CS686: Configuration Space II

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(윤성의)

Course URL:
http://sgvr.kaist.ac.kr/~sungeui/MPA

Class Objectives (Ch. 3)

- **Configuration space**
  - **Definitions and examples**
  - **Obstacles**
  - **Paths**
  - **Metrics**

- **Last time:**
  - **Degrees-of-freedom (DoFs) of C-space w/ holonomic, non-holonomic and dynamic constraints**

Obstacles in the Configuration Space

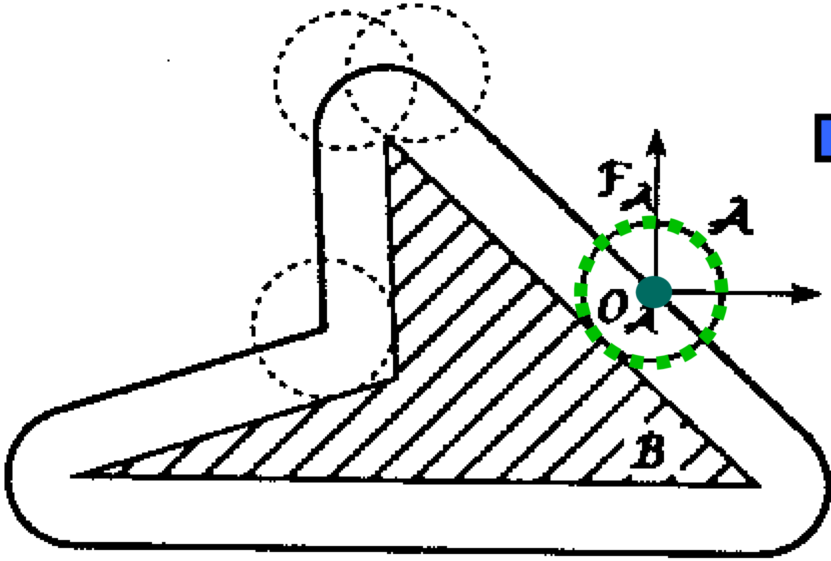
- **A configuration q is collision-free, or free, if a moving object placed at q does not intersect any obstacles in the workspace**

- **The free space F is the set of free configurations**

- **A configuration space obstacle (C-obstacle) is the set of configurations where the moving object collides with workspace obstacles**

Disc in 2-D Workspace

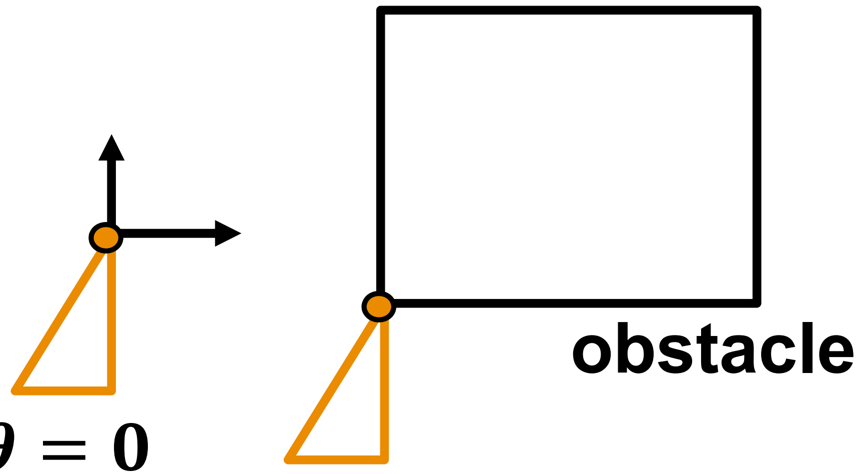
workspace



configuration space

Polygonal Robot Translating & Rotating in 2-D Workspace

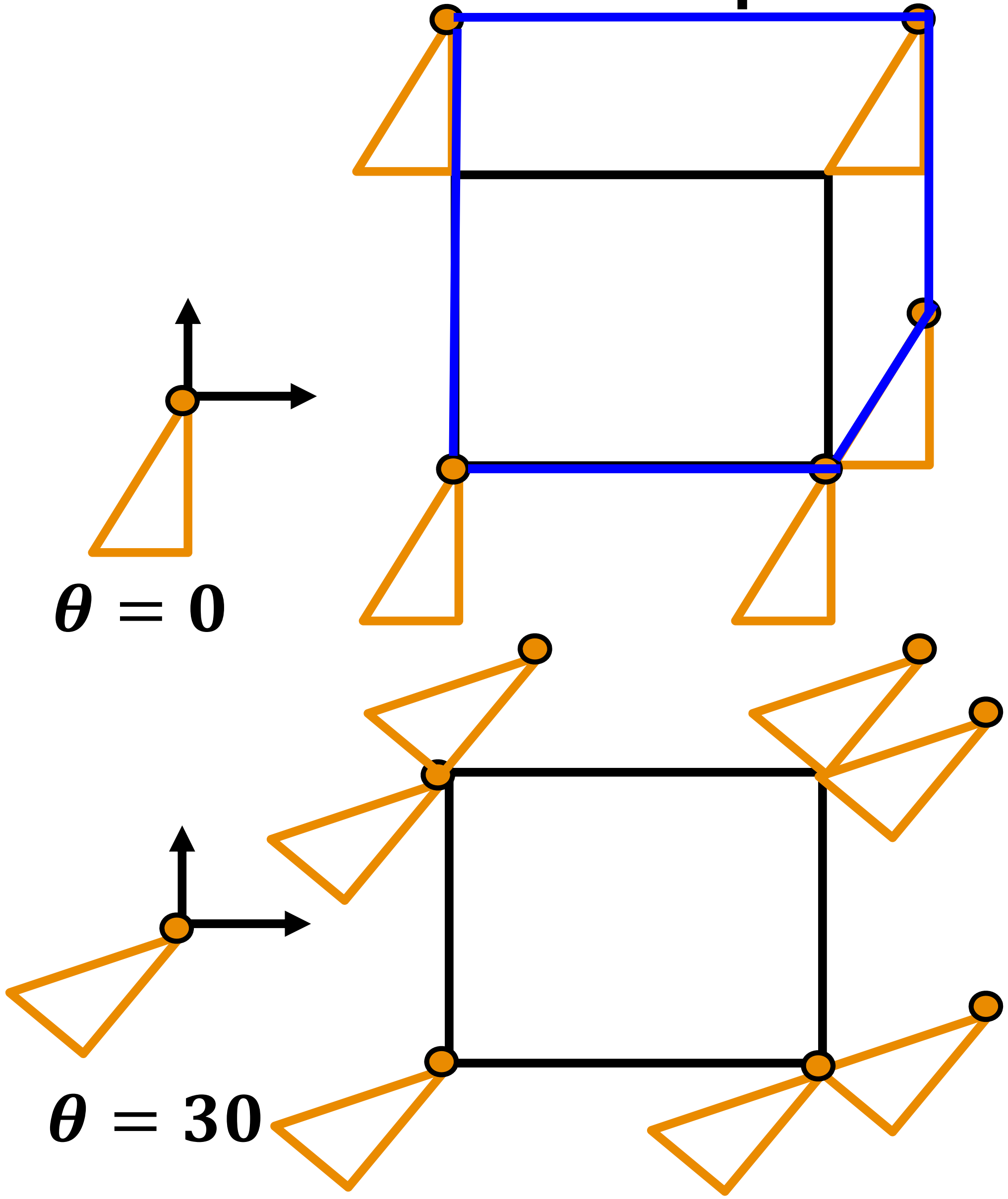
Workspace **C-space**



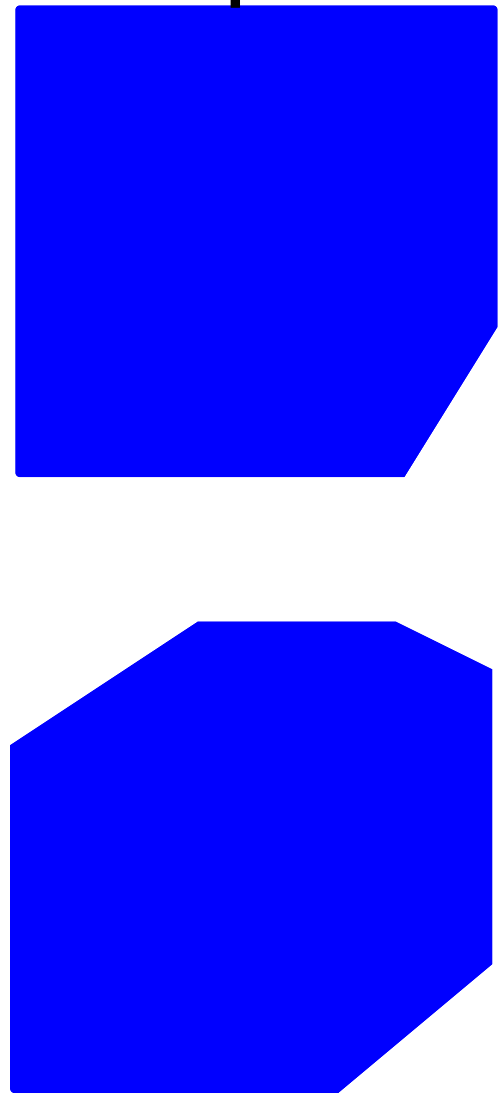
$\theta = 0$

Polygonal Robot Translating & Rotating in 2-D Workspace

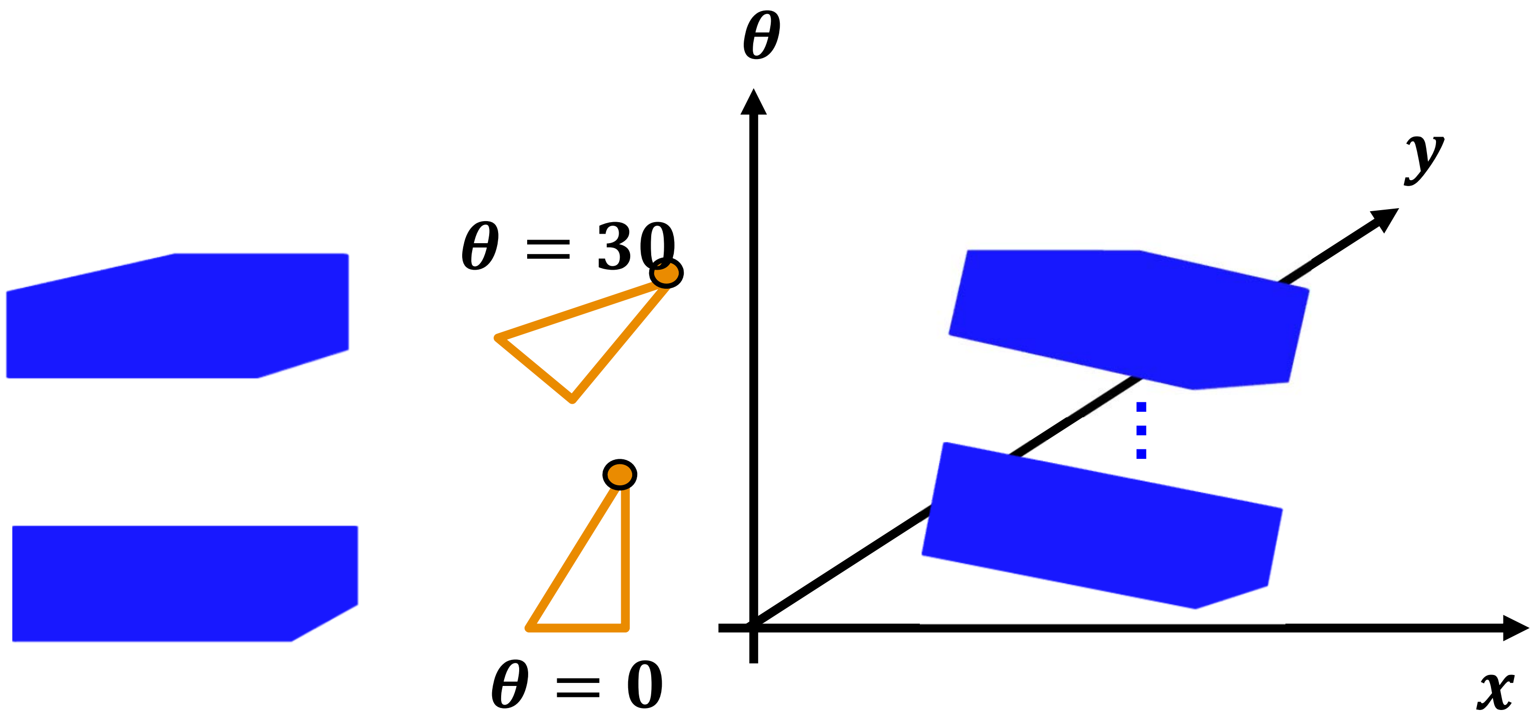
Workspace



C-space



Polygonal Robot Translating & Rotating in 2-D Workspace



3D C-space

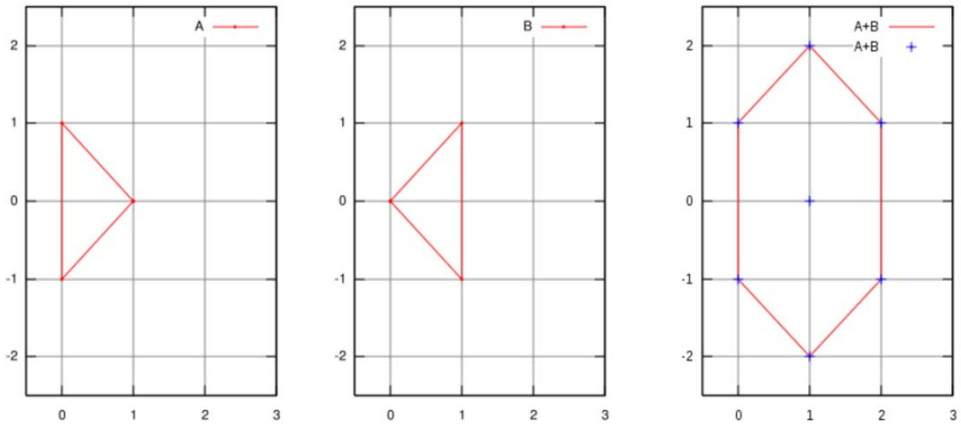
C-Obstacle Construction

- **Input:**
  - **Polygonal moving object translating in 2-D workspace**
  - **Polygonal obstacles**
- **Output:**
  - **Configuration space obstacles represented as polygons**

Minkowski Sum

- **The Minkowski sum of two sets P and Q, denoted by $P \oplus Q$, is defined as**

$$P \oplus Q = \{\, p+q \mid p \in P,\ q \in Q \,\}$$



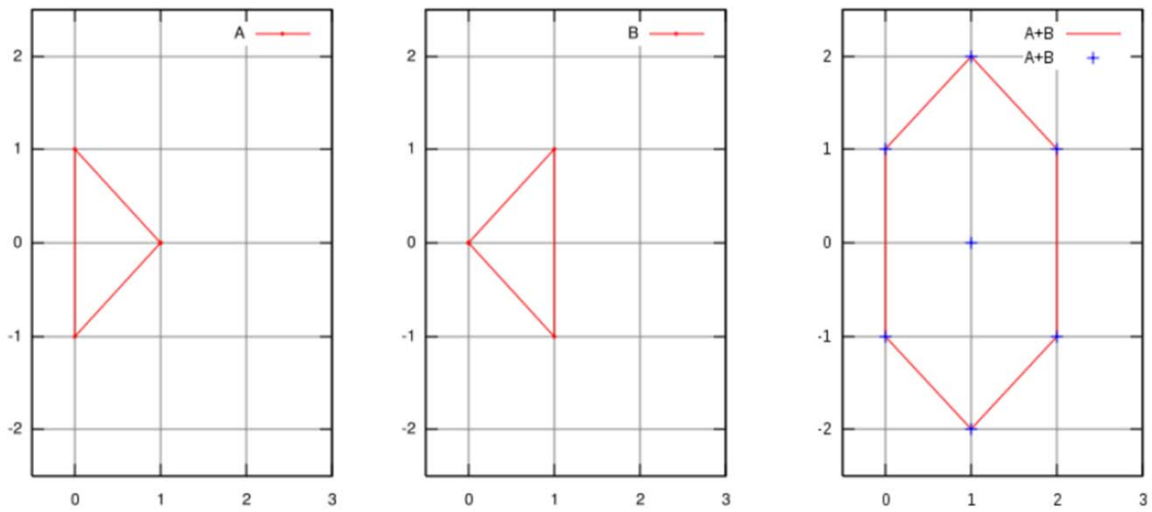
wiki

- **Similarly, the Minkowski difference is defined as**

$$P \ominus Q = \{\, p-q \mid p \in P,\ q \in Q \,\}$$
$$= P \oplus -Q$$

Minkowski Sum of Convex Polygons

- The Minkowski sum of two convex polygons P and Q of m and n vertices respectively is a convex polygon $P \oplus Q$ of $m + n$ vertices.
  - The vertices of $P \oplus Q$ are the "sums" of vertices of P and Q.



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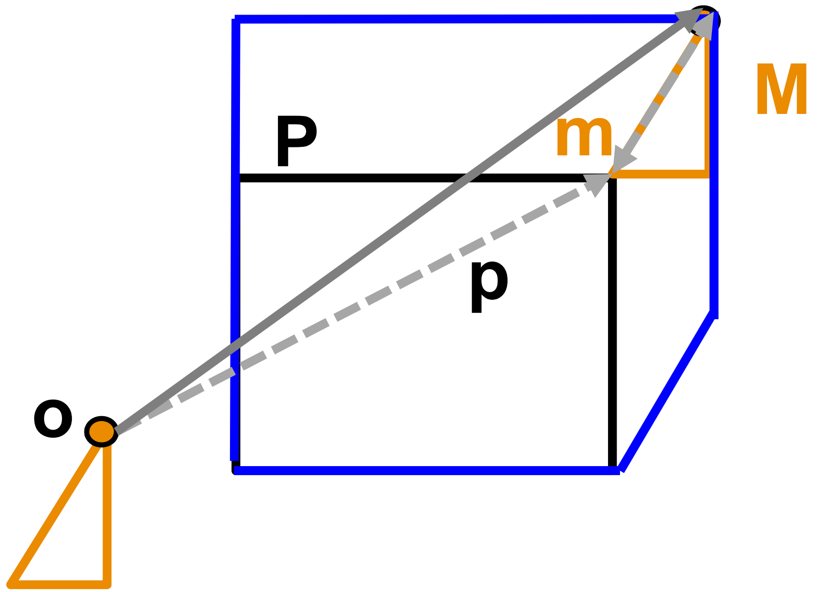
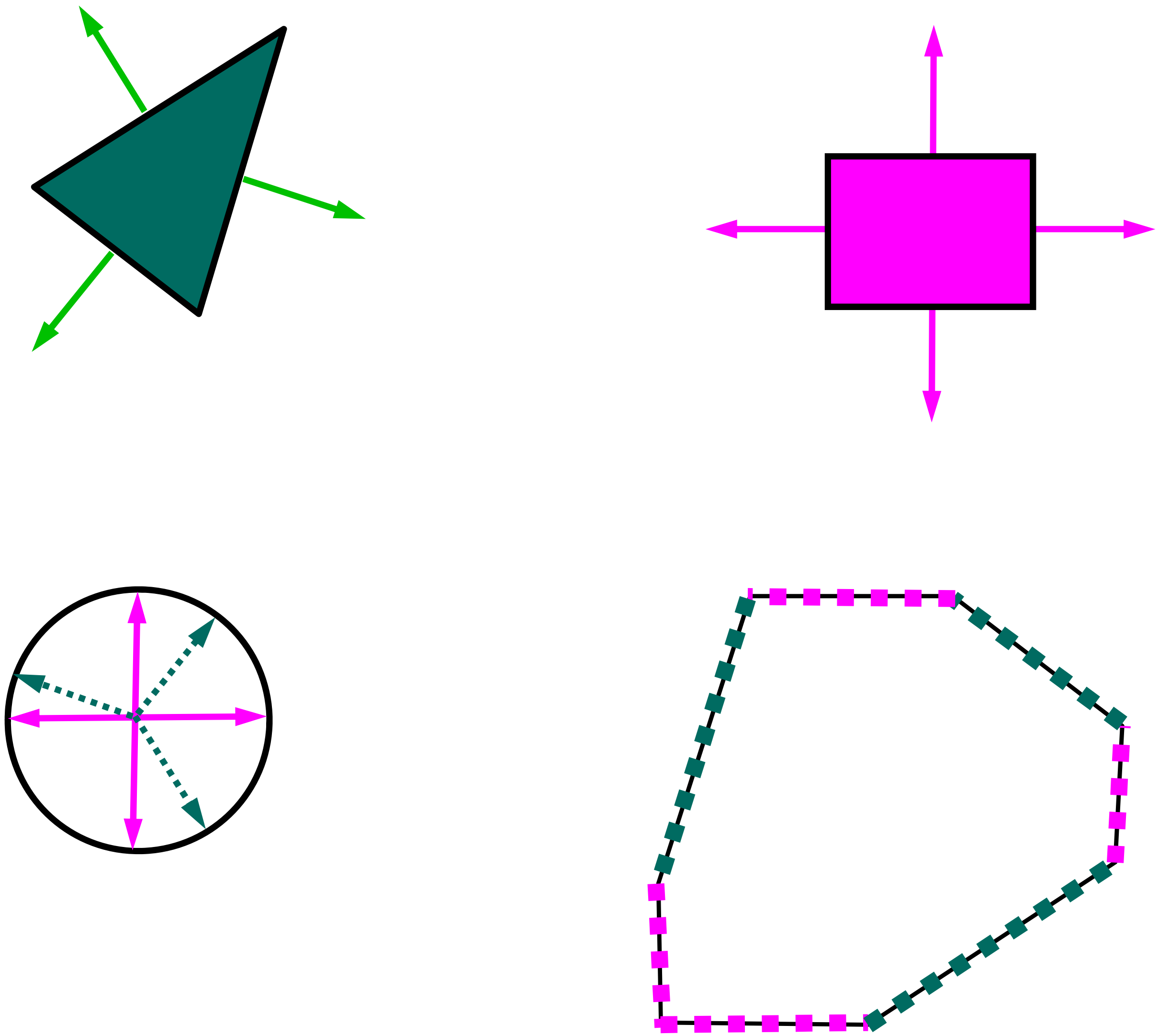
Observation

- Suppose P is an obstacle in the workspace and M is a moving object
- Then the C-obstacle is $P \ominus M$



Computing C-obstacles



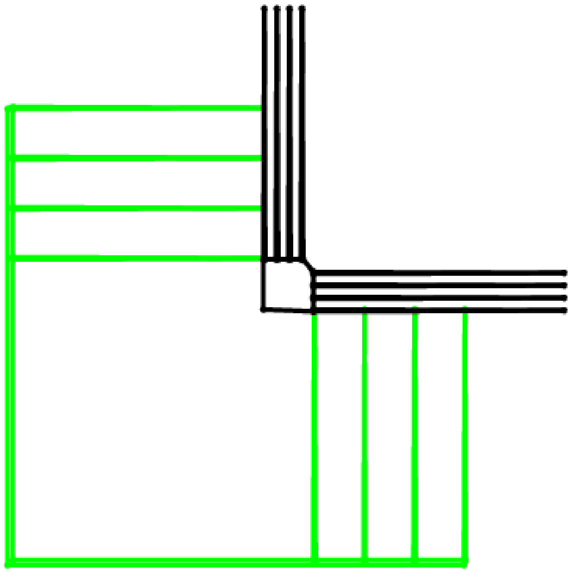
Computational efficiency

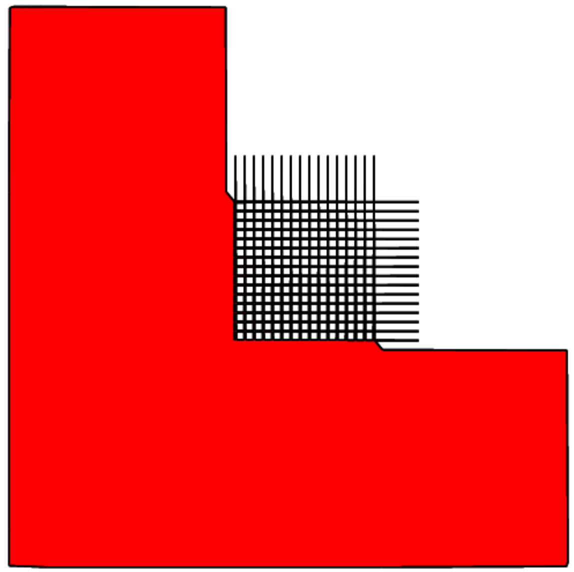
- Running time $O(n+m)$
- Space $O(n+m)$
- Non-convex obstacles
  - Decompose into convex polygons (*e.g.*, triangles or trapezoids), compute the Minkowski sums, and take the union
  - Complexity of Minkowksi sum $O(n^2m^2)$
- 3-D workspace
  - Convex case: $O(nm)$
  - Non-convex case: $O(n^3m^3)$

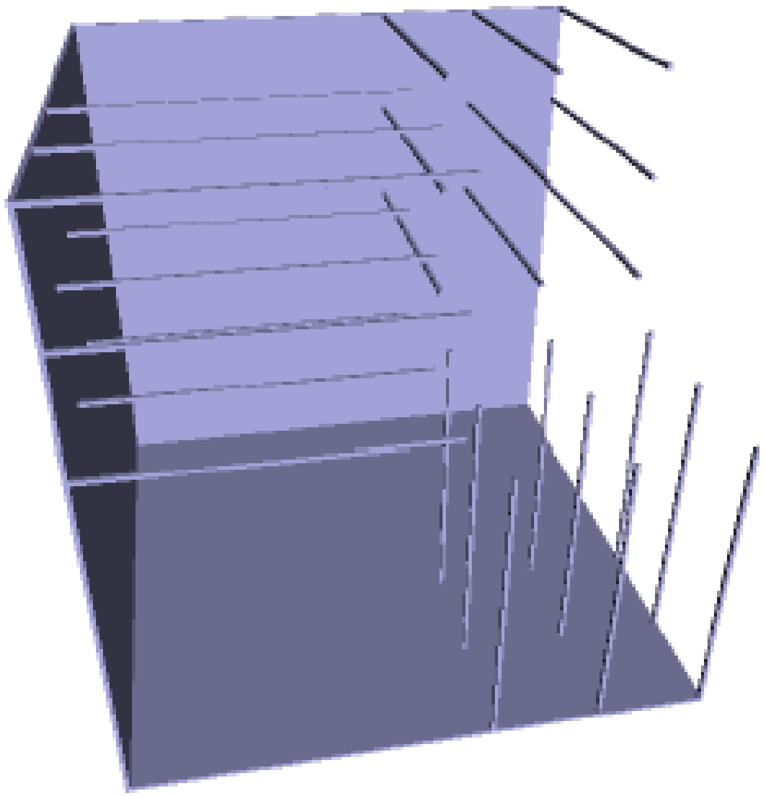
Worst case example

- $O(n^2m^2)$ **complexity**

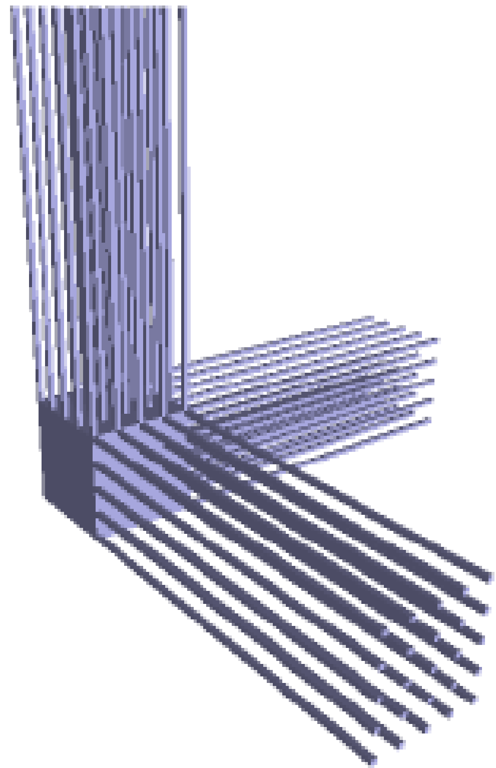
2D example
Agarwal et al. 02





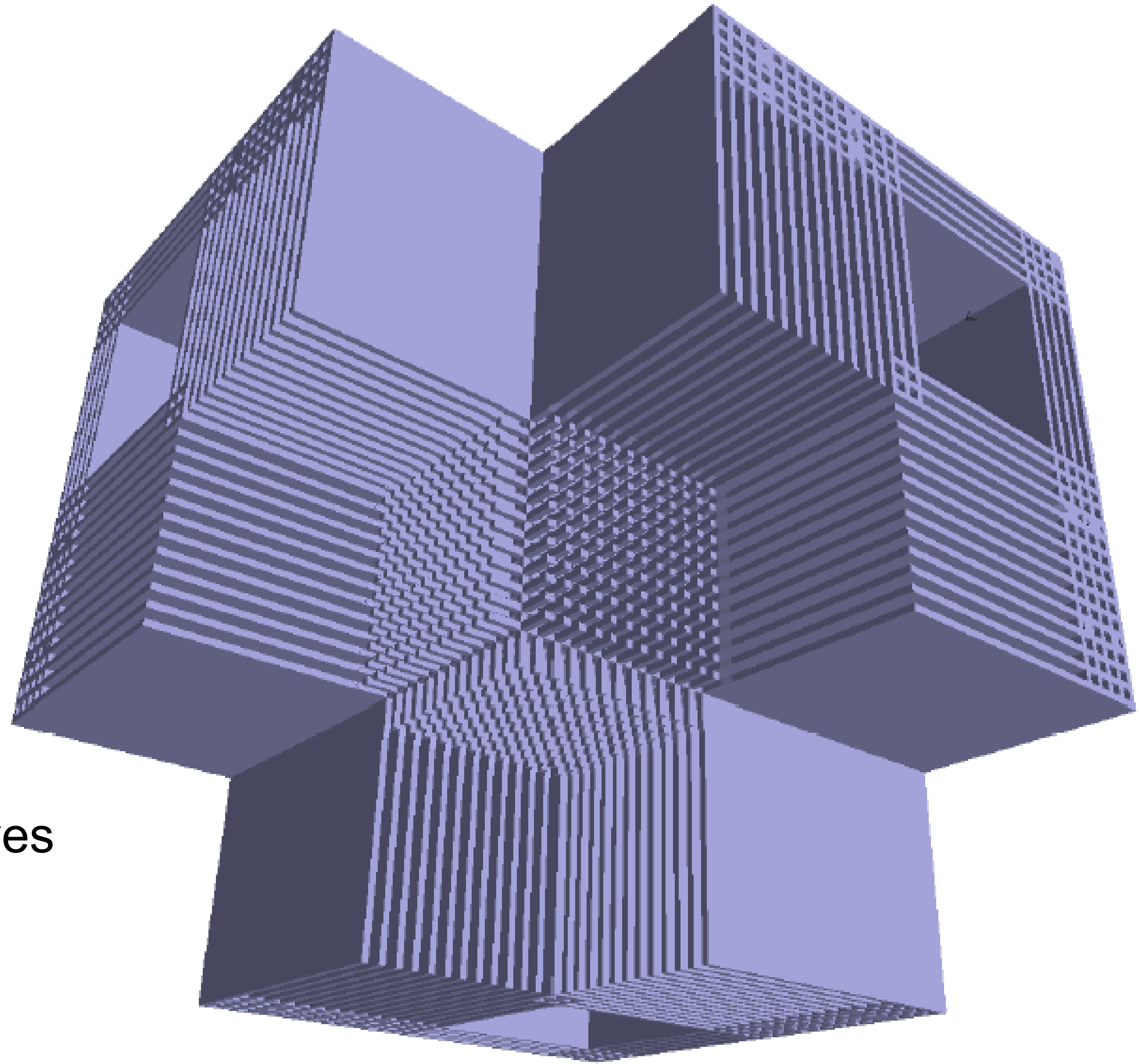


$\oplus$



444 tris

1,134 tris



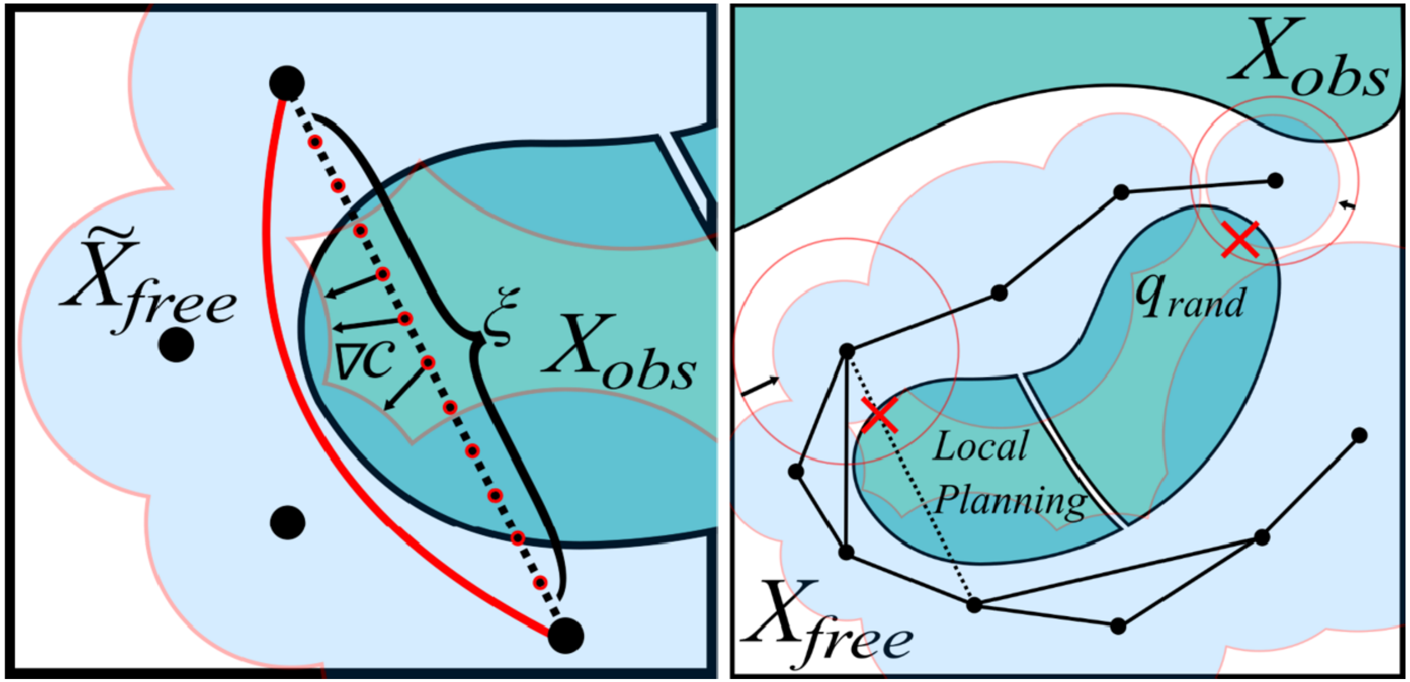
Union of
66,667 primitives

Main Message

- Computing the free or obstacle space in an accurate way is an expensive and non-trivial problem
- Lead to many sampling based methods
  - Locally utilize many geometric concepts developed for designing complete planners

Approximation of Configuration Free Space

- **Dancing PRM* : Simultaneous Planning of Sampling and Optimization with Configuration Free Space Approximation**
  - **Approximate C-Space and perform planning**
  - **Improve the quality in an iterative manner**



Video

KAIST

Sensors!

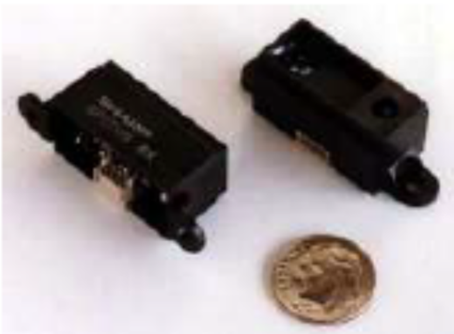
Robots' link to the external world...

sonar rangefinder

gyro

Sensors, sensors, sensors!
and tracking what is sensed: world models

compass



IR rangefinder

sonar rangefinder

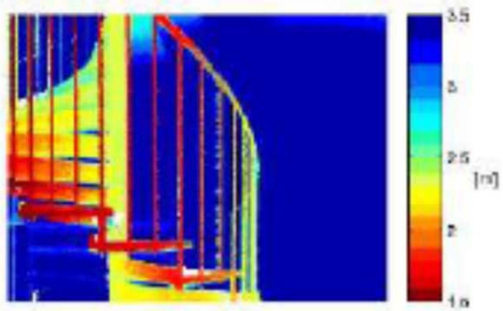
CMU cam with on-board processing

odometry…

Laser Ranging

LIDAR

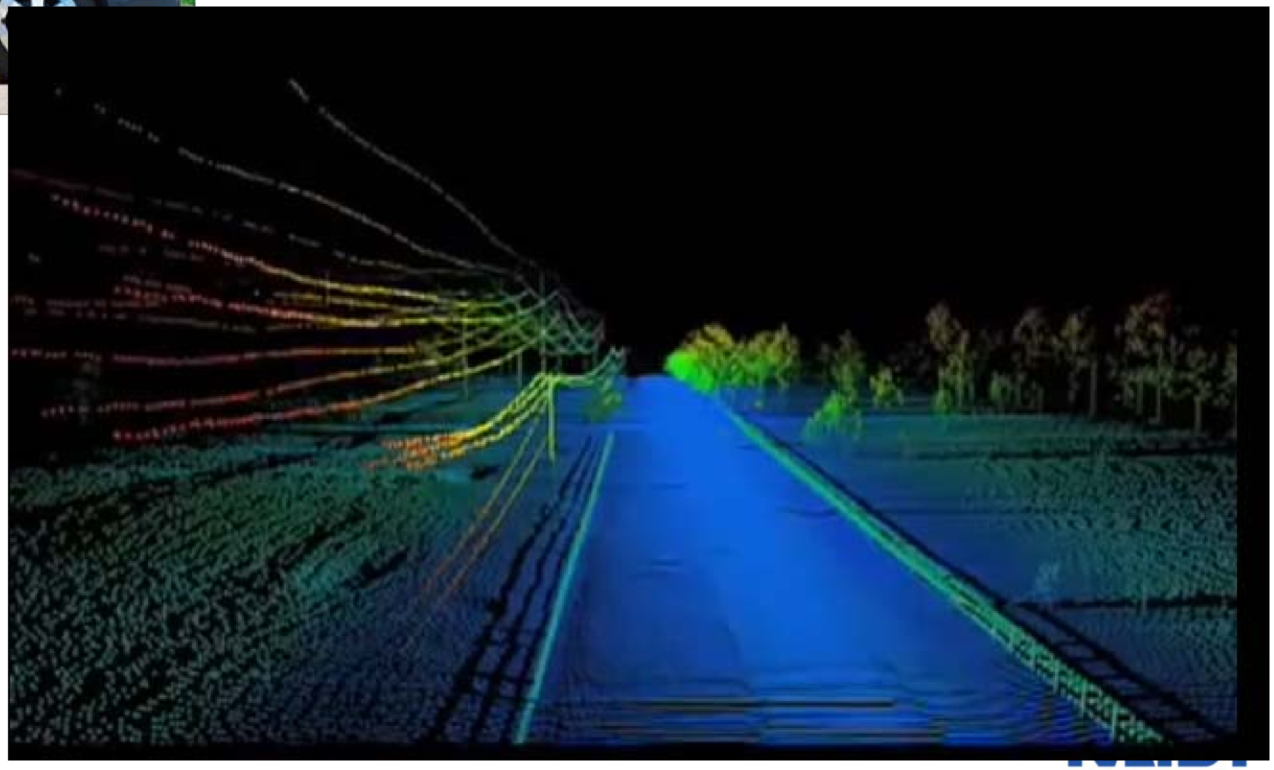
Sick Laser



LIDAR map

Sick laser range finder

Velodyne

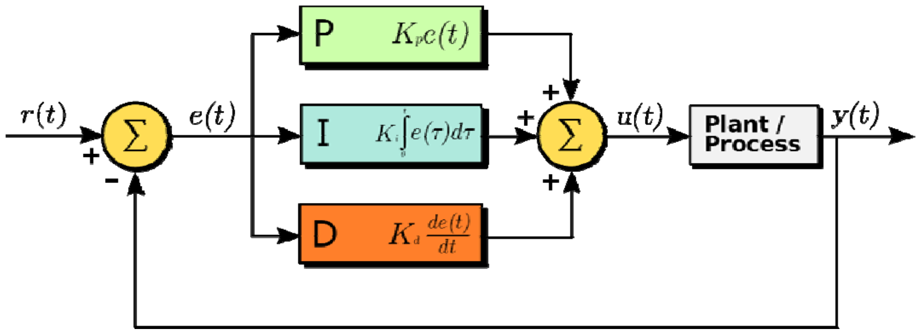


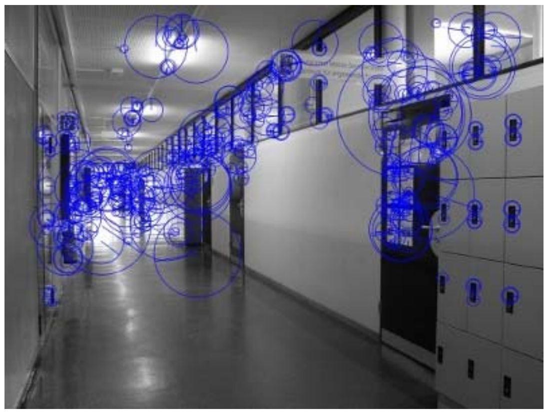
Kinect and Xtion

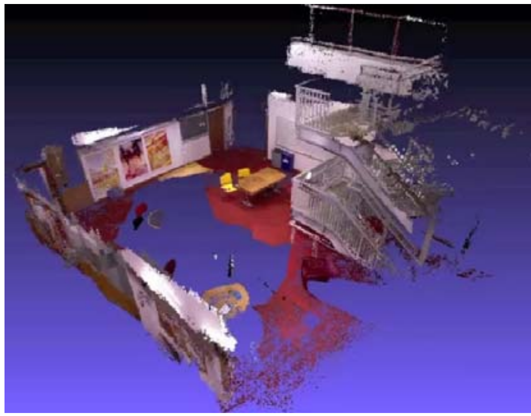
- **Kinect resolution**
  - **640×480 pixels @ 30 Hz (RGB camera)**
  - **640×480 pixels @ 30 Hz (IR depth-finding camera)**

Whole Picture

- **Sensor**
  - **Point clouds as obstacle map**
- **SLAM (Simultaneous Localization and Mapping)**
- **Path/motion planner**
- **Control**
  - **Compute force controls given a computed path**







Configuration space

- **Definitions and examples**
- **Obstacles**
- **Paths**
- **Metrics**

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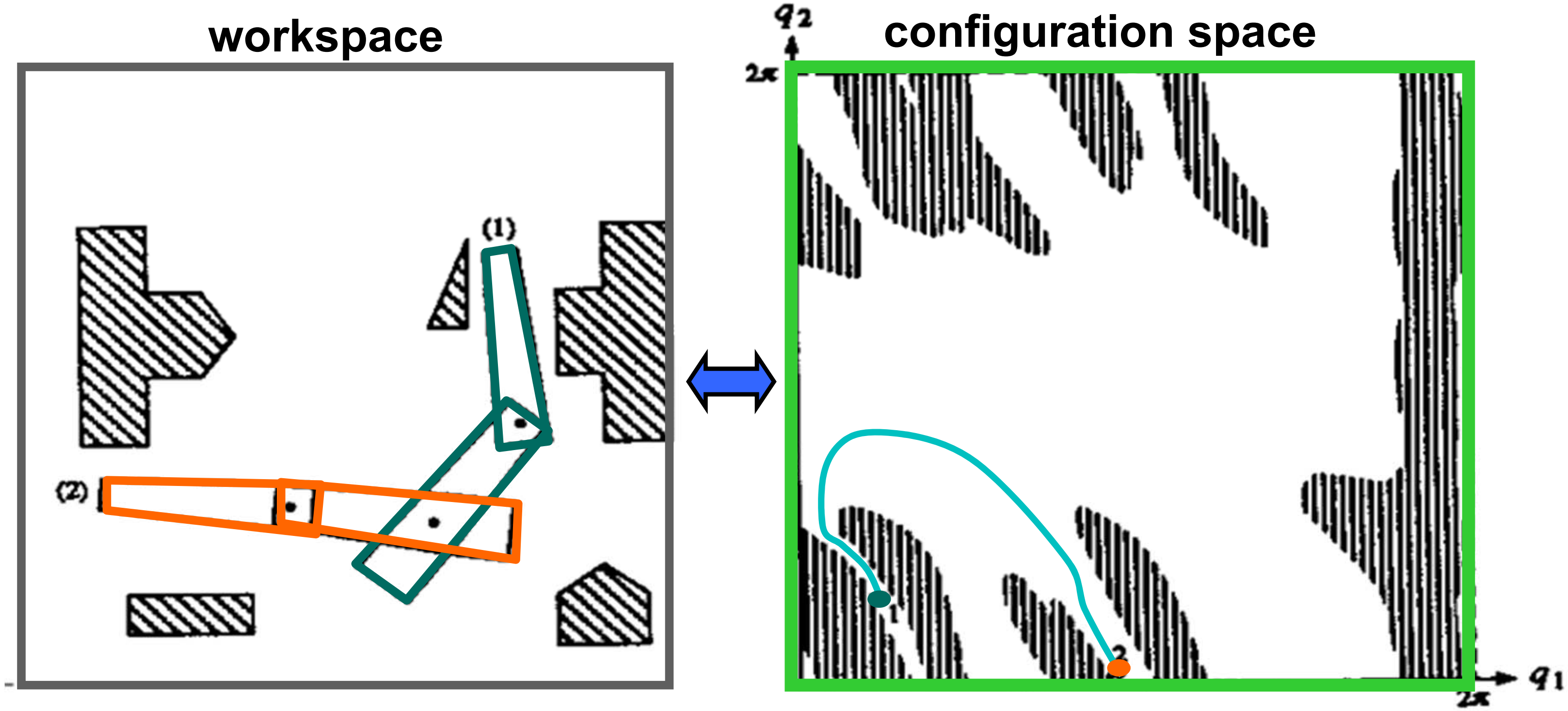
Paths in the configuration space



- **A path in C is a continuous curve connecting two configurations q and q':**

$$\tau : s \in [0,1] \rightarrow \tau(s) \in C$$

such that $\tau(0) = q$ and $\tau(1)=q'$.

Constraints on paths

- A **trajectory** is a path parameterized by time:

$$\tau : t \in [0, T] \rightarrow \tau(t) \in C$$

- Constraints
  - Finite length
  - Bounded curvature
  - Smoothness
  - Minimum length
  - Minimum time
  - Minimum energy
  - ...

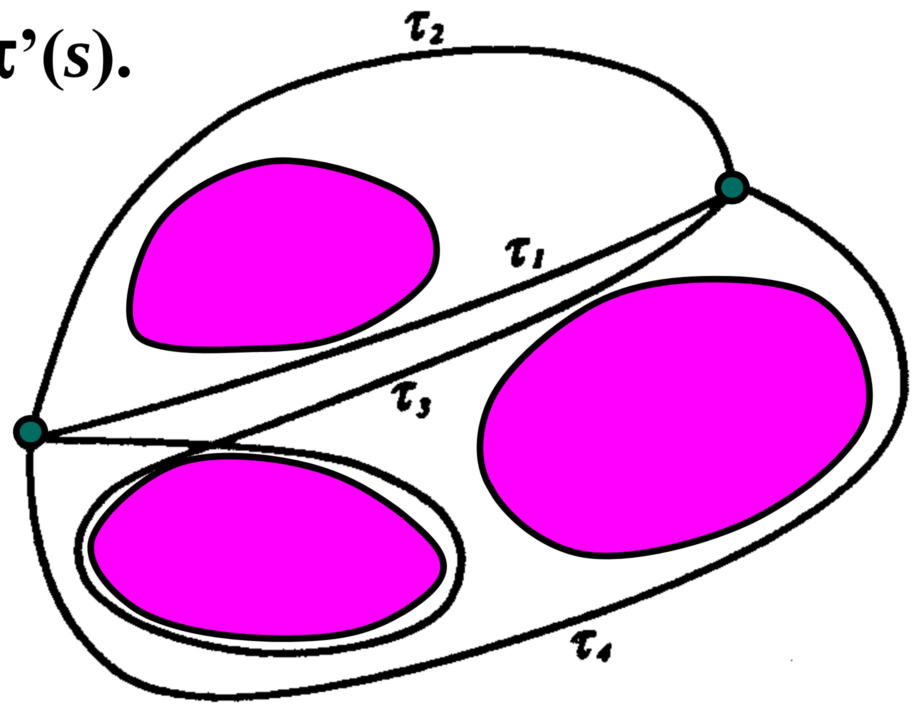
Homotopic Paths

- **Two paths τ and τ' (that map from U to V) with the same endpoints are homotopic if one can be continuously deformed into the other:**

$$h : U \times [0,1] \rightarrow V$$

with $h(s,0) = \tau(s)$ and $h(s,1) = \tau'(s)$.

- **A homotopic class of paths contains all paths that are homotopic to one another**



Configuration space

- Definitions and examples
- Obstacles
- Paths
- Metrics

Metric in Configuration Space

- **A metric or distance function d in a configuration space C is a function**

$$d:(q,q')\in C^2 \rightarrow d(q,q')\geq 0$$

such that

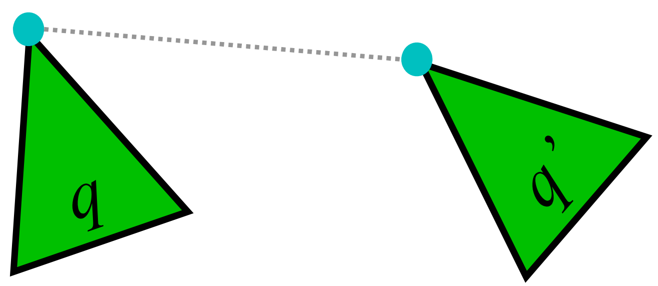
  - $d(q, q') = 0$ **if and only if** $q = q'$, Identity
  - $d(q, q') = d(q', q)$, Symmetry
  - $d(q,q') \leq d(q,q'') + d(q'',q')$. Triangle inequality

Example

- **Robot *A* and a point *x* on *A***
- **$x(q)$: position of *x* in the workspace when *A* is at configuration *q***
- **A distance *d* in *C* is defined by**

$$d(q, q') = \max_{x \in A} \| x(q) - x(q') \|,$$

where $||x - y||$ denotes the Euclidean distance between points *x* and *y* in the workspace.



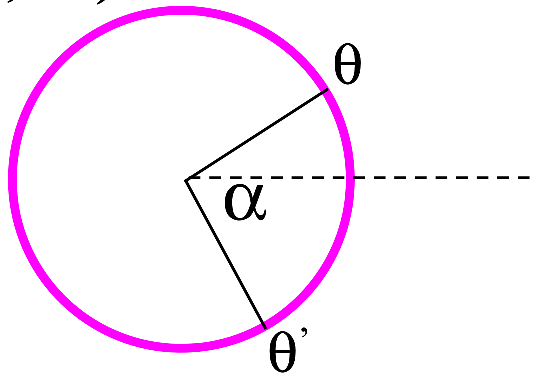
L_p Metrics

$$d(x, x') = \left(\sum_{i=1}^{n} | x_i - x_i' |^p \right)^{1/p}$$

- **L_2: Euclidean metric**
- **L_1: Manhattan metric**
- **L_∞: Max $(| x_i - x_i' |)$**

Examples in $R^2 \times S^1$

- **Consider** $R^2 \times S^1$
  - $q = (x, y, \theta)$, $q' = (x', y', \theta')$ **with** $\theta, \theta' \in [0, 2\pi)$
  - $\alpha = \min\{\, |\theta - \theta'|\,,\ 2\pi - |\theta - \theta'|\,\}$



- $d(q, q') = \mathrm{sqrt}(\, (x-x')^2 + (y-y')^2 + \alpha^2\,)$

Class Objectives were:

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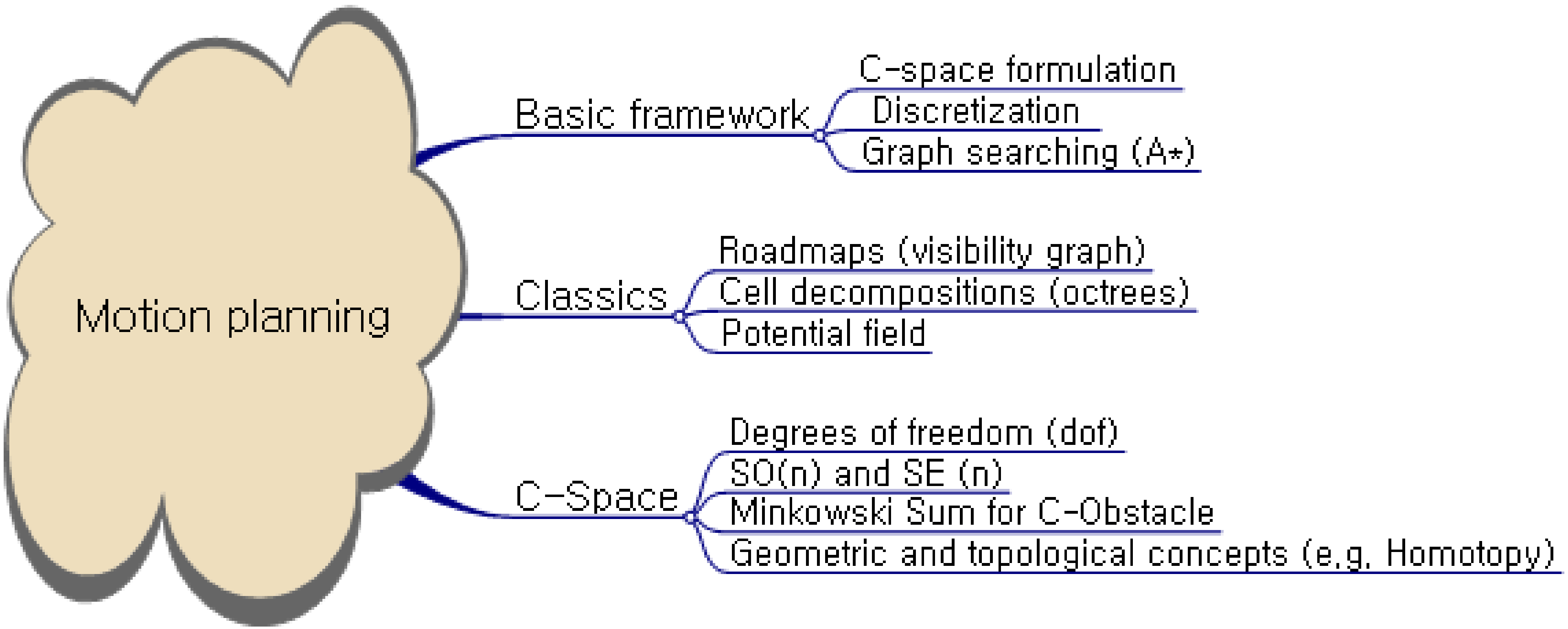
Summary


Motion planning
Basic framework
C-space formulation
Discretization
Graph searching (A*)
Classics
Roadmaps (visibility graph)
Cell decompositions (octrees)
Potential field
C-Space
Degrees of freedom (dof)
SO(n) and SE (n)
Minkowski Sum for C-Obstacle
Geometric and topological concepts (e.g. Homotopy)

Next Time….

- **Collision detection and distance computation**

Homework

- **Submit summaries of 2 ICRA/IROS/RSS/CoRL/TRO/IJRR papers**
- **Go over the next lecture slides**
- **Come up with two questions before the mid-term exam**