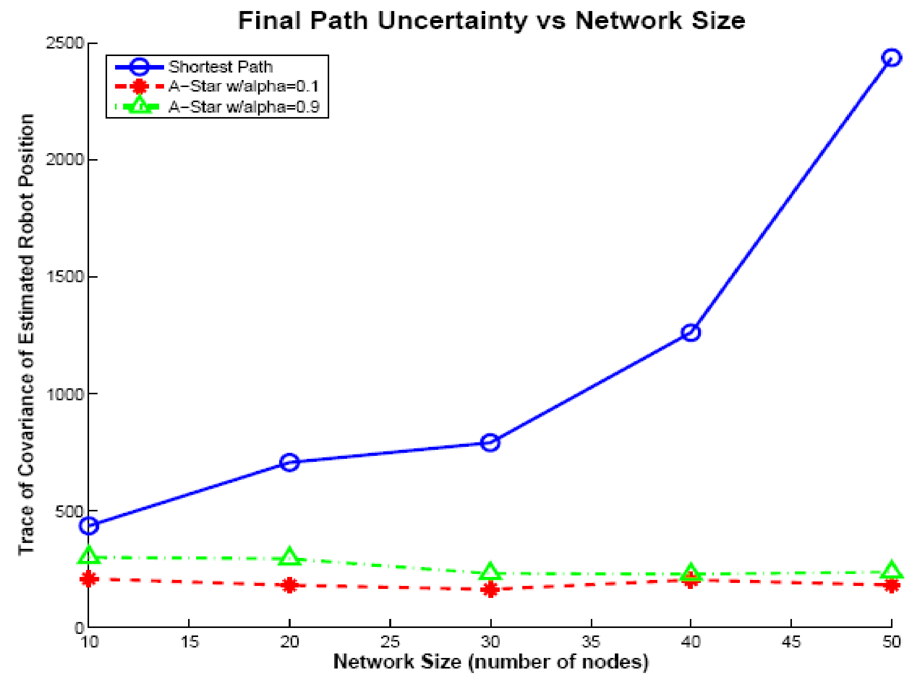
- Compared planners over many trials
- 3 realistic network types (2 shown)
- 3 methods for comparison:
  - Depth-first
  - Return to origin
  - Return to nearest explored



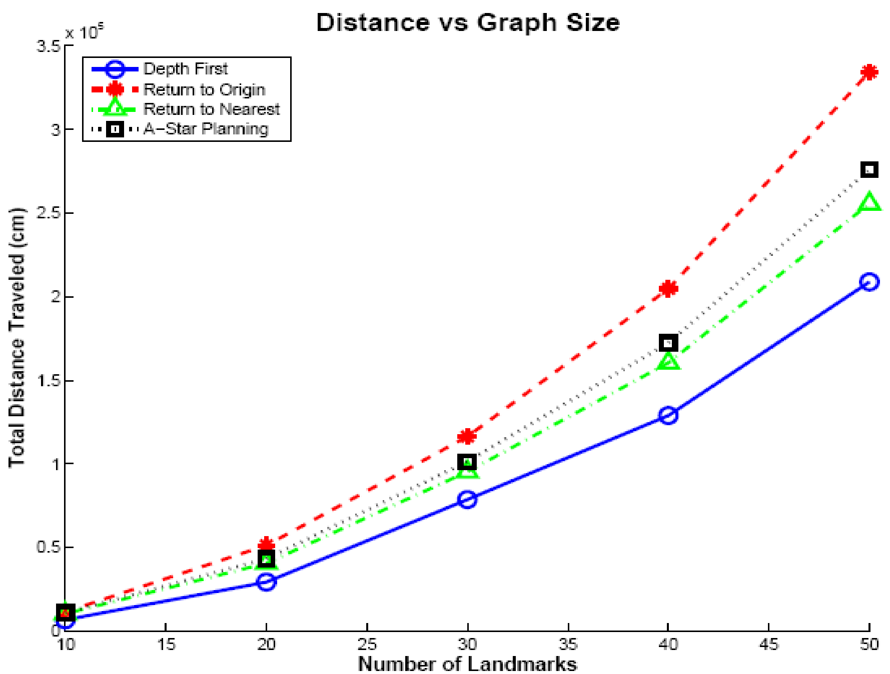


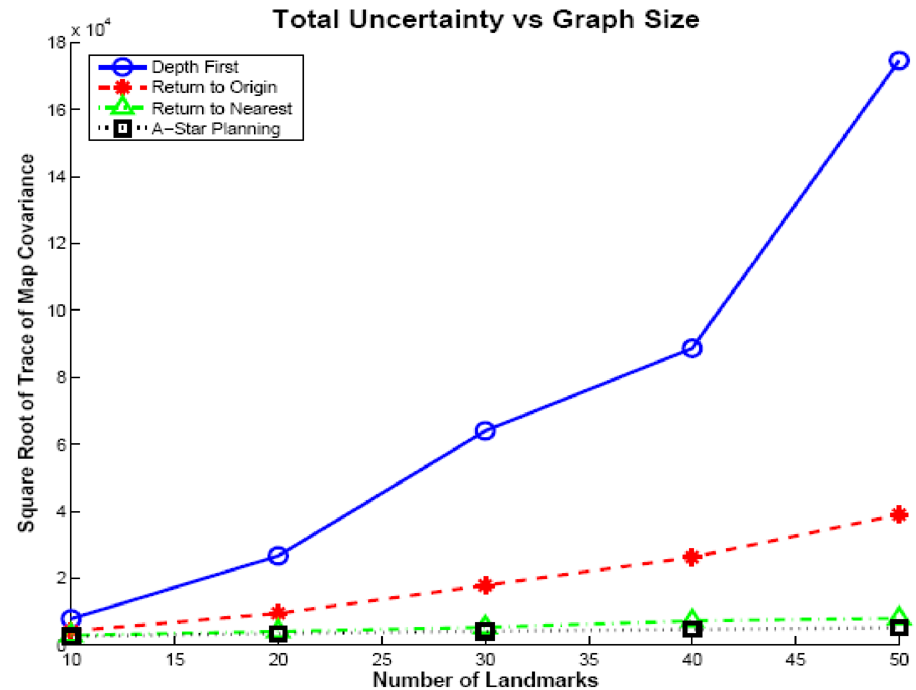
Simulated Relocalization Results





Simulated Exploration Results





Key Points

- Mapping requires exploration
- Exploration strategies depend on the representation
- Topological representations are the most convenient for exploration
- Two objectives:
  - Explore new territory
  - Improve the accuracy by relocalization

References

- B. J. Kuipers and Y.-T. Byun. “A robot exploration and mapping strategy based on a semantic hierarchy of spatial representations”. In *Journal of Robotics and Autonomous Systems*, 8: 47-63, 1991.
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- QUESTIONS?