UNIVERSITÀ DEGLI STUDI DELLA BASILICATA

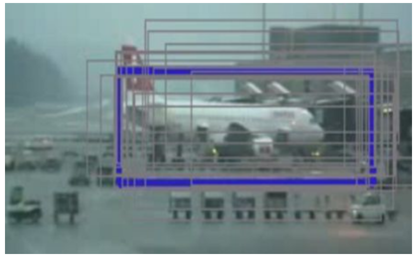


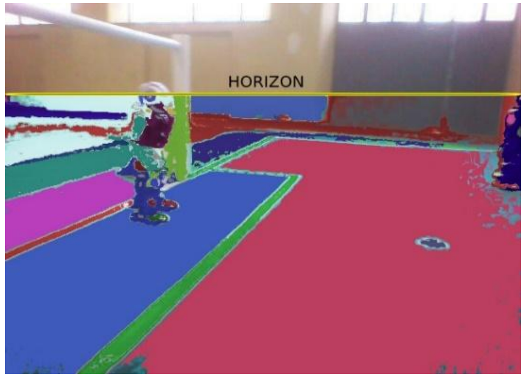
Corso di Visione e Percezione

Docente

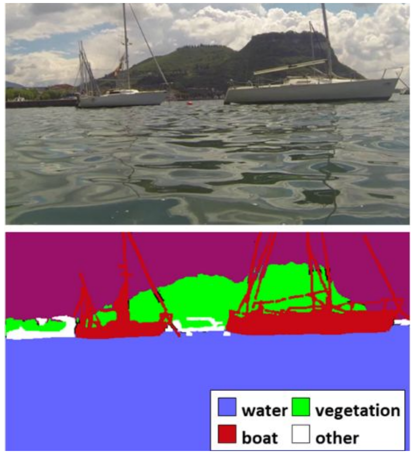
Domenico D. Bloisi

Navigazione in ROS







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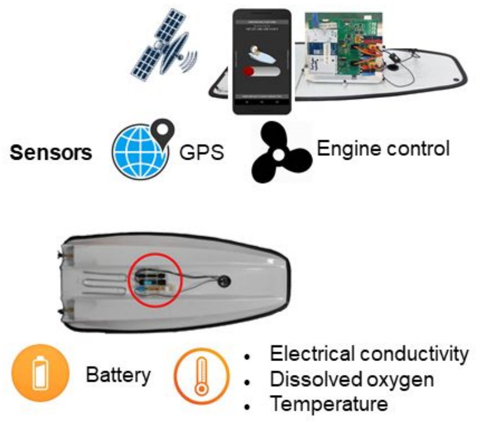
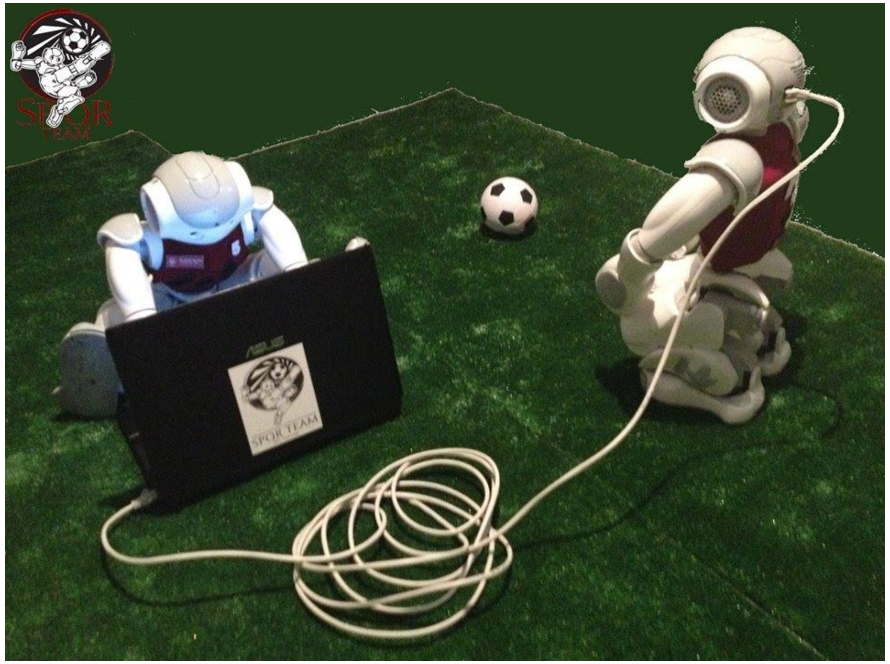
- SPQR Robot Soccer Team
Dipartimento di Informatica, Automatica e Gestionale Università degli studi di Roma “La Sapienza”
http://spqr.diag.uniroma1.it





Informazioni sul corso

- Home page del corso
  http://web.unibas.it/bloisi/corsi/visione-e-percezione.html
- Docente: Domenico Daniele Bloisi
- Periodo: II semestre marzo 2021 – giugno 2021

  Martedì 17:00-19:00 (Aula COPERNICO)
  Mercoledì 8:30-10:30 (Aula COPERNICO)

Codice corso Google Classroom:
https://classroom.google.com/c/NjI2MjA4MzgzNDFa?cjc=xgolays

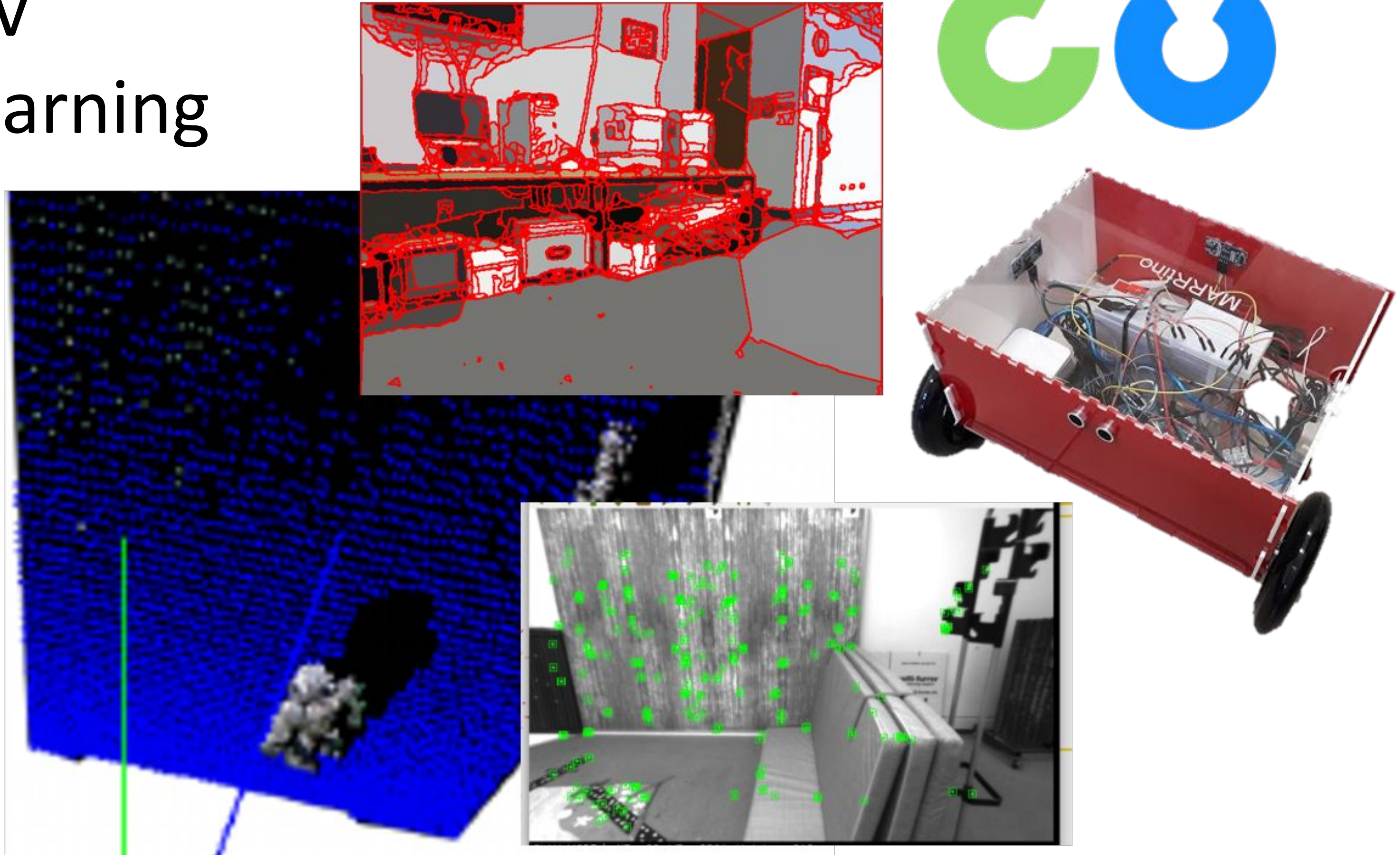
Ricevimento

- Su appuntamento tramite Google Meet

Per prenotare un appuntamento inviare una email a
domenico.bloisi@unibas.it

Programma – Visione e Percezione

- Introduzione al linguaggio Python
- Elaborazione delle immagini con Python
- Percezione 2D – OpenCV
- Introduzione al Deep Learning
- ROS
- Il paradigma publisher and subscriber
- Simulatori
- Percezione 3D - PCL



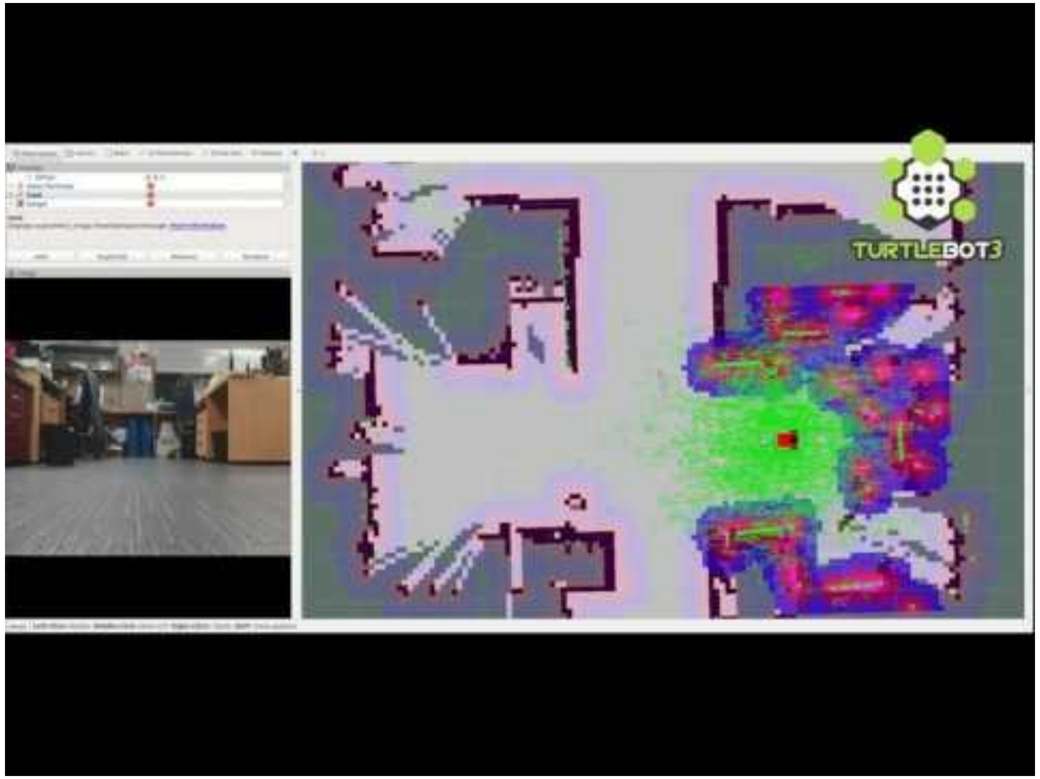
References and credits

Alcune delle slide seguenti sono tratte da

- Giorgio Grisetti, “*Introduction to Navigation using ROS*”
- Giorgio Grisetti, “*Introduction*” in Probabilistic Robotics Course
- Giorgio Grisetti, *“Multi-Pose Registration Graph-SLAM” in* Probabilistic Robotics Course
- YoonSeok Pyo, HanCheol Cho, RyuWoon Jung, TaeHoon Lim,
  “ROS Robot Programming - A Handbook Written by TurtleBot3 Developers”
  http://www.robotis.com/service/download.php?no=719
- Learn TurtleBot and ROS (http://learn.turtlebot.com/)
  - Creating a Map
  - Autonomous Navigation

Navigazione con robot mobili

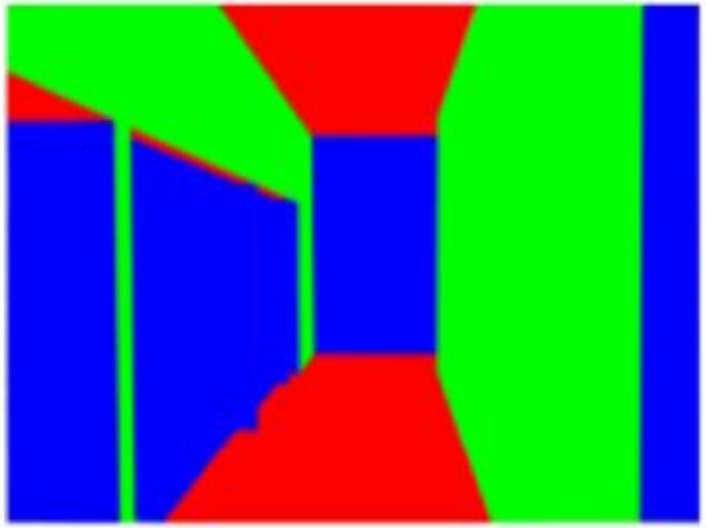
Il compito principale che un robot autonomo mobile deve essere in grado di compiere è quello di saper muoversi nell'ambiente operativo



https://www.youtube.com/watch?v=lOZmFC79S6A

Ambiente operativo

Strutturato



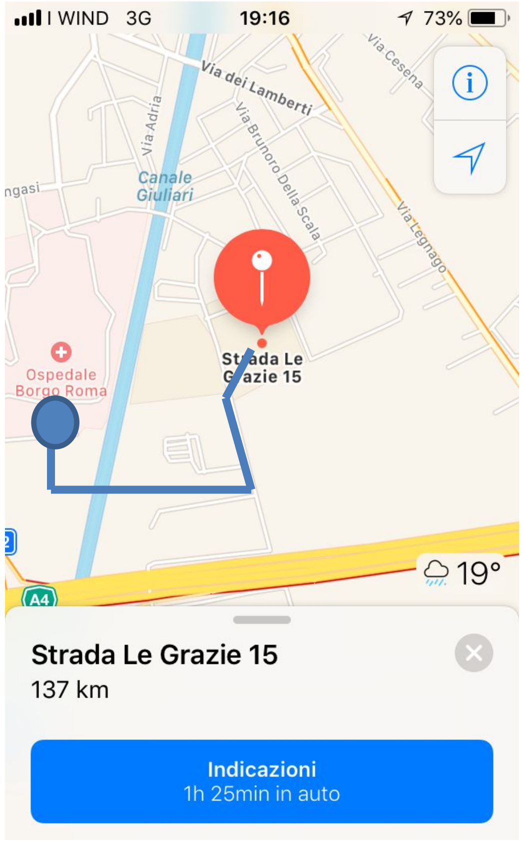
Non strutturato

Navigazione GPS

Il navigatore, che utilizziamo nella vita di tutti i giorni, ci fornisce tre elementi di base:

1. una mappa
2. la nostra posizione sulla mappa
3. una rotta per la destinazione desiderata

Questi tre elementi sono necessari per muoversi con successo nell'ambiente



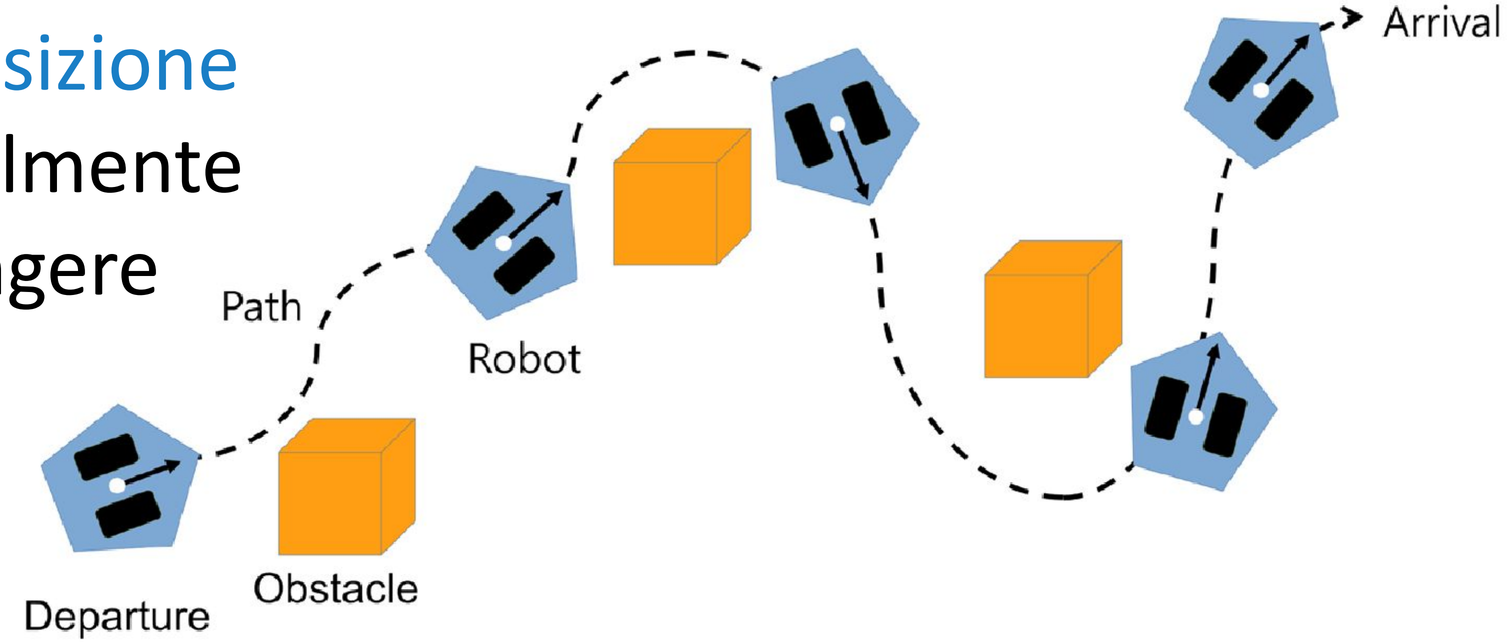
Sono sufficienti?

Navigazione robotica

Con il termine navigazione indichiamo il movimento del robot verso una destinazione predefinita

Per poter navigare, un robot ha bisogno di:

1. Avere una mappa dell'ambiente
2. Conoscere la propria posizione
3. Avere una rotta (possibilmente ottimizzata) per raggiungere la destinazione
4. Evitare gli ostacoli presenti sul percorso



Ostacoli fissi e mobili

In base all'ambiente operativo in cui il robot si trova ad agire, si avranno

- ostacoli fissi
  muri e scale sono esempi di ostacoli fissi

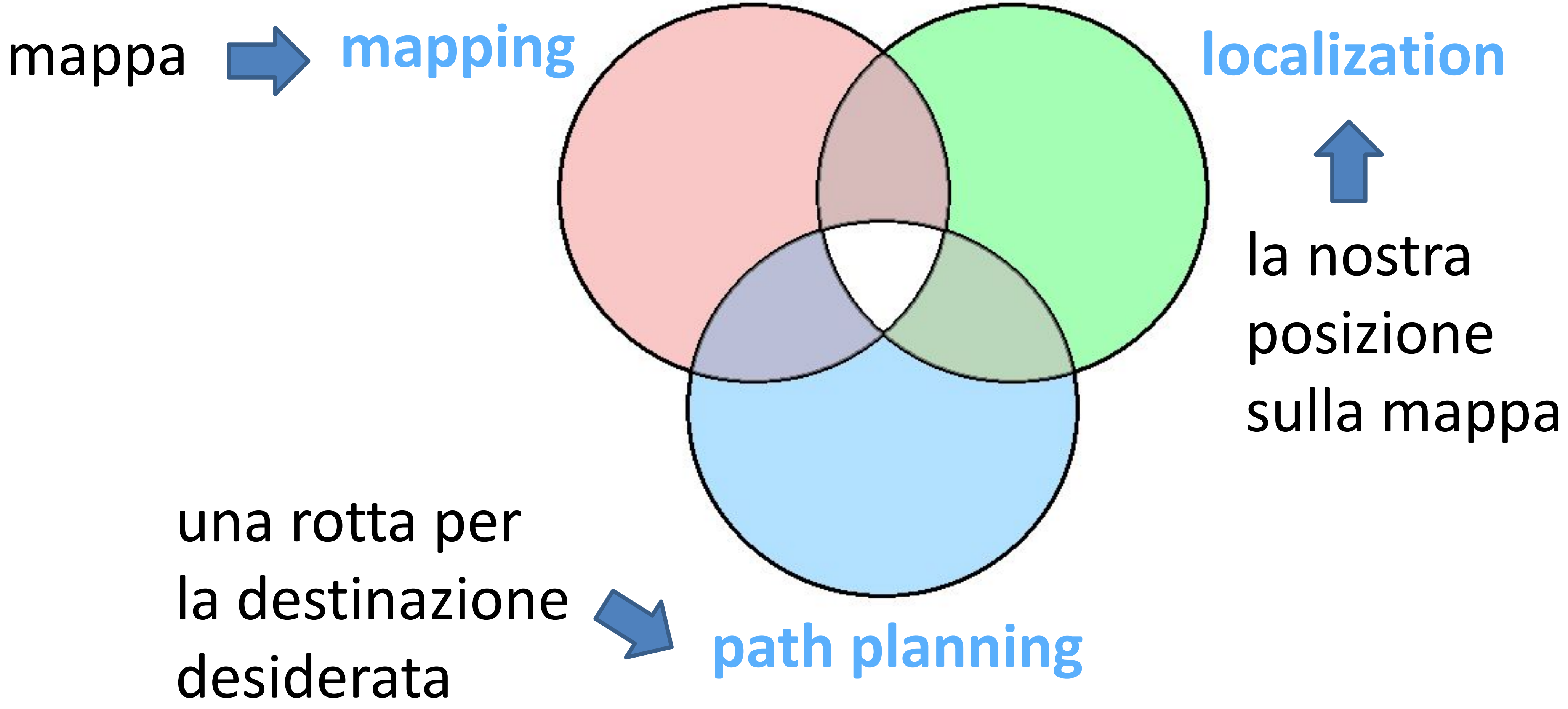
- ostacoli mobili
  persone e sedie sono esempi di ostacoli mobili

Basic features

Affinché il robot sia in grado di navigare autonomamente in un ambiente con ostacoli avremo bisogno di

❶ Map
❷ Pose of Robot
❸ Sensing
❹ Path Calculation and Driving

Mapping, localization, planning

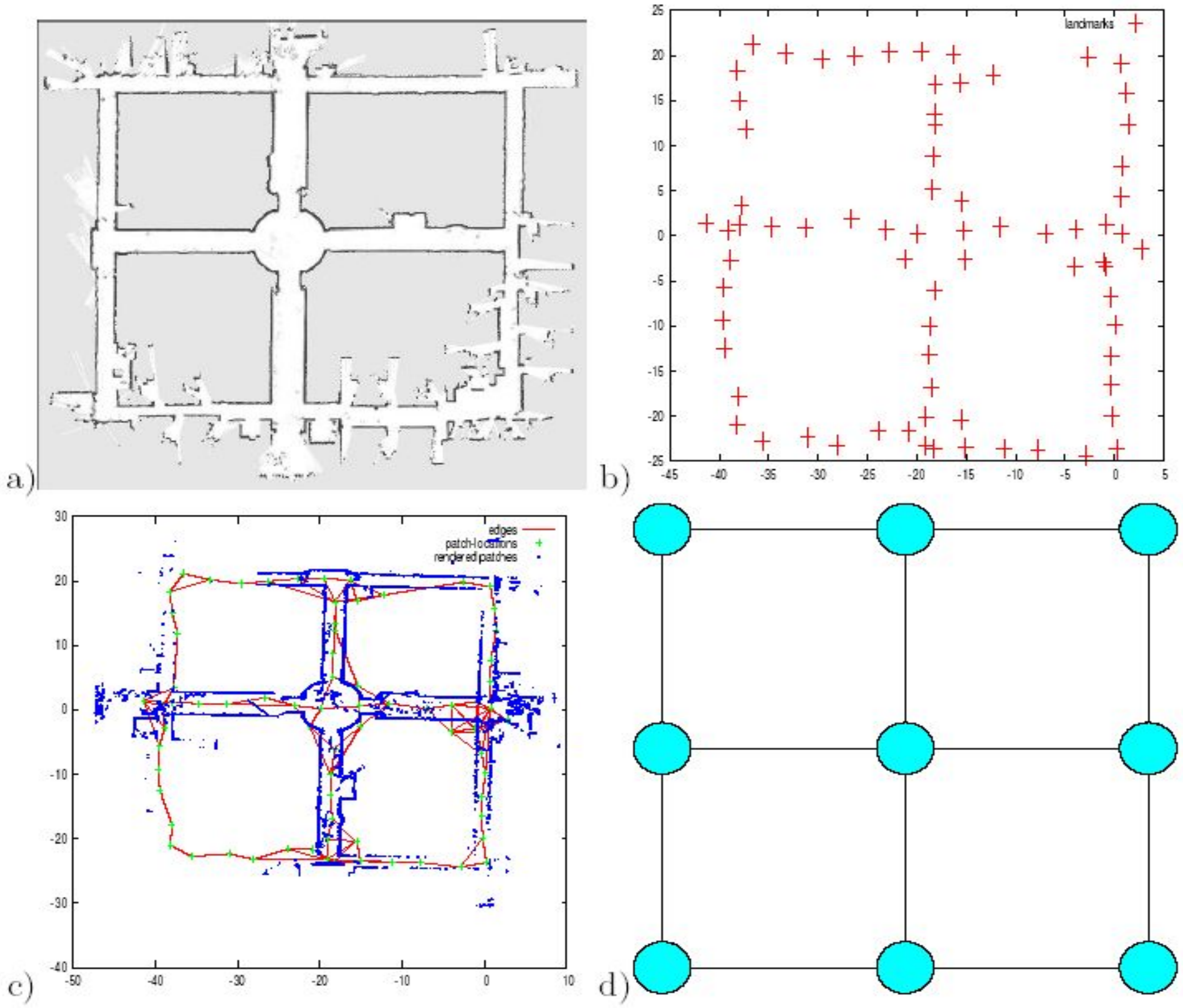


Map

- A map is a representation of the environment where the robot is operating
- It should contain enough information to accomplish a task of interest

Representations:

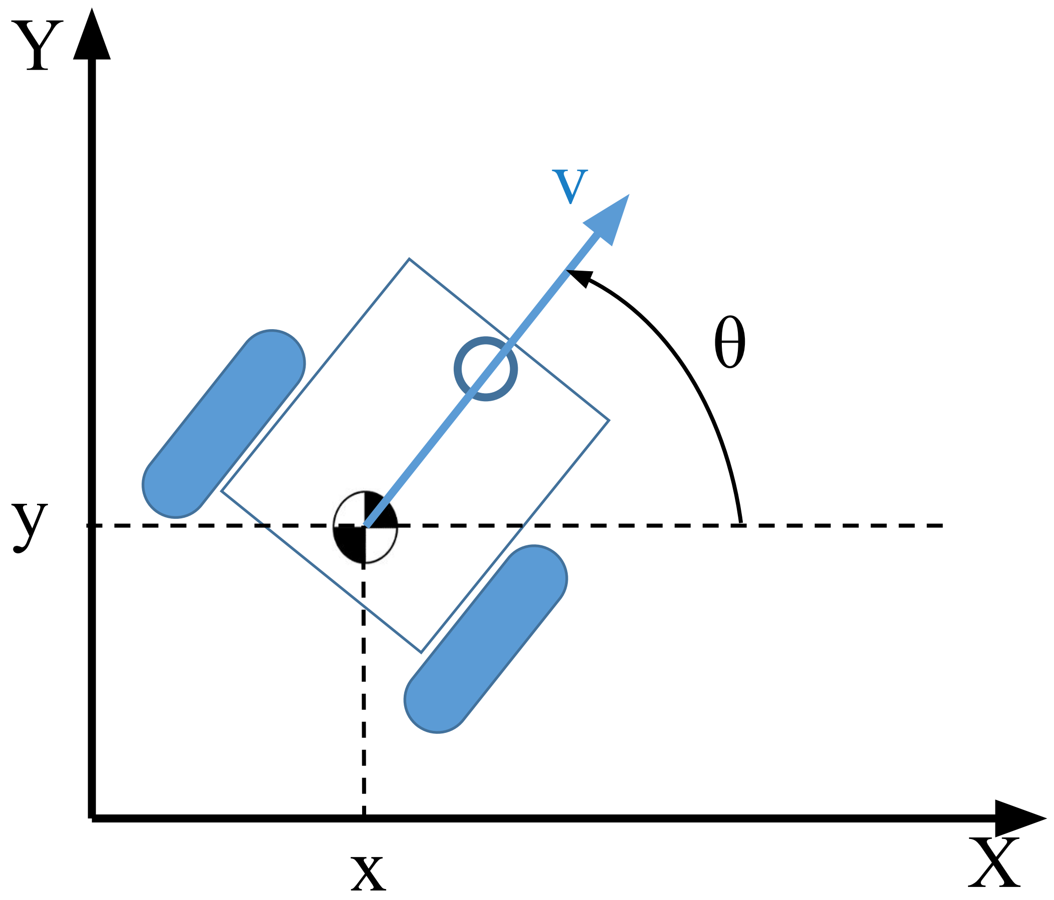
- Metric
  - Grid Based
  - Feature Based
  - Hybrid
- Topological
- Hybrid



Robot pose

- La *robot pose* è definita come la posizione del robot e la sua orientazione in un dato sistema di riferimento

- Per un robot mobile che si muove su un piano, la *pose* è definita dalla tripla [x, y, θ]



Introduction to Autonomous Mobile Robots
Roland Siegwart, Illah Nourbakhsh, Davide Scaramuzza

Pose in ROS

geometry_msgs/Pose Message

File: geometry_msgs/Pose.msg

Raw Message Definition

```
# A representation of pose in free space, composed of position and orientation.
Point position
Quaternion orientation
```

Compact Message Definition

geometry_msgs/Point position
geometry_msgs/Quaternion orientation

http://docs.ros.org/api/geometry_msgs/html/msg/Pose.html

Position in ROS

pose = position + orientation

geometry_msgs/Point Message

File: geometry_msgs/Point.msg

Raw Message Definition

```
# This contains the position of a point in free space
float64 x
float64 y
float64 z
```

Compact Message Definition

```
float64 x
float64 y
float64 z
```

Orientation in ROS

pose = position + orientation

geometry_msgs/Quaternion Message

File: geometry_msgs/Quaternion.msg

Raw Message Definition

```
# This represents an orientation in free space in quaternion form.

float64 x
float64 y
float64 z
float64 w
```

Compact Message Definition

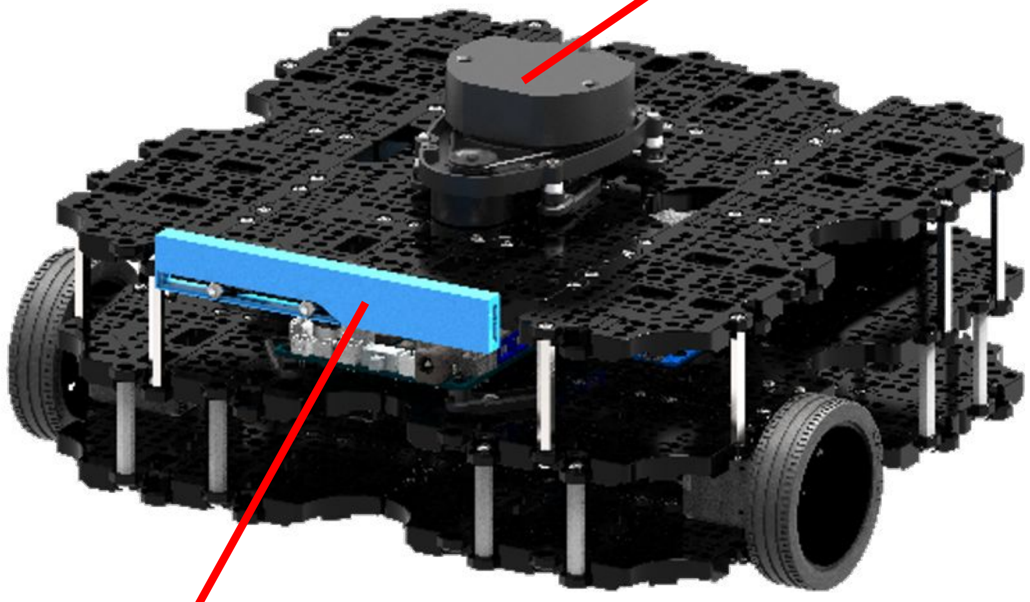
```
float64 x
float64 y
float64 z
float64 w
```

http://wiki.ros.org/tf2/Tutorials/Quaternions

http://run.usc.edu/cs520-s12/quaternions/quaternions-cs520.pdf

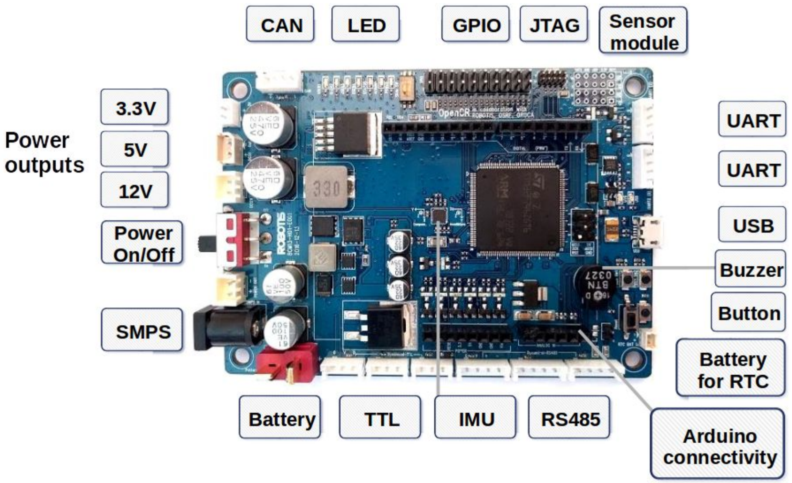
Sensing – Turtlebot3

360 Laser Distance Sensor LDS-01



Intel® Realsense™ R200

OpenCR1.0



Gyroscope 3Axis, Accelerometer 3Axis, Magnetometer 3Axis

http://emanual.robotis.com/docs/en/platform/turtlebot3/hardware_setup/#hardware-setup

Sensori di distanza

- Sonar

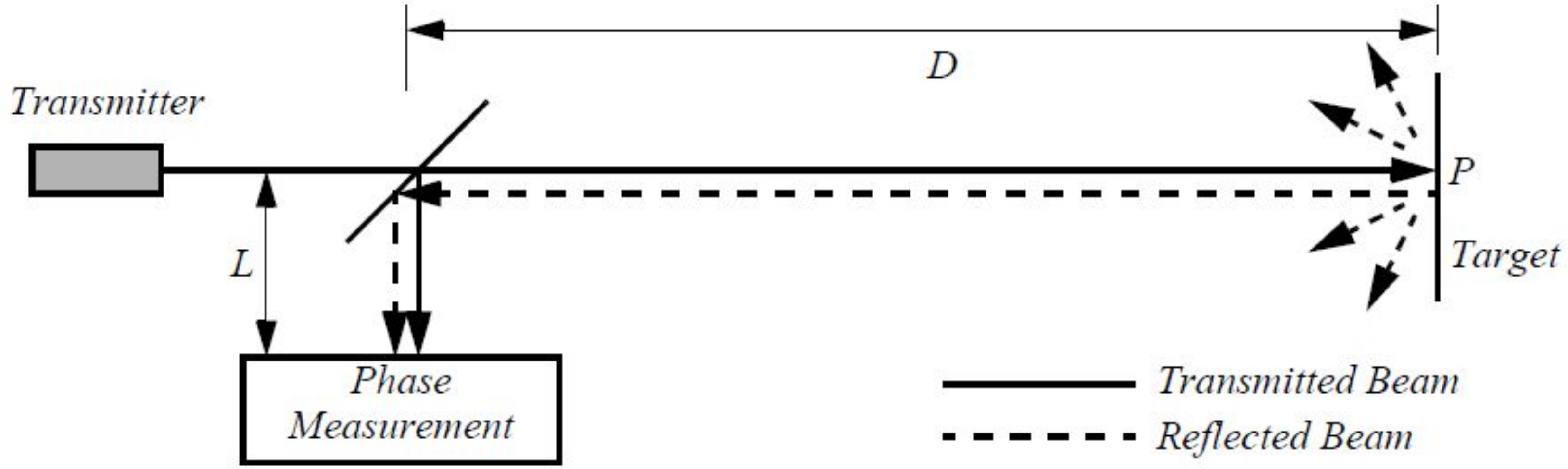
- Laser range finder

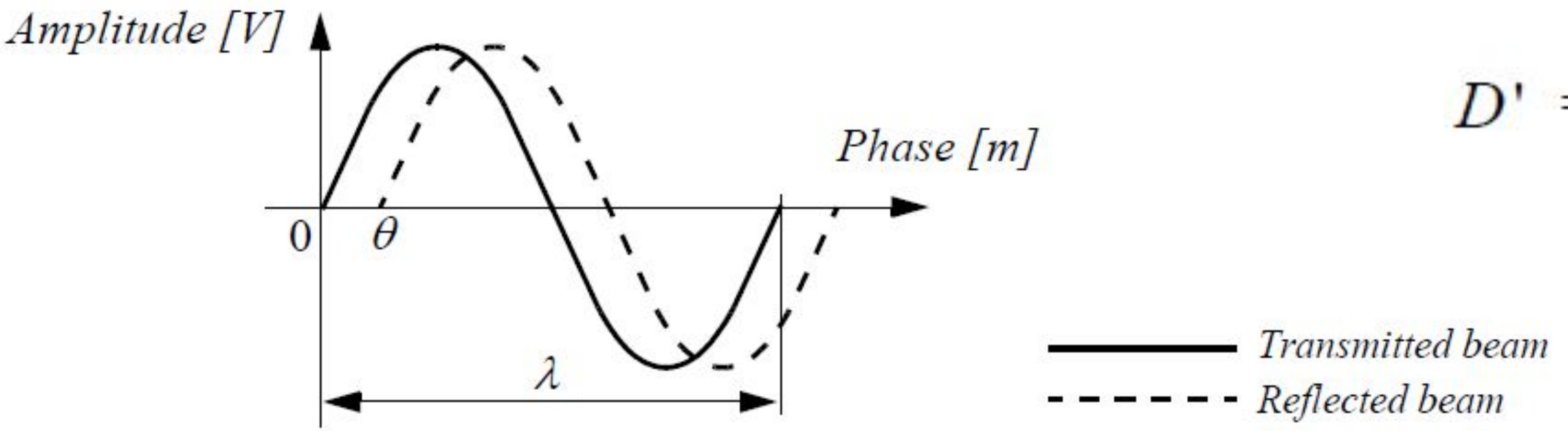
- Time of Flight Camera

I sensori di distanza basati sul time-of-flight sfruttano la velocità di propagazione del suono o delle onde elettromagnetiche per calcolare la distanza

Introduction to Autonomous Mobile Robots
Roland Siegwart, Illah Nourbakhsh, Davide Scaramuzza

Laser Range Finder

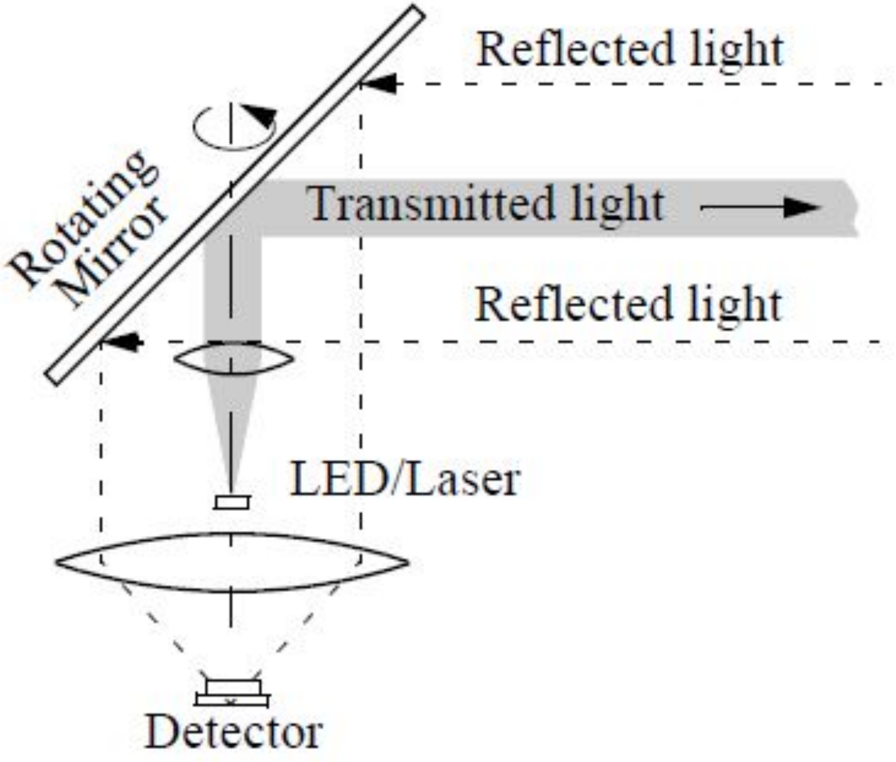


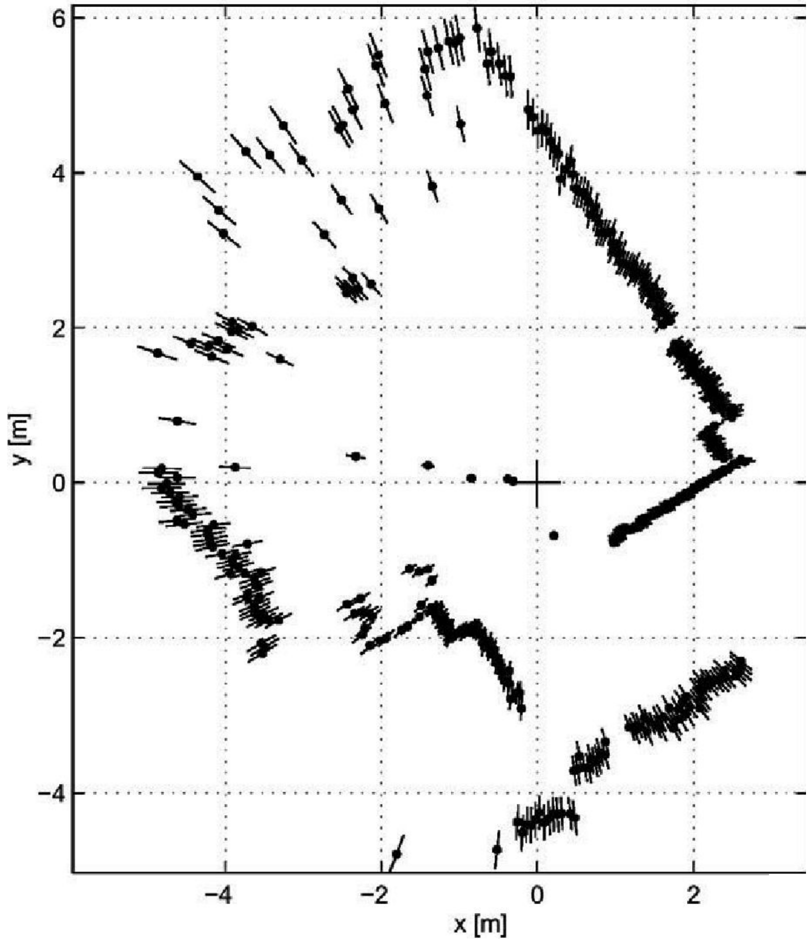


$$D' = L + 2D = L + \frac{\theta}{2\pi}\lambda$$

Introduction to Autonomous Mobile Robots
Roland Siegwart, Illah Nourbakhsh, Davide Scaramuzza

Laser range sensor with rotating mirror





Introduction to Autonomous Mobile Robots
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Path

- A metric map defines a reference frame
- To operate in a map, a robot should know its position in that reference frame
- A sequence of waypoints or of actions to reach a goal location in the map is a path

Mapping problem

Given

1. a robot that has a perfect ego-estimate of the position
2. a sequence of measurements

Determine the map of the environment

However,

a perfect estimate of the robot pose is usually not available

⇓

We solve a more complex problem:

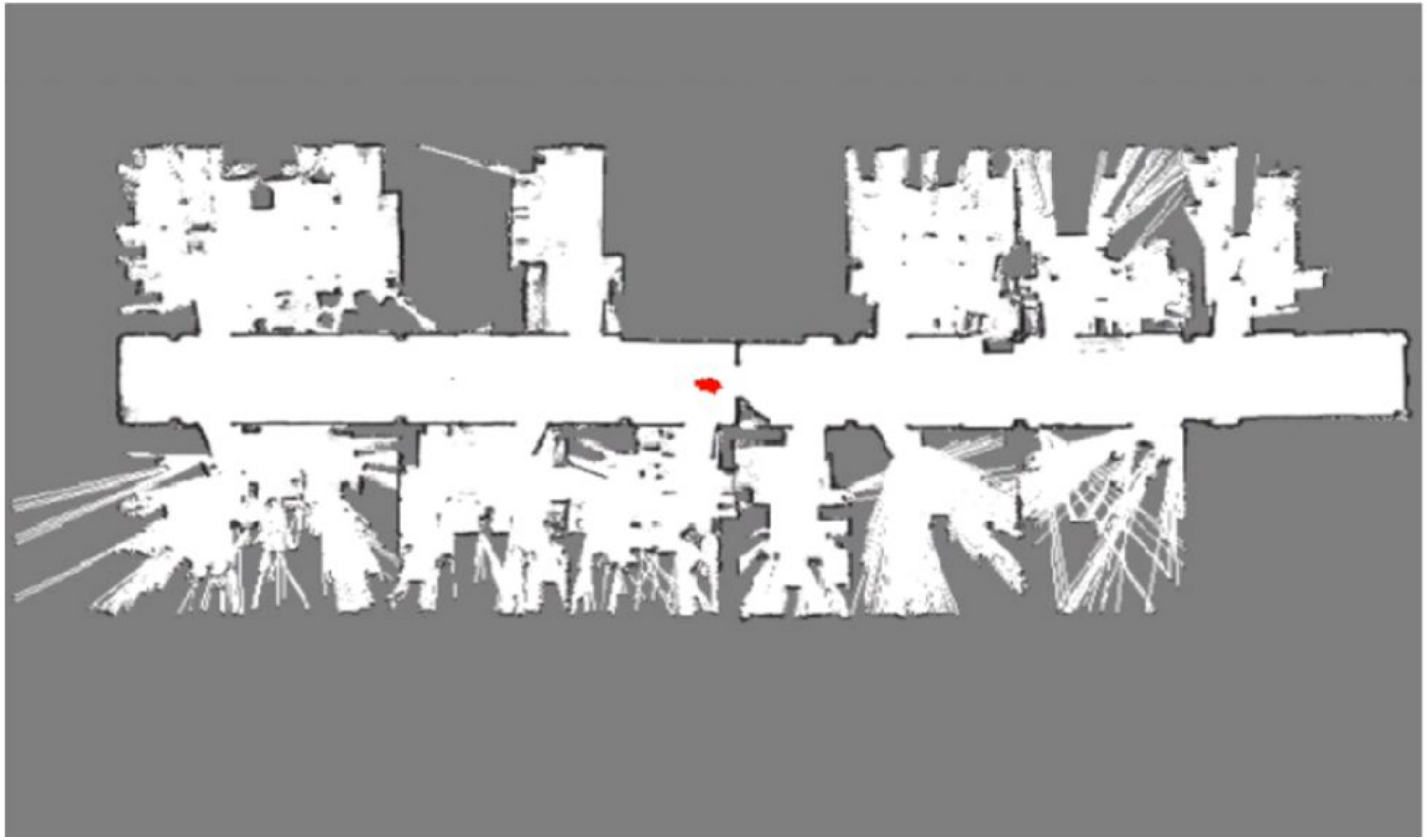
Simultaneous Localization and Mapping (SLAM)

Localization problem

Given

1. the knowledge of the map
2. all sensor measurements up to the current time

Determine the current position of the robot

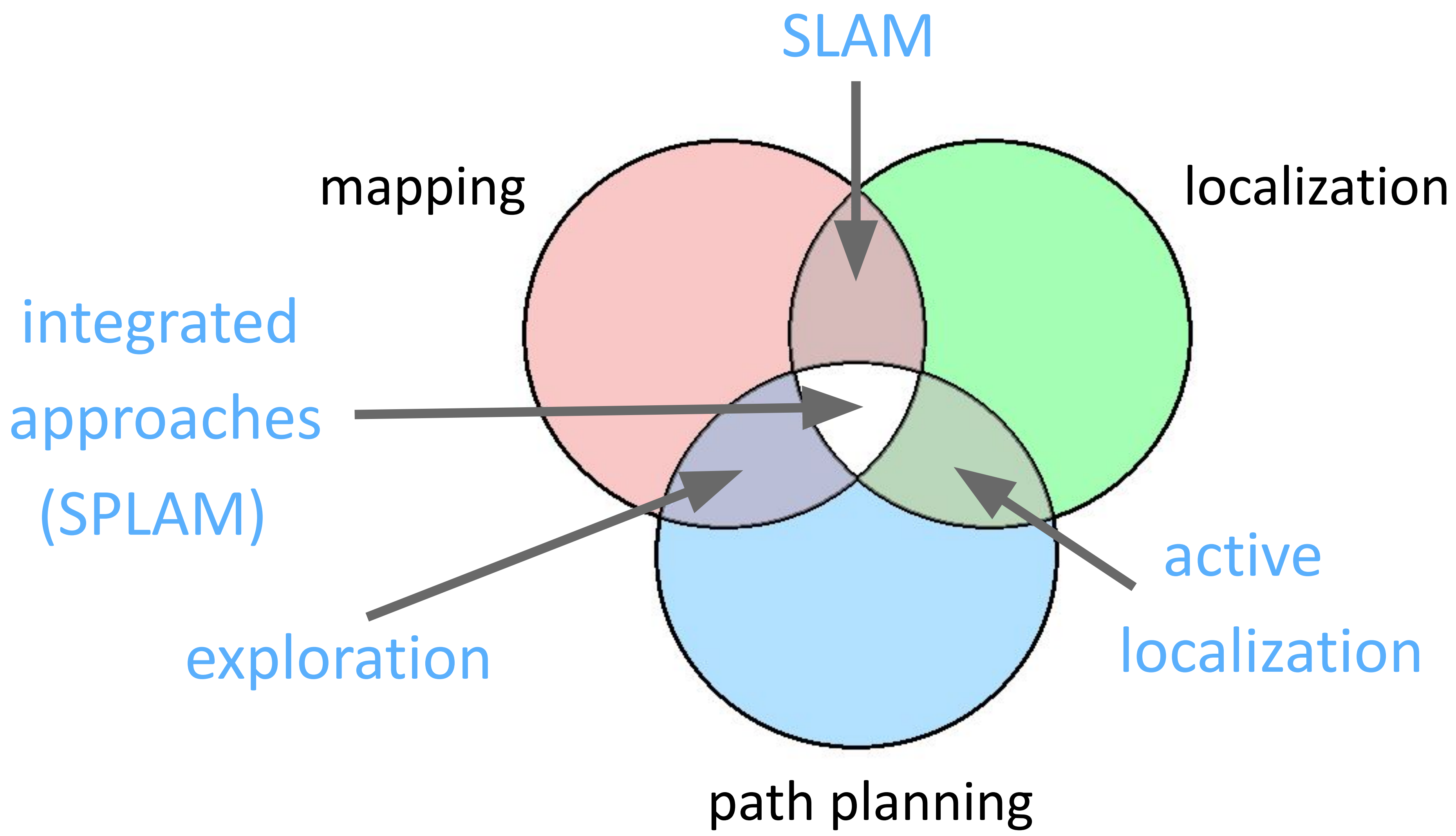


Path planning problem

Given
1. a localized robot
2. a map of traversable regions

Determine (if it exists) a path to reach a given goal location

Metodi


SLAM
mapping
localization
integrated
approaches
(SPLAM)
exploration
active
localization
path planning

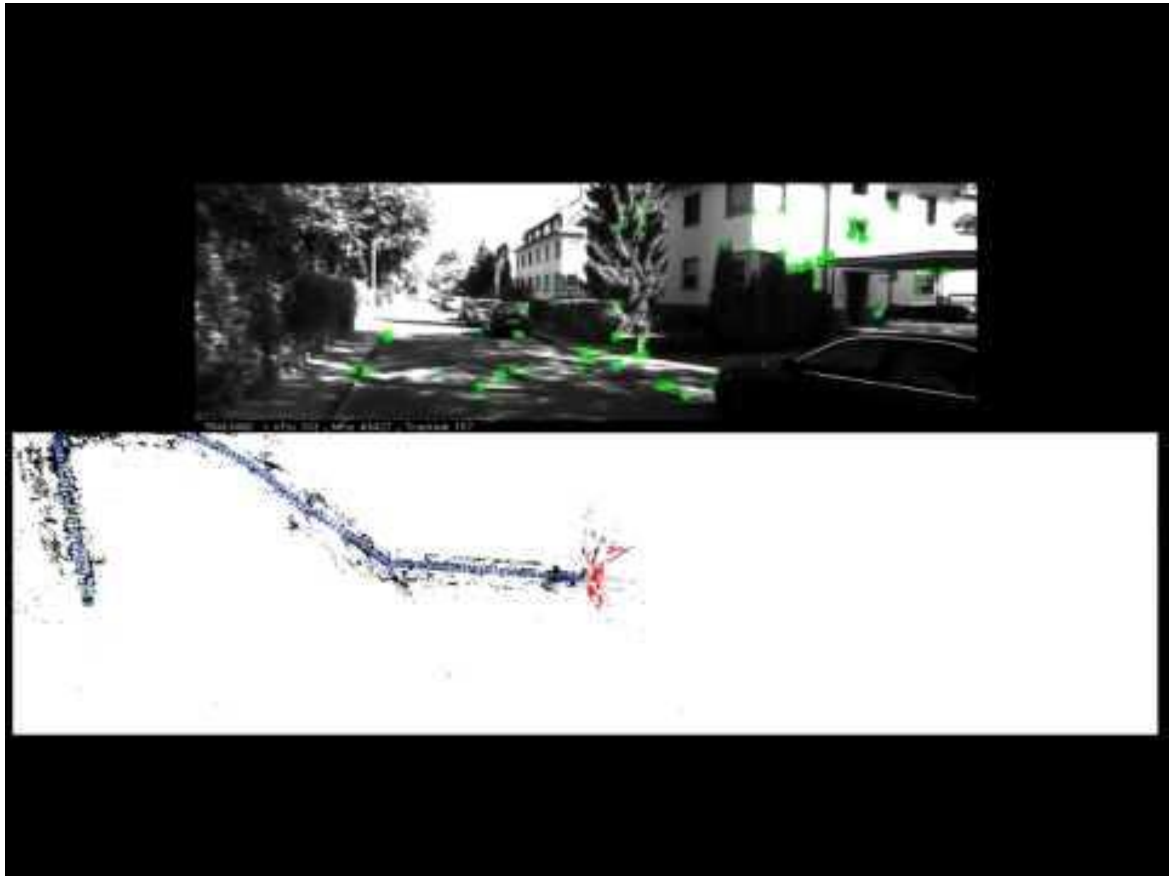
Simultaneous Localization And Mapping

Estimate:

1. the map of the environment
2. the trajectory of a moving device

using a sequence of sensor measurements

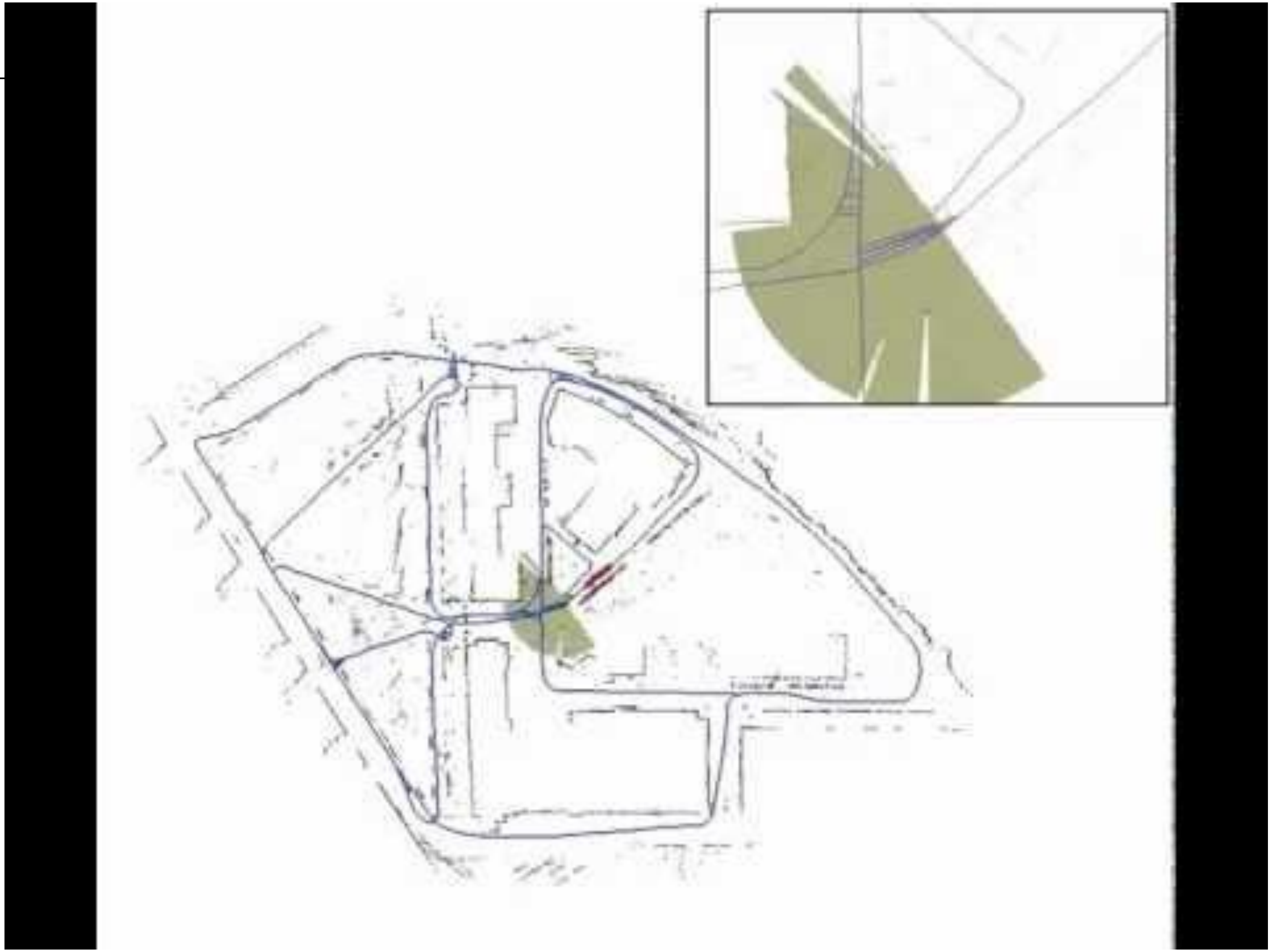
these quantities are correlated



https://www.youtube.com/watch?v=8DISRmsO2YQ

SLAM

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

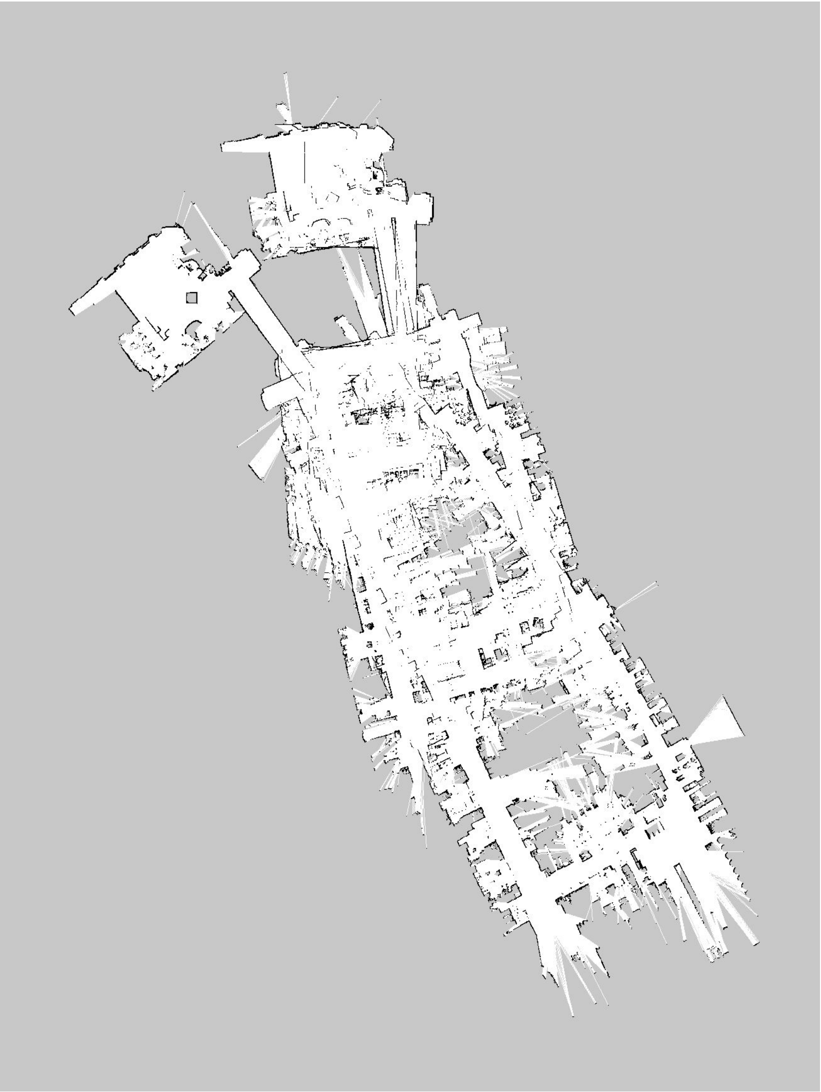


https://www.youtube.com/watch?v=hRyL5KwFLAE

Graph-based SLAM

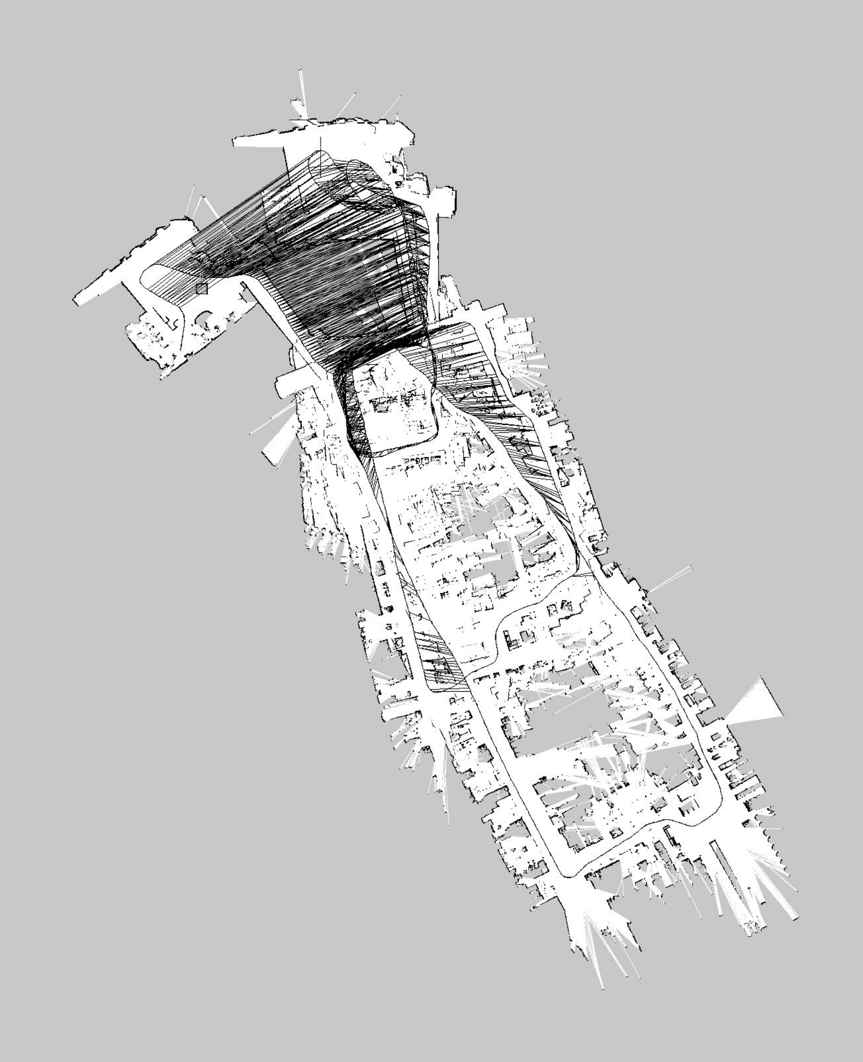
Problem described as a graph

Every node corresponds
to a robot position and
to a laser measurement



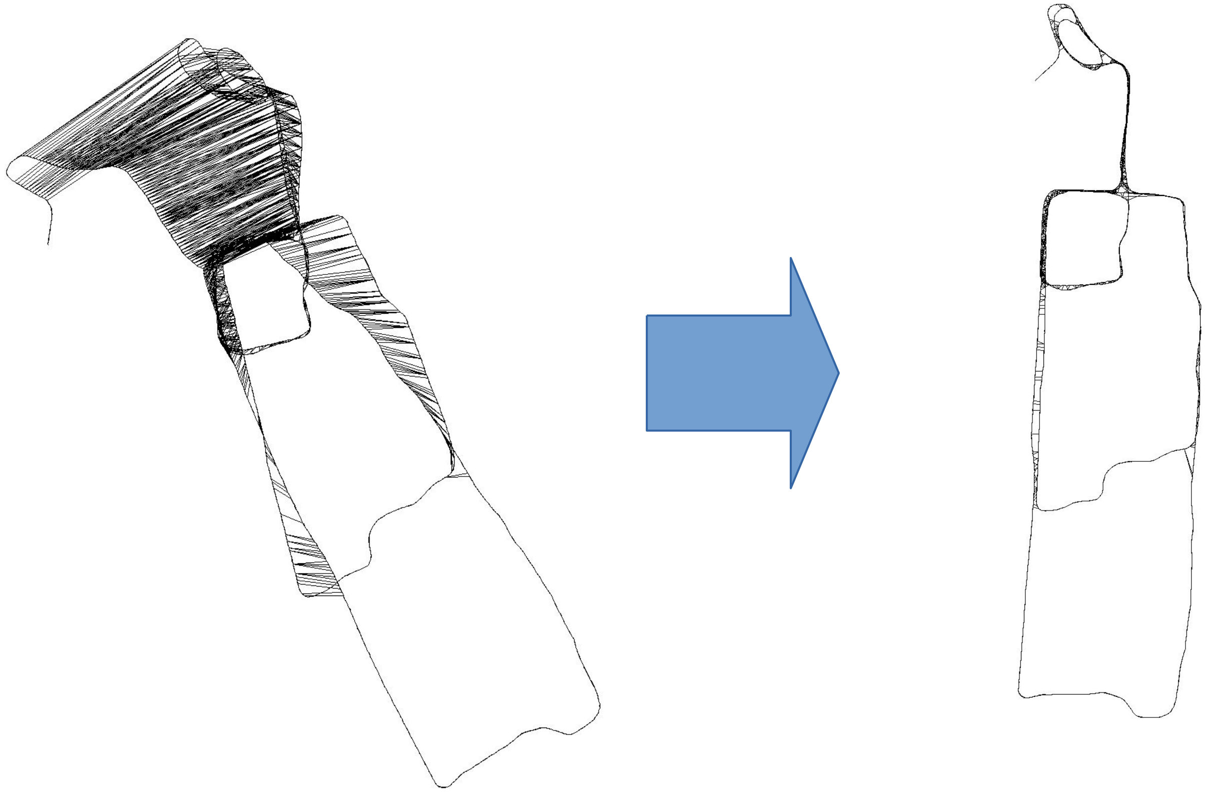
Graph-based SLAM

An edge between two nodes represents a data-dependent spatial constraint between the nodes



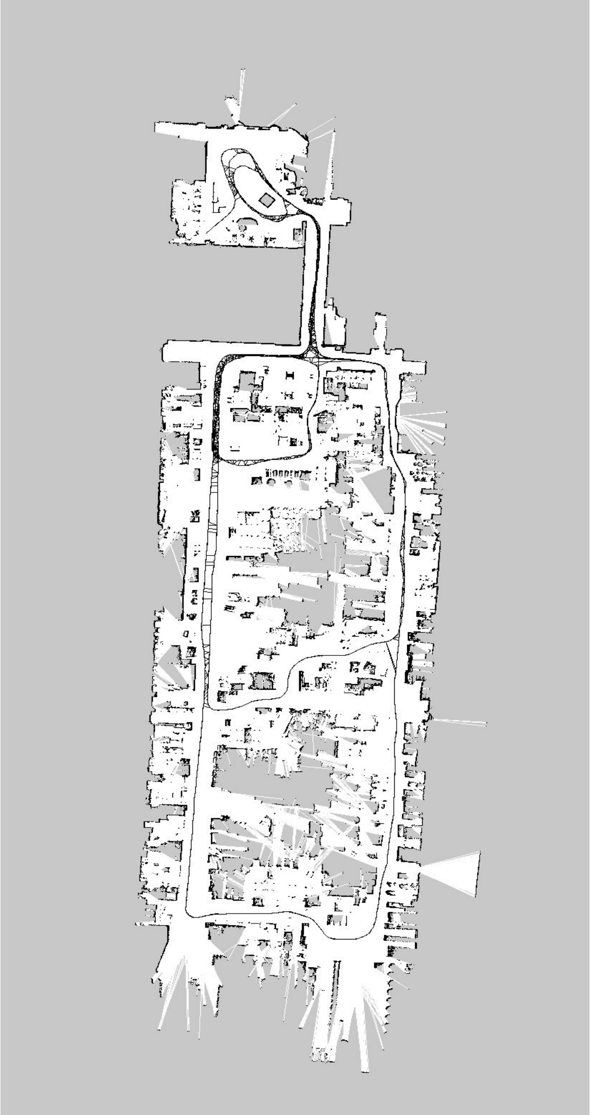
Graph-based SLAM

Once we have the graph we determine the most likely map by “moving” the nodes



Graph-based SLAM

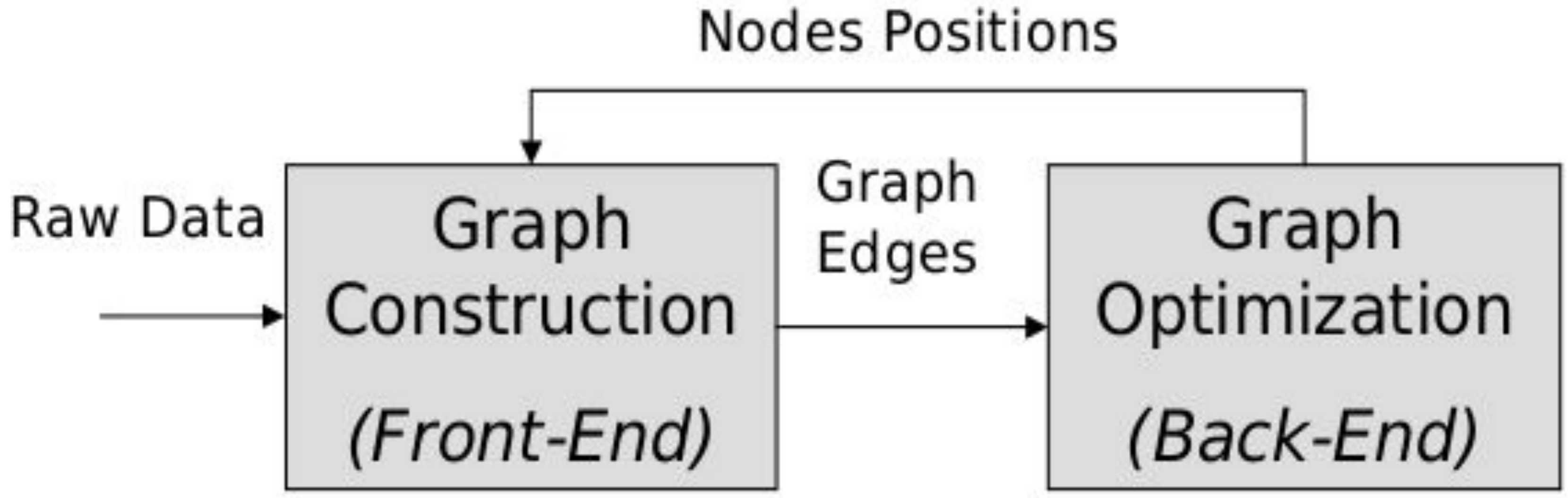
Then, we can render a map based on the known poses



Graph optimization

A general Graph-based SLAM algorithm interleaves the two steps

1. Graph construction
2. Graph optimization

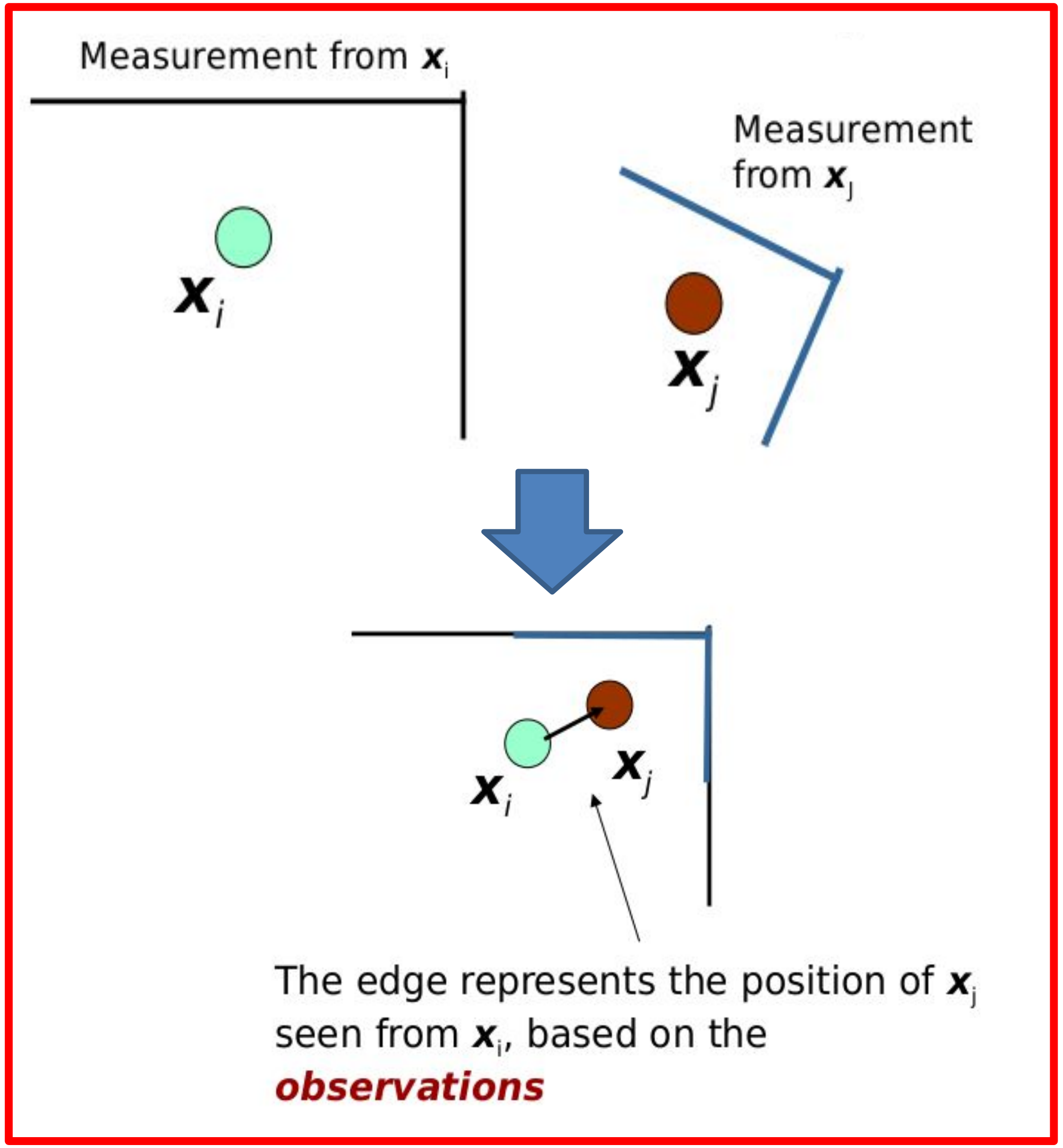


What Does the Graph Look Like?

Each node x_i is a 2D or 3D transformation representing the pose of the robot at time t_i

There is a constraint e_{ij} between the node x_i and the node x_j if

- either
  the robot observed the same part of the environment from both x_i and x_j and, via this common observation, it constructs a "virtual measurement" about the position of x_j
- or
  the positions are subsequent in time and there is an odometry measurement between the two



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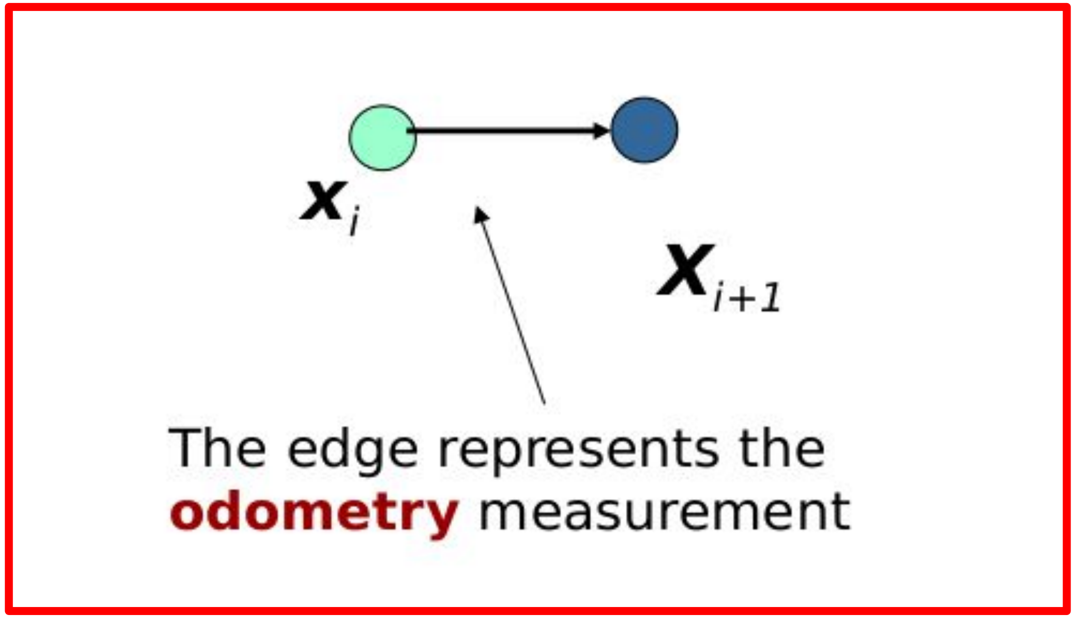
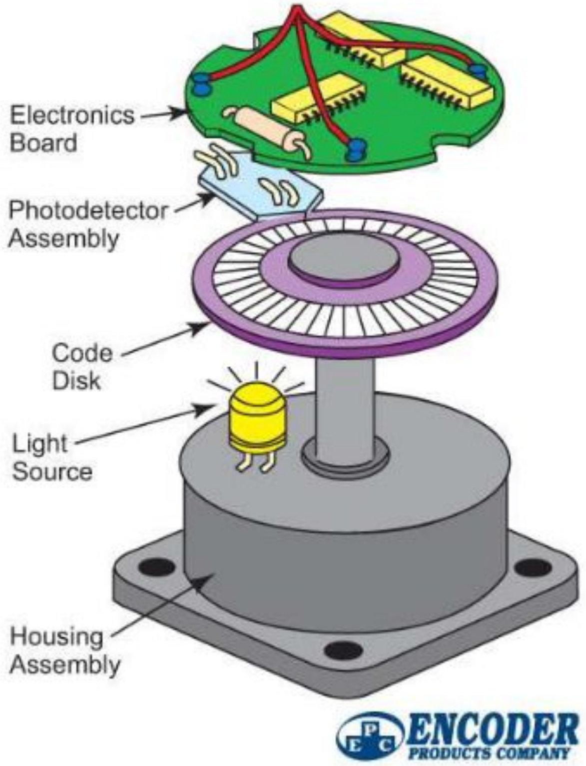


Odometria

Un encoder è un dispositivo elettromeccanico in grado di convertire la posizione lineare o angolare di un asse in un segnale analogico o digitale, facendone quindi un **trasduttore di posizione** lineare/angolare

encoder ottico

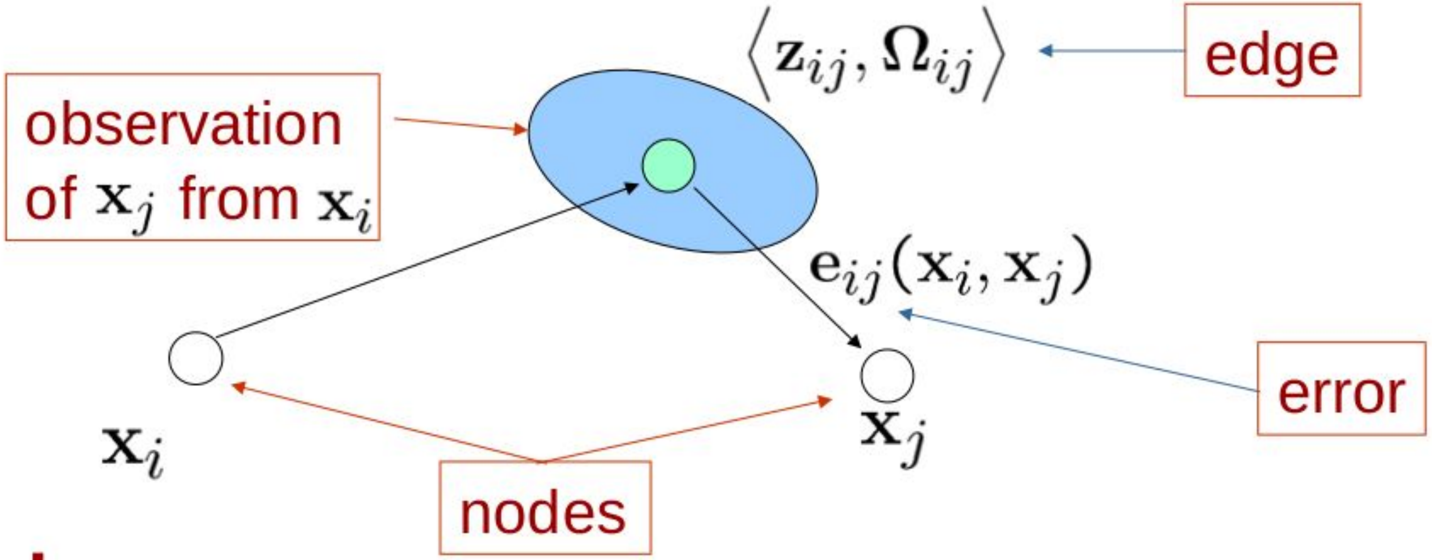


https://www.roboticstomorrow.com/article/2016/07/what-is-an-encoder/8553

Le misure fornite dagli encoder possono essere integrate per ottenere una stima della posizione (odometria)

Pose graph

- The input for the optimization procedure is a graph annotated as follows:



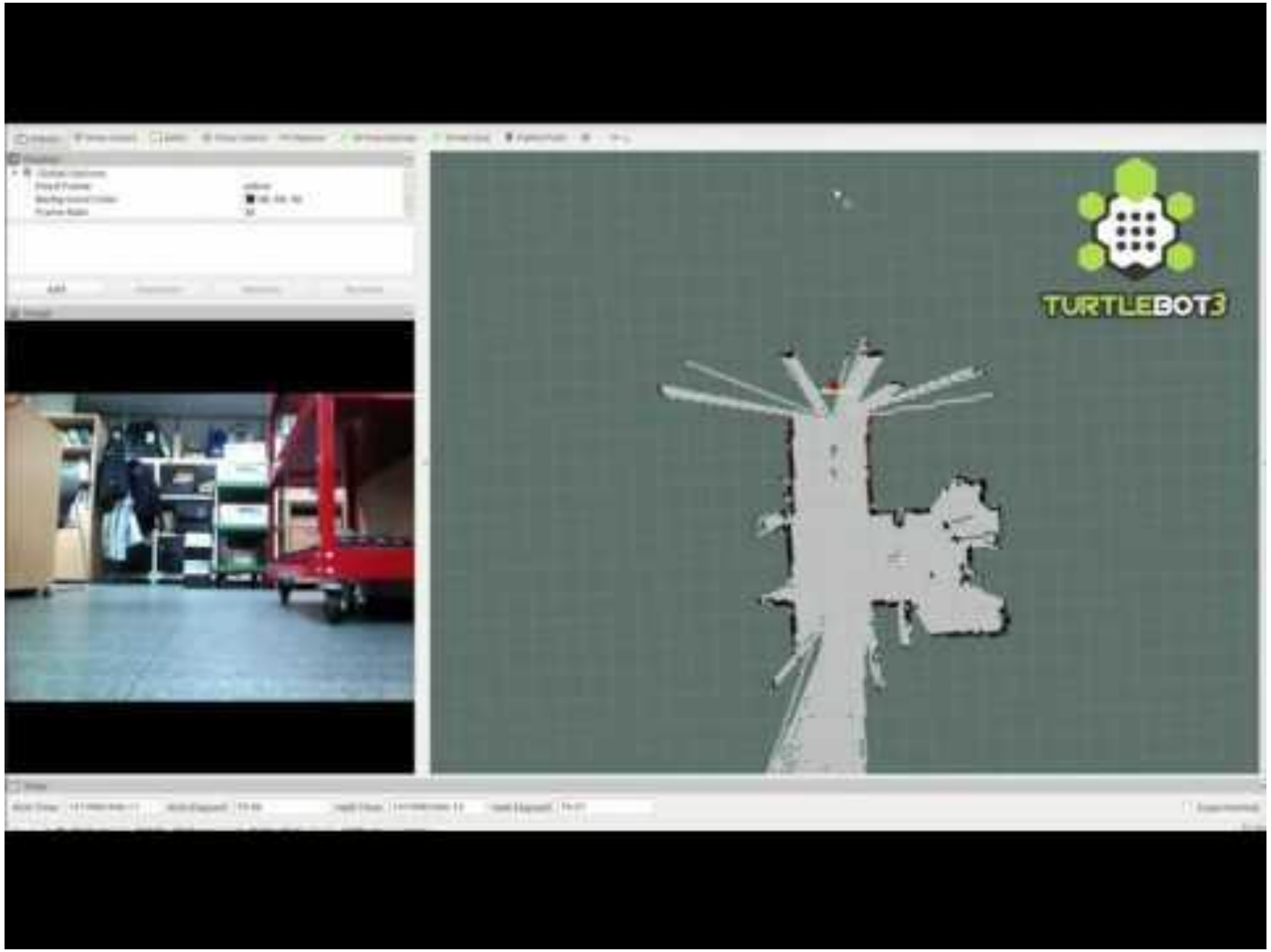
- **Goal:**
  - Find the assignment of poses to the nodes of the graph which minimizes the negative log likelihood of the observations:

$$\hat{\mathbf{x}} = \operatorname{argmin} \sum_{ij} \mathbf{e}_{ij}^T \mathbf{\Omega}_{ij} \mathbf{e}_{ij}$$

z_{ij} is a measurement of the robot pose j, performed from robot pose i

Ω_{ij} is a matrix to encode the uncertainty of the edge

SLAM – TurtleBot3



https://www.youtube.com/watch?v=hX6pFcfr29c

Getting started - Navigation

To navigate a robot we need

1. a map
2. a localization module
3. a path planning module

These components are sufficient if

- ✔ the map fully reflects the environment
- ✔ the environment is static
- ✔ there are no errors in the estimate

Getting started - Navigation

However

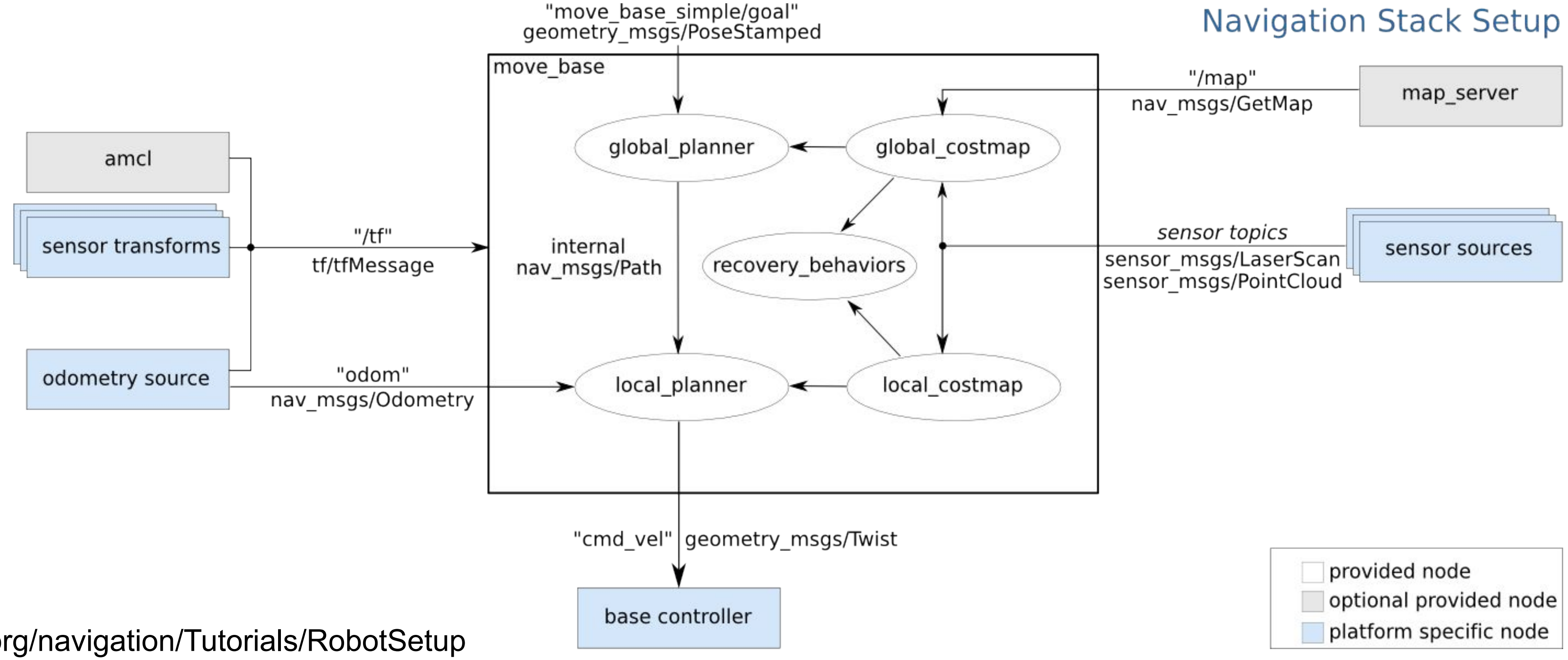
1. The environment changes (e.g., opening/closing doors)
2. It is dynamic (things might appear/disappear from the perception range of the robot)
3. The estimate is "noisy"

Thus we need to complement our ideal design with other components that address these issues, namely

1. Obstacle-Detection/Avoidance
2. Local Map Refinement, based on the most recent sensor reading

ROS navigation stack

- Map provided by a “Map Server”
- Each module is a node
- Planner has a layered architecture (local and global planner)
- Obstacle sensing refined on-line by appropriate modules (local and global costmap)



http://wiki.ros.org/navigation/Tutorials/RobotSetup

Building the map in ROS

- ROS uses GMapping, which implements a particle filter to track the robot trajectories

- To build a map you need to
  1. Record a bag with /odom, /scan and /tf while driving the robot around in the environment it is going to operate in
  2. Play the bag and the gmapping-node (see the ros wiki), and then save it

- The map is an occupancy map and it is represented as
  1. An image showing the blueprint of the environment
  2. A configuration file (yaml) that gives meta information about the map (origin, size of a pixel in real world)

Localizing the robot

ROS implements the Adaptive Monte Carlo Localization algorithm

1. AMCL uses a particle filter to track the position of the robot
2. Each pose is represented by a particle
3. Particles are
    - Moved according to (relative) movement measured by the odometry
    - Suppressed/replicated based on how well the laser scan fits the map, given the position of the particle

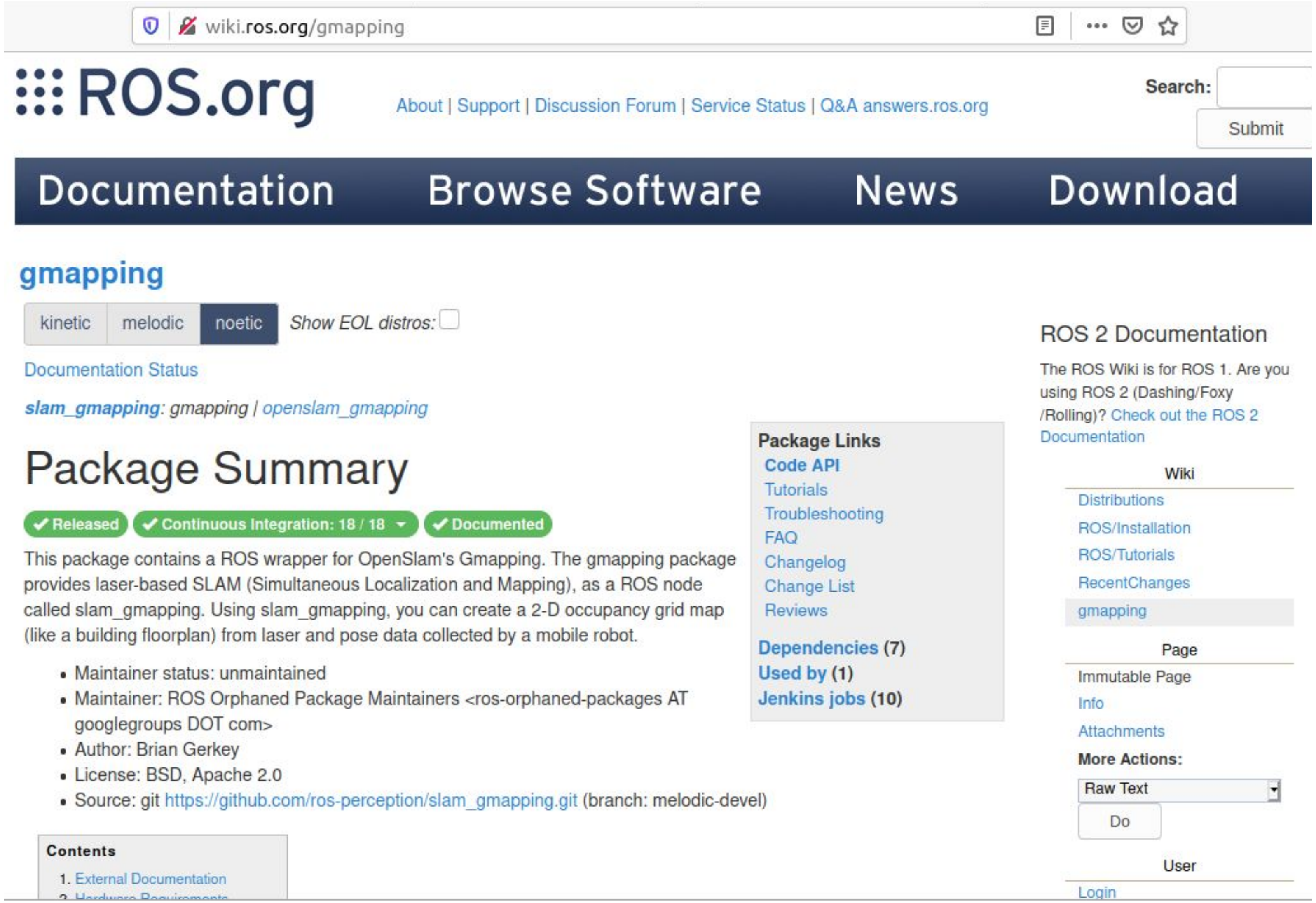
Virtual SLAM and Navigation

Useremo

- i package ROS per lo SLAM per creare una mappa di un mondo simulato tramite Gazebo

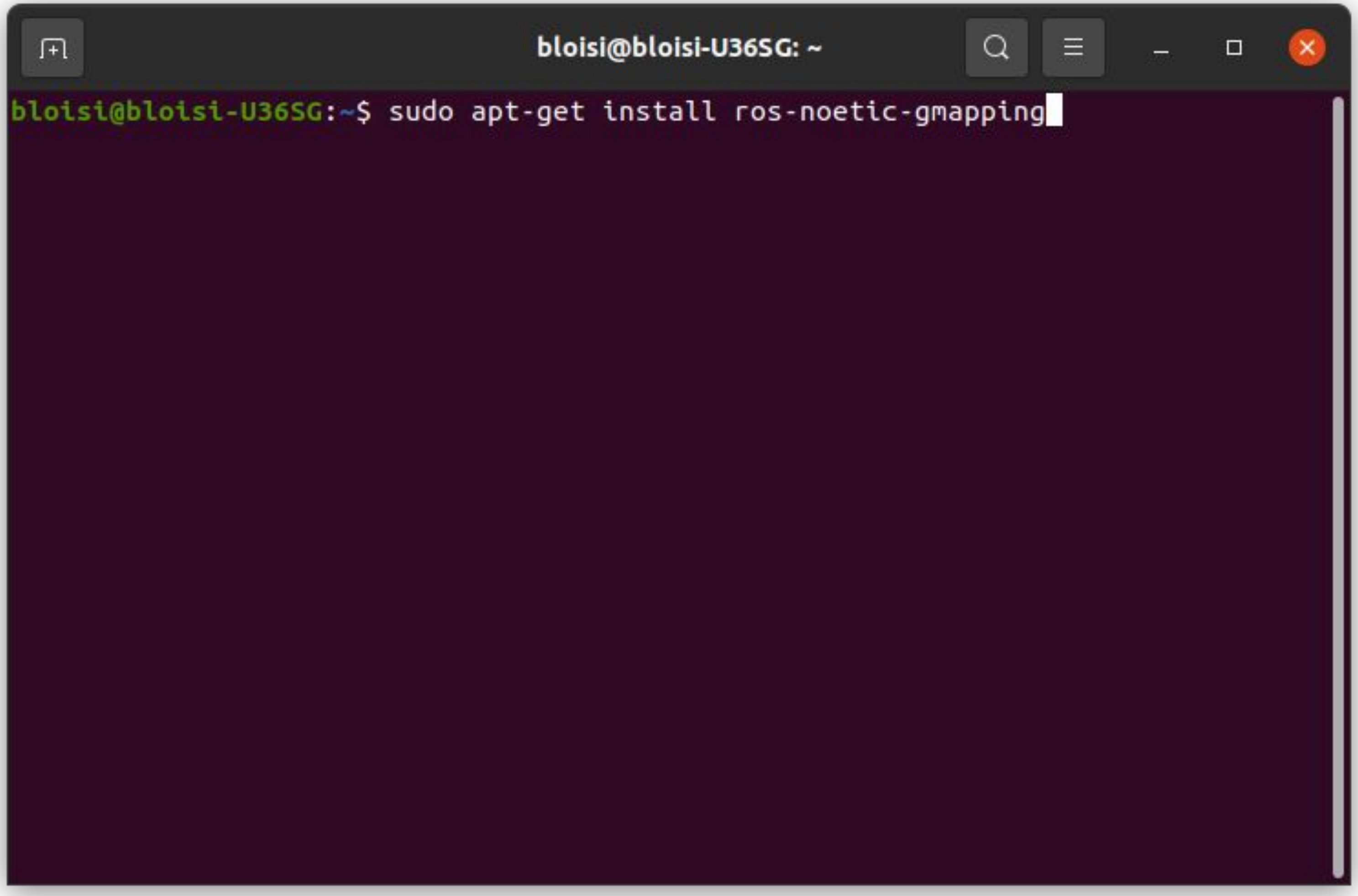
- lo stack ROS per la navigazione per far muovere il TurtleBot3 verso una destinazione sulla mappa

gmapping

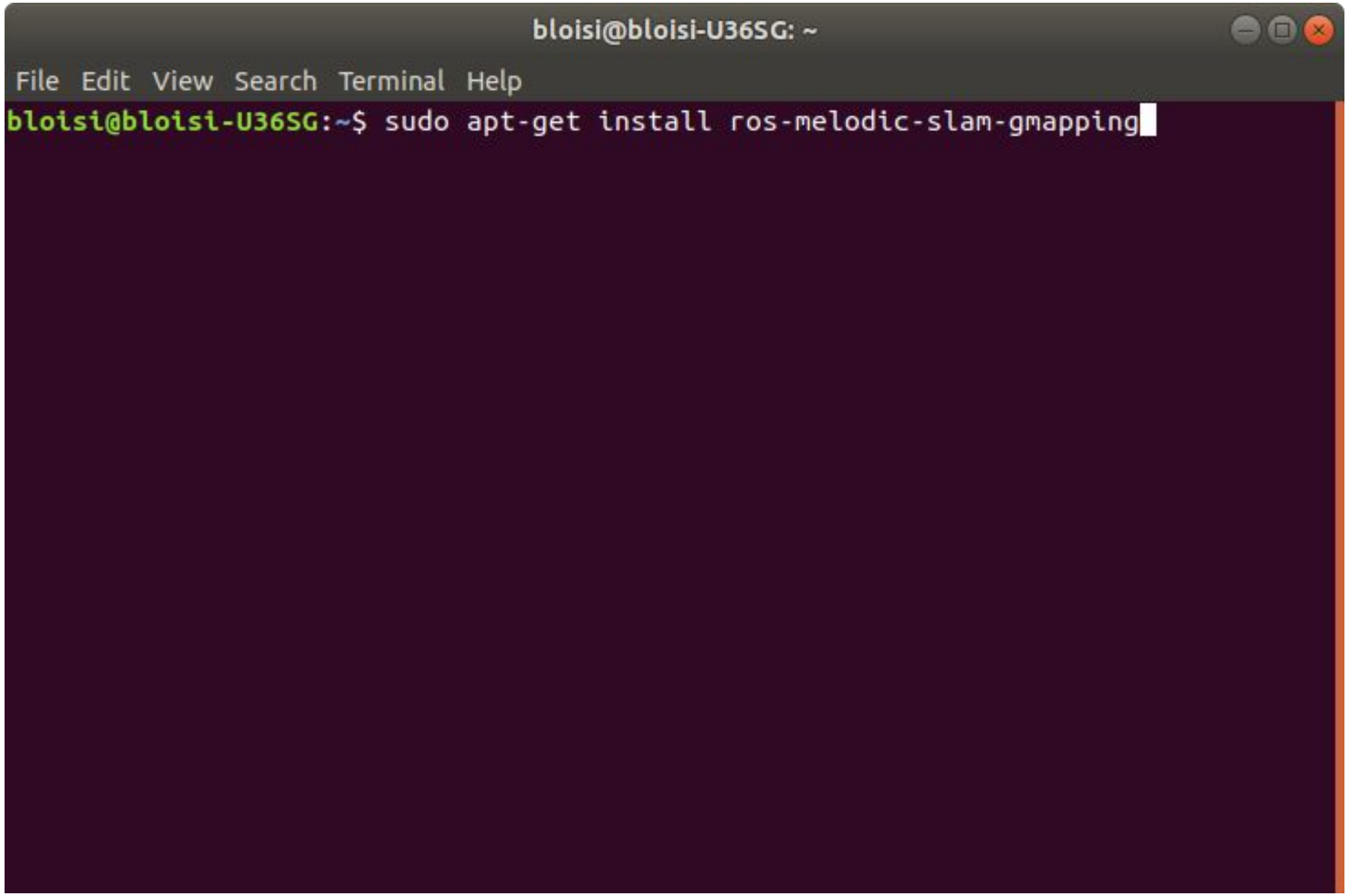


http://wiki.ros.org/gmapping

Installing GMapping in ROS Noetic



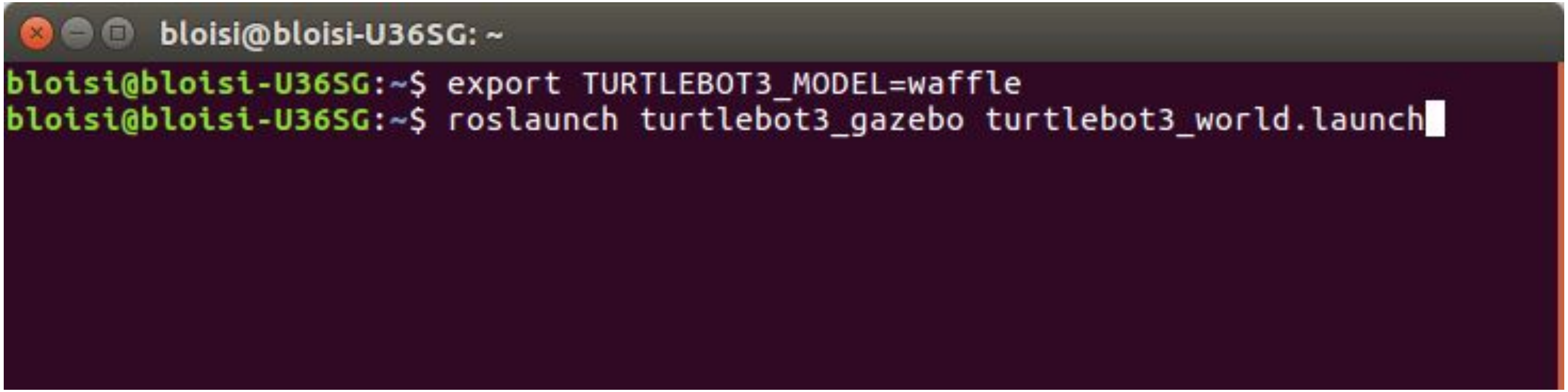
Installing GMapping in ROS Melodic



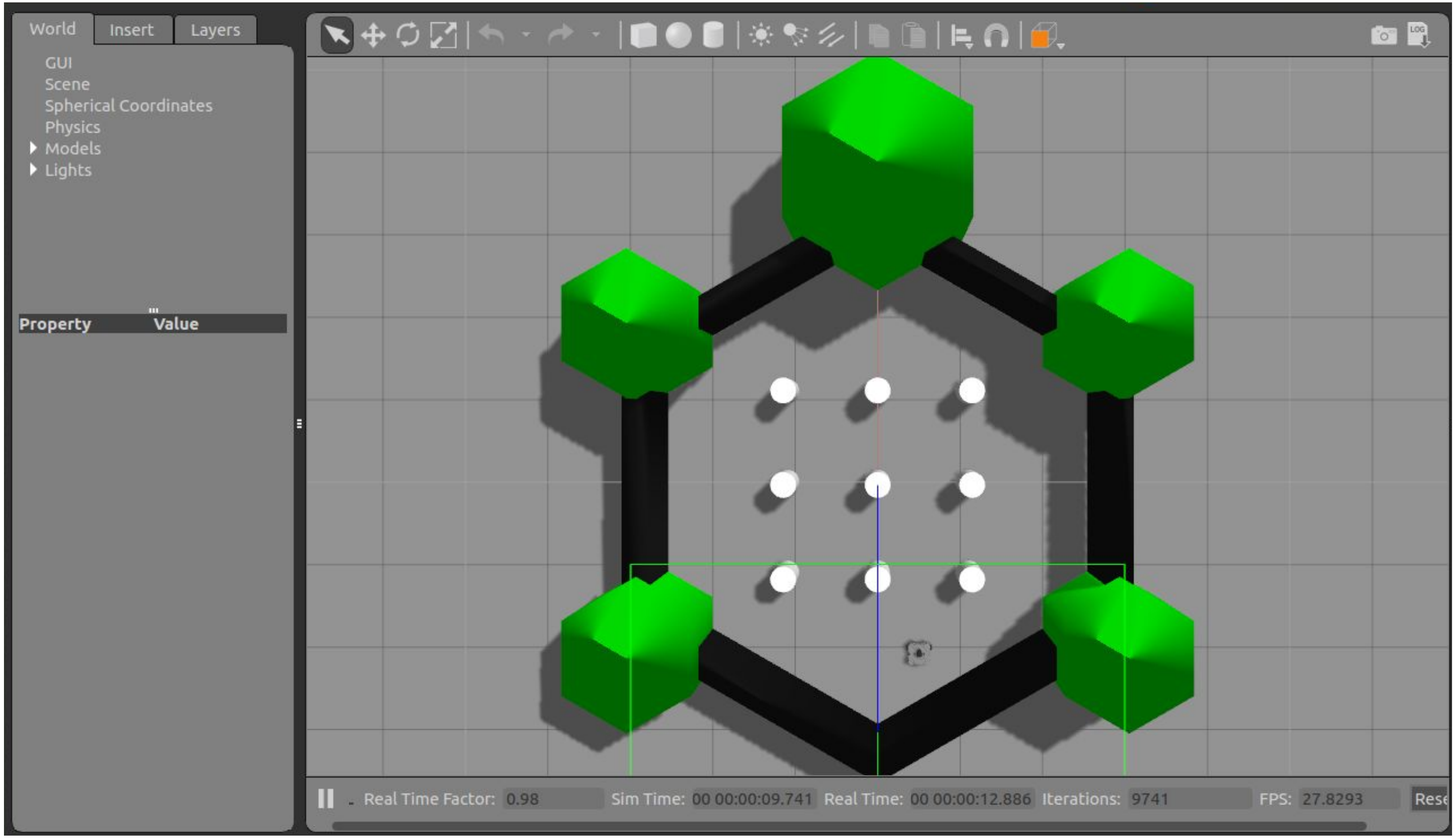
Launch Gazebo

In un primo terminale digitiamo

```
export TURTLEBOT3_MODEL=waffle
roslaunch turtlebot3_gazebo turtlebot3_world.launch
```



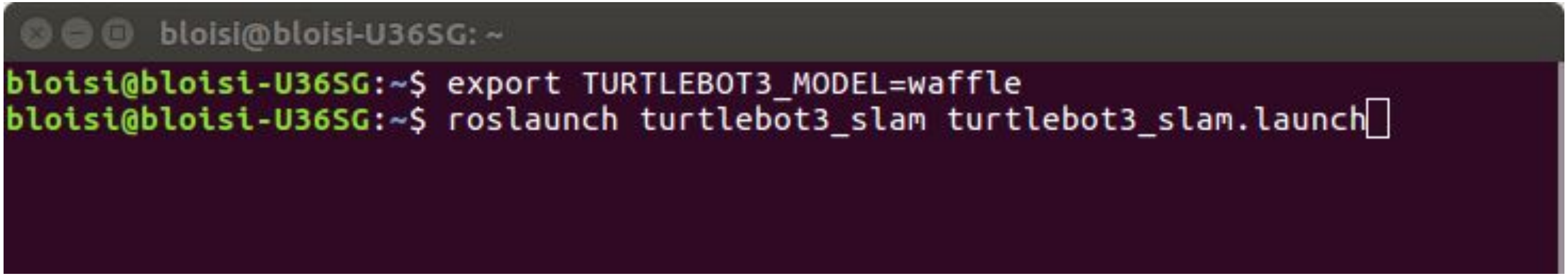
Launch Gazebo



Launch SLAM

In un secondo terminale digitiamo

```
export TURTLEBOT3_MODEL=waffle
roslaunch turtlebot3_slam turtlebot3_slam.launch
```



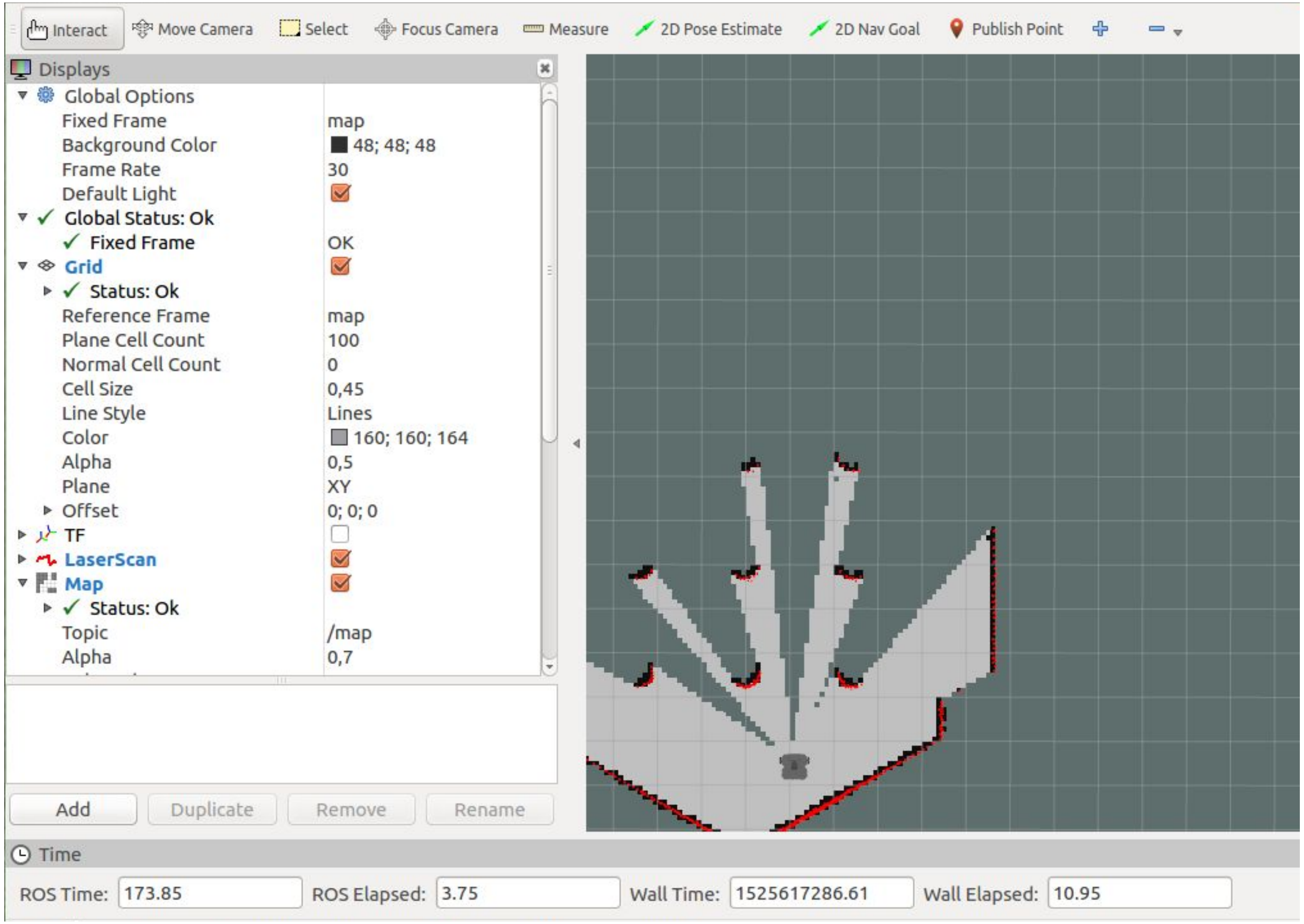
Launch SLAM

/home/bloisi/catkin_ws/src/turtlebot3/turtlebot3_slam/launch/turtlebot3_slam.launch

```
Laser Pose= -2.064 -0.500004 3.14007
m_count 7
Average Scan Matching Score=322.728
neff= 120
Registering Scans:Done
update frame 39
update ld=7.41779e-08 ad=5.33264e-07
Laser Pose= -2.064 -0.500004 3.14007
m_count 8
Average Scan Matching Score=322.791
neff= 120
Registering Scans:Done
update frame 40
update ld=6.27647e-08 ad=4.47942e-07
Laser Pose= -2.064 -0.500004 3.14007
m_count 9
Average Scan Matching Score=322.845
neff= 120
Registering Scans:Done
update frame 41
update ld=6.49517e-08 ad=4.6394e-07
Laser Pose= -2.064 -0.500004 3.14007
m_count 10
```

RViz

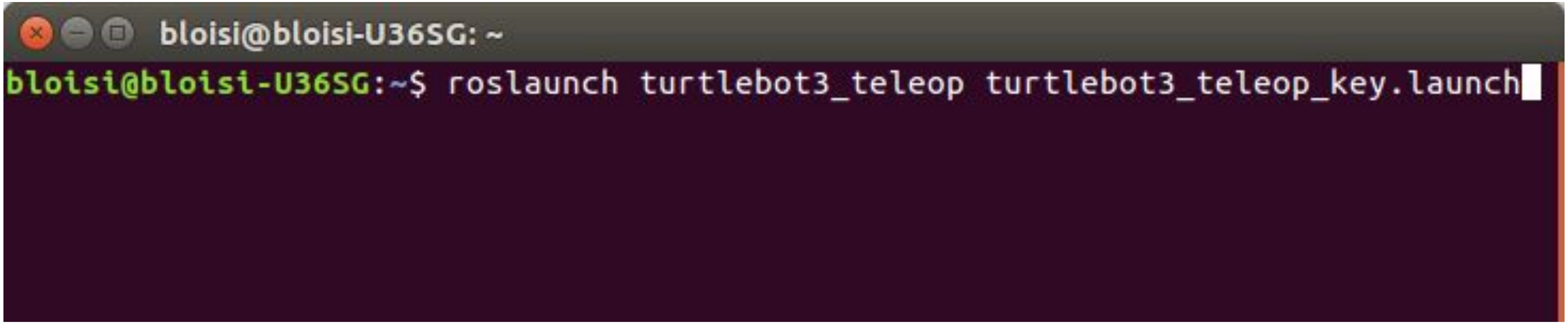
Con Rviz potremo visualizzare i dati che i sensori del robot stanno inviando



Remotely Control TurtleBot3

In un terzo terminale digitiamo

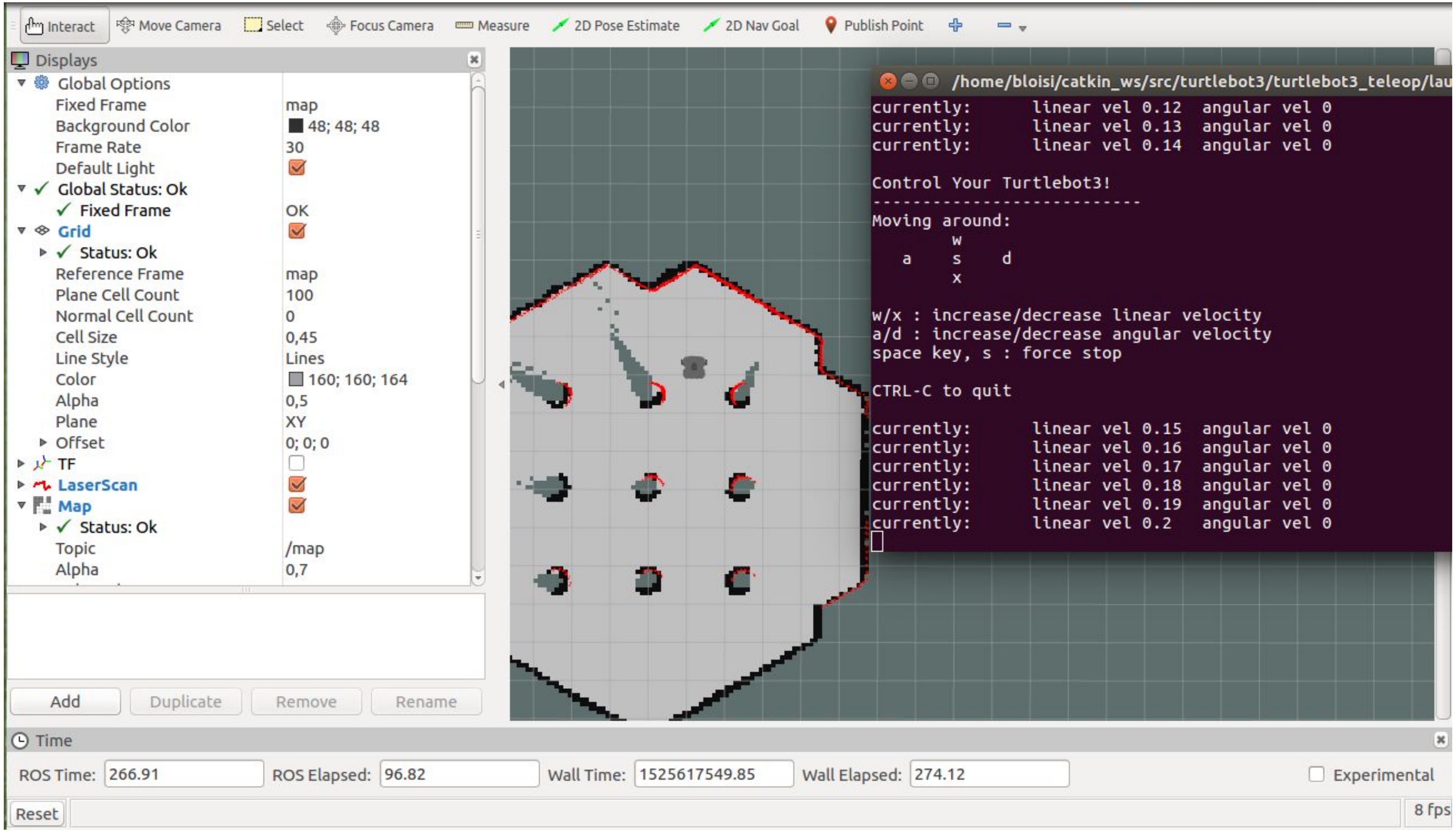
```
roslaunch turtlebot3_teleop turtlebot3_teleop_key.launch
```



Remotely Control TurtleBot3

```
/home/bloisi/catkin_ws/src/turtlebot3/turtlebot3_teleop/launch/turtlebot3_teleop_key
 * /rosversion: 1.12.13

NODES
  /
    turtlebot3_teleop_keyboard (turtlebot3_teleop/turtlebot3_teleop_key)

ROS_MASTER_URI=http://localhost:11311

process[turtlebot3_teleop_keyboard-1]: started with pid [6305]

Control Your Turtlebot3!
---------------------------
Moving around:
        w
   a    s    d
        x

w/x : increase/decrease linear velocity
a/d : increase/decrease angular velocity
space key, s : force stop

CTRL-C to quit
```

Costruiamo la mappa



Gazebo + RViz views

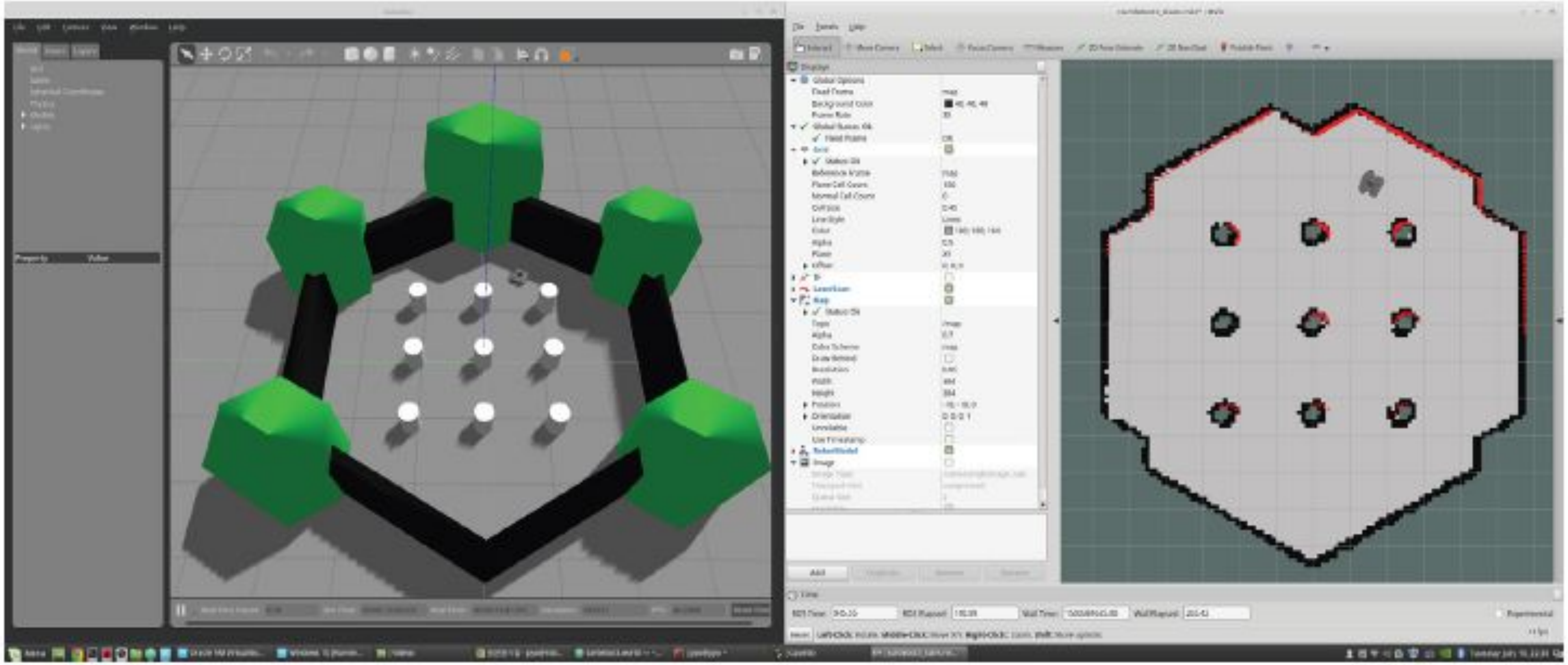


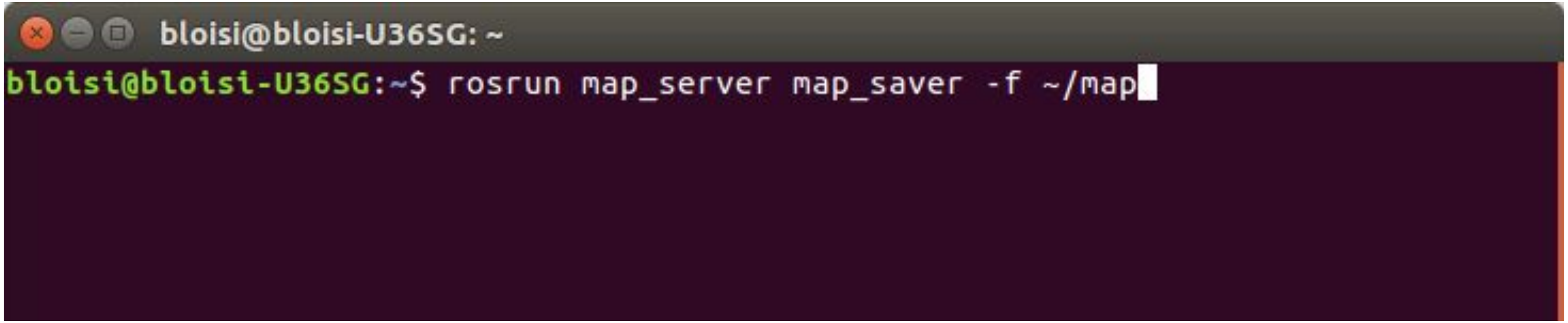
FIGURE 10-20 Running SLAM on Gazebo (Left: Gazebo, Right: RViz)

YoonSeok Pyo, HanCheol Cho, RyuWoon Jung, TaeHoon Lim, *"ROS Robot Programming - A Handbook Written by TurtleBot3 Developers"*

Save the Map

Terminata l'esplorazione, possiamo salvare la mappa che è stata generata con il `map_server` digitando

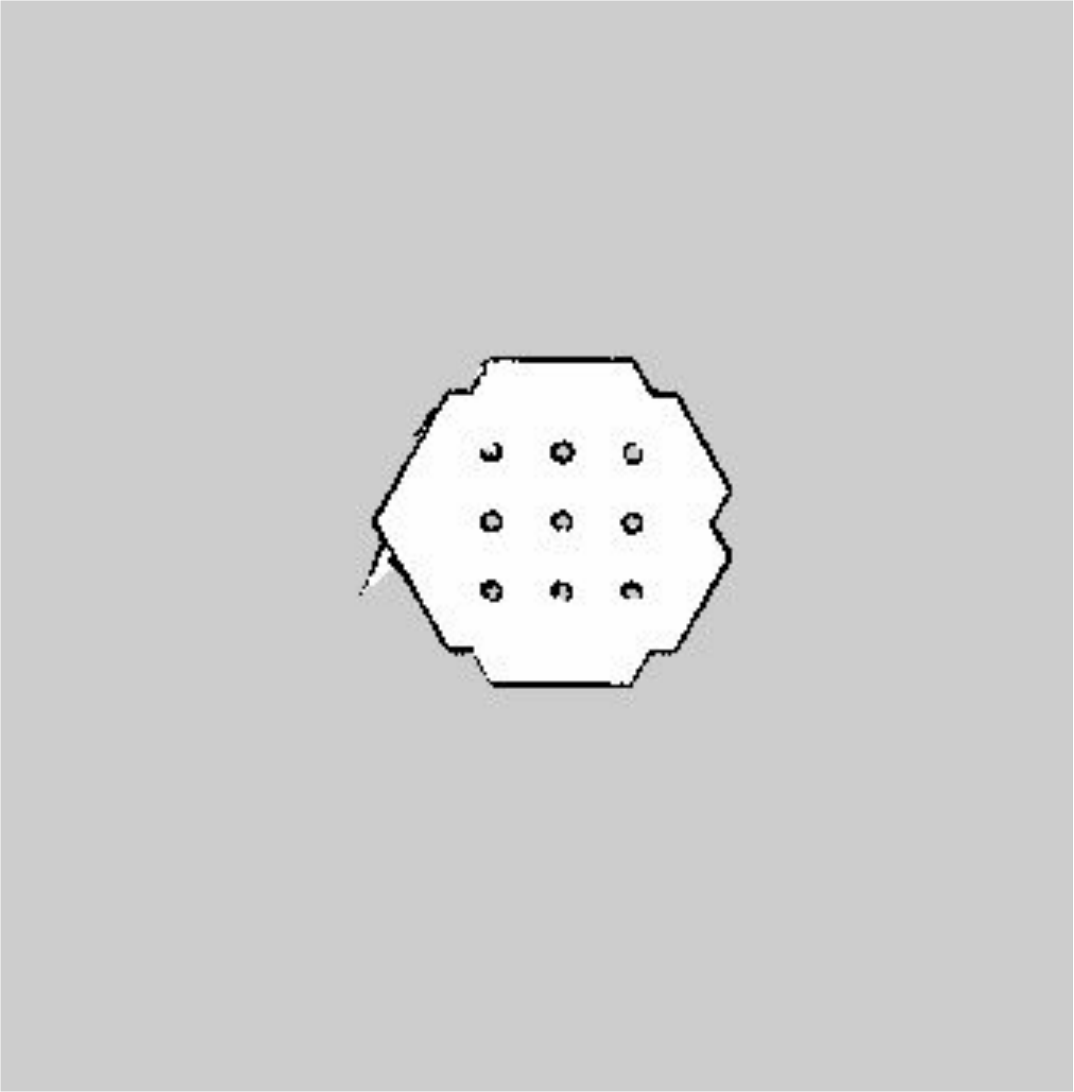
```
rosrun map_server map_saver -f ~/map
```



Save the Map

```
bloisi@bloisi-U36SG: ~
bloisi@bloisi-U36SG:~$ rosrun map_server map_saver -f ~/map
[ INFO] [1525617922.440250407]: Waiting for the map
[ INFO] [1525617922.705725024, 410.589000000]: Received a 384 X 384 map @ 0.050
m/pix
[ INFO] [1525617922.706387150, 410.589000000]: Writing map occupancy data to /ho
me/bloisi/map.pgm
[ INFO] [1525617922.715131989, 410.590000000]: Writing map occupancy data to /ho
me/bloisi/map.yaml
[ INFO] [1525617922.716040700, 410.590000000]: Done

bloisi@bloisi-U36SG:~$
```

map.pgm



map.yaml


```yaml
image: /home/bloisi/map.pgm
resolution: 0.050000
origin: [-10.000000, -10.000000, 0.000000]
negate: 0
occupied_thresh: 0.65
free_thresh: 0.196
```

Navigazione con TurtleBot3

Per poter procedere con la navigazione

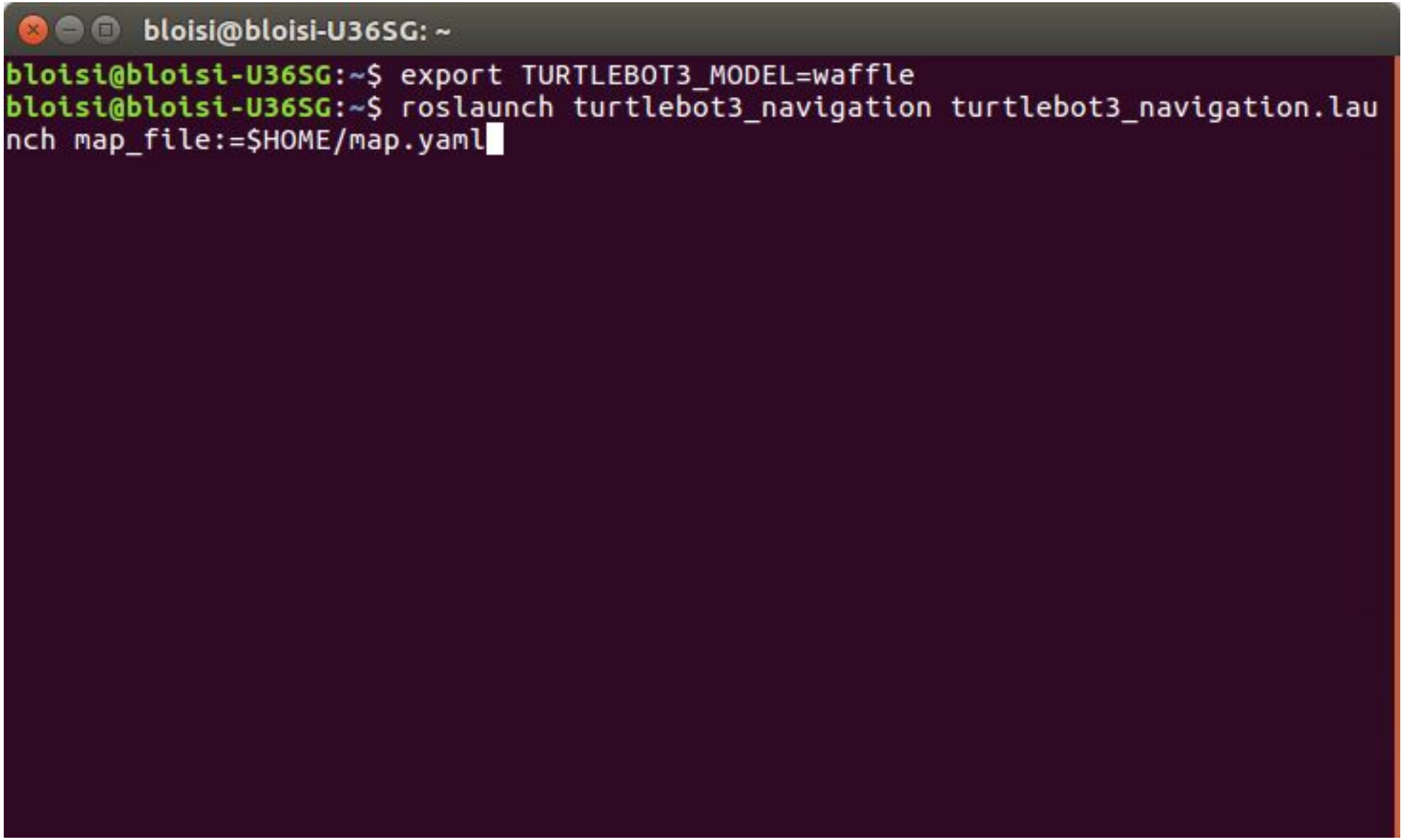
1. Terminare tutti i processi attivi
2. Digitare in un primo terminale

   export TURTLEBOT3_MODEL=waffle
   roslaunch turtlebot3_gazebo turtlebot3_world.launch

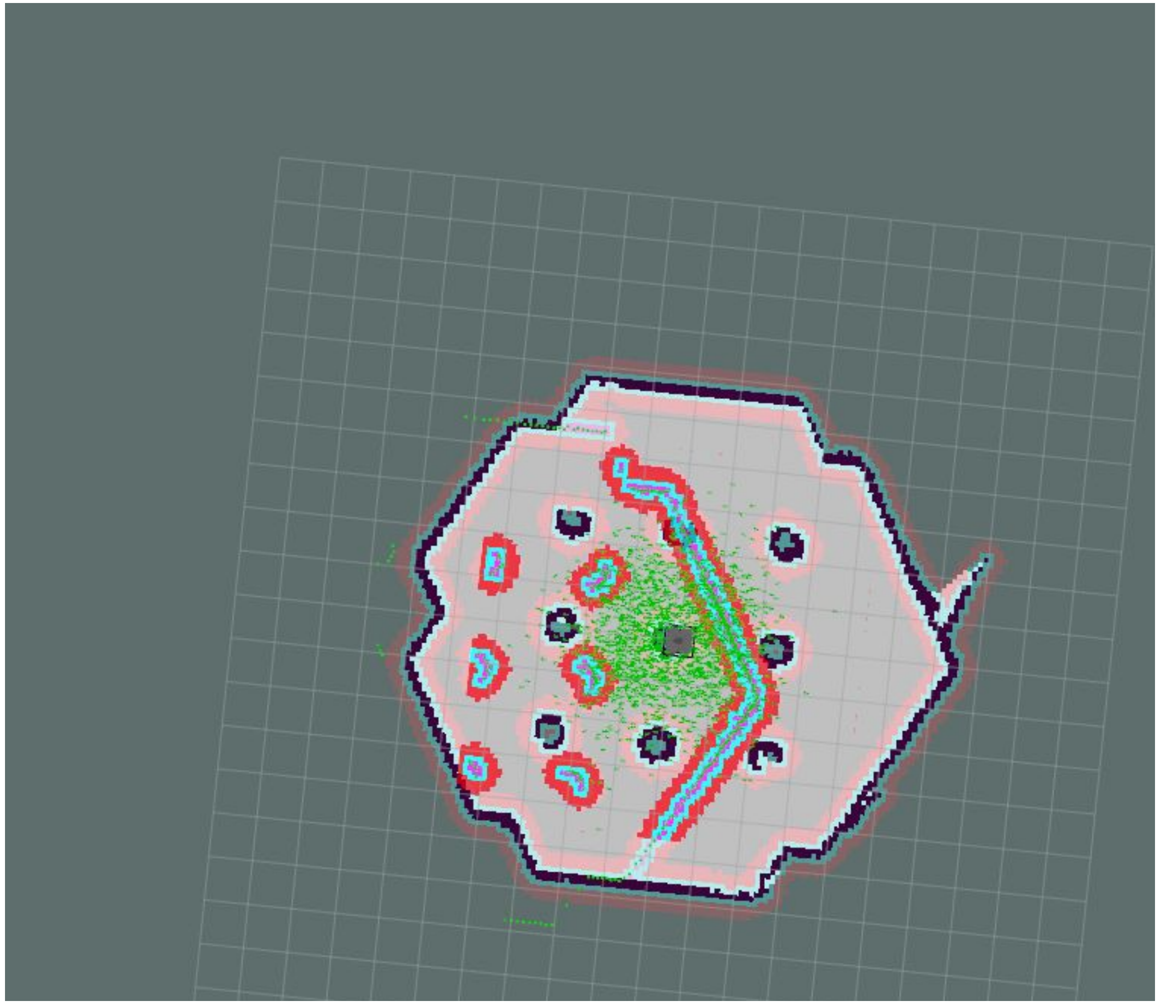
3. Aprire un secondo terminale e digitare

   export TURTLEBOT3_MODEL=waffle
   roslaunch turtlebot3_navigation turtlebot3_navigation.launch
   map_file:=$HOME/map.yaml

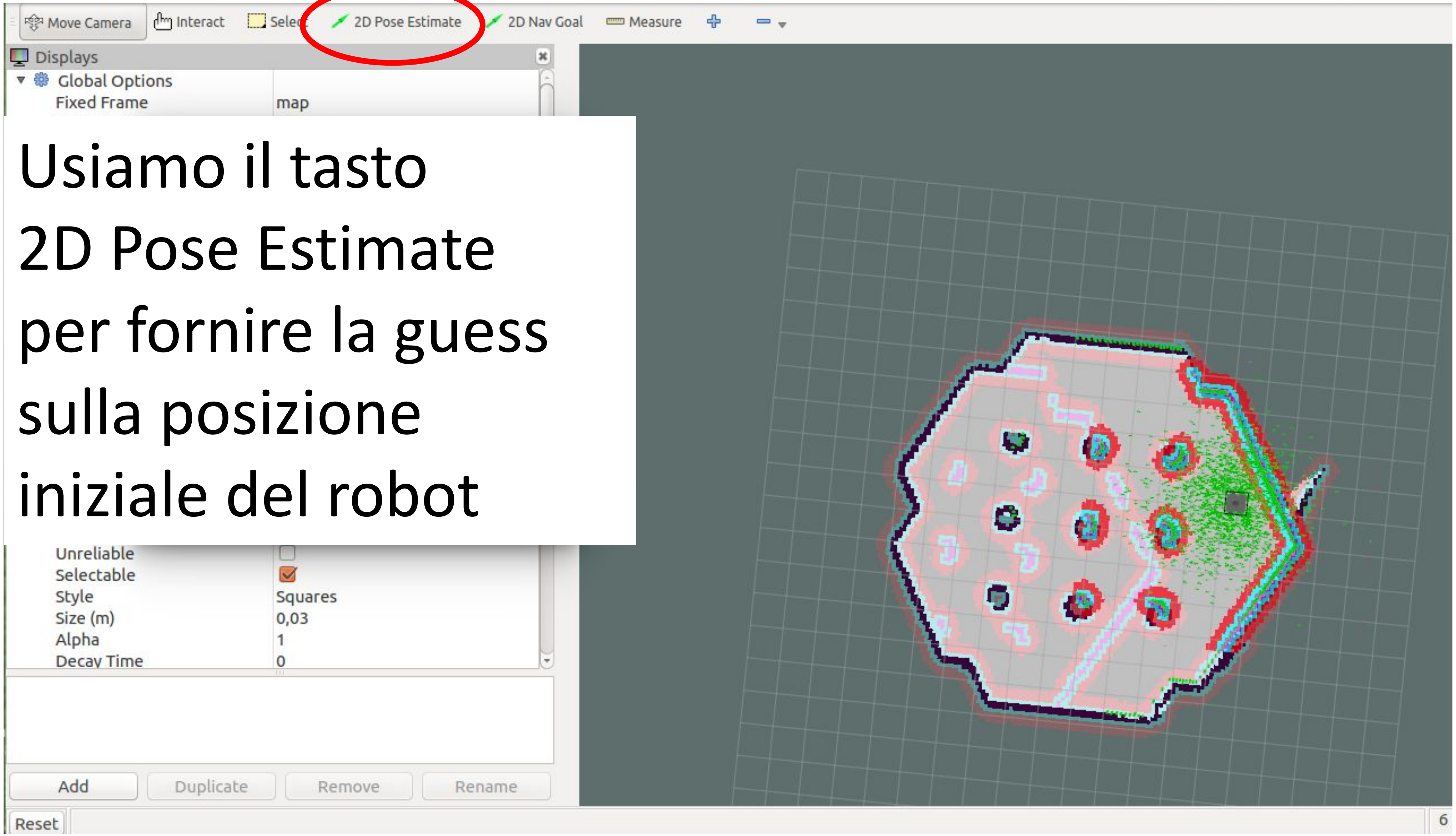
Navigazione con TurtleBot3



Navigazione con TurtleBot3

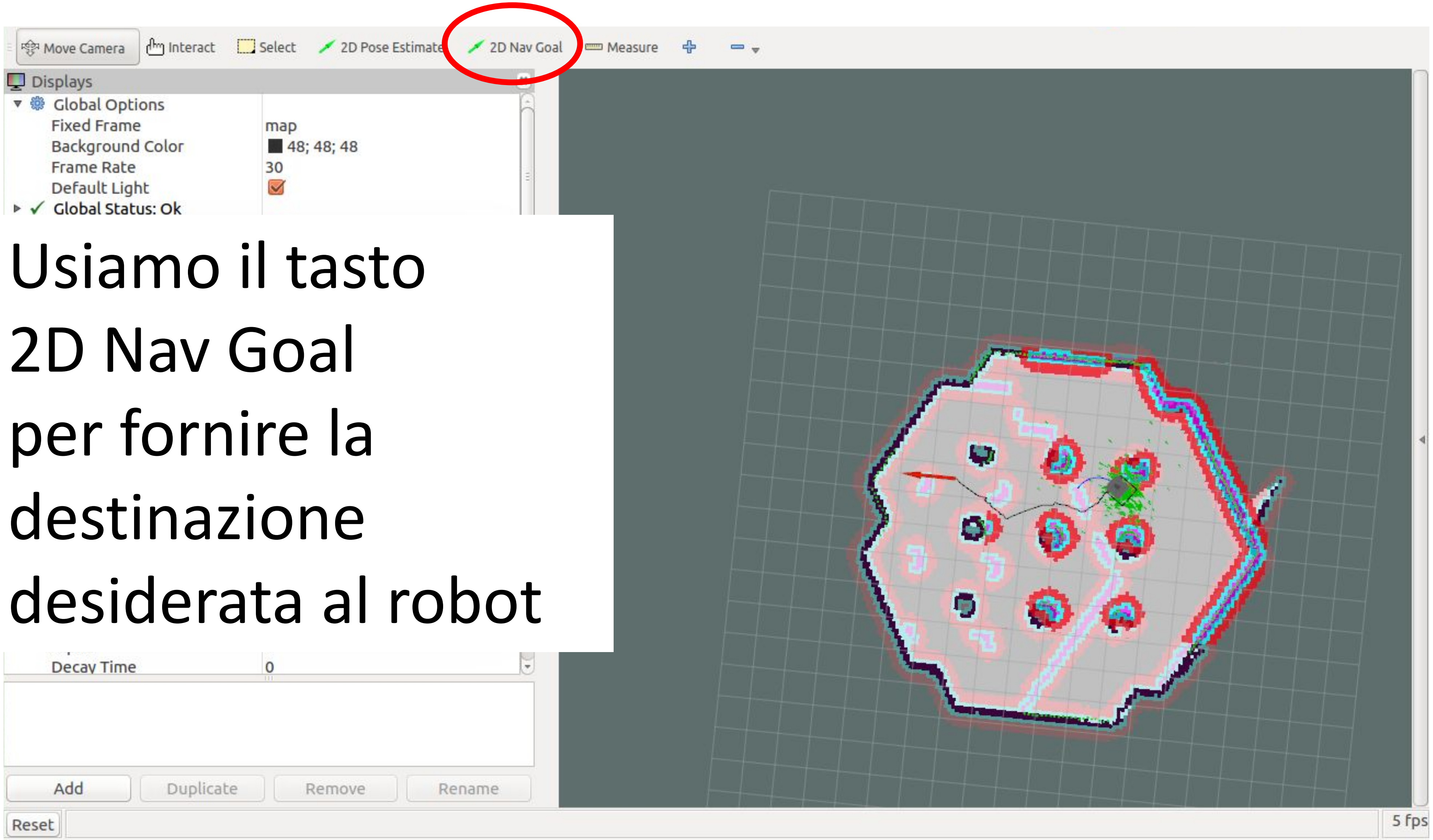


Pose Estimate



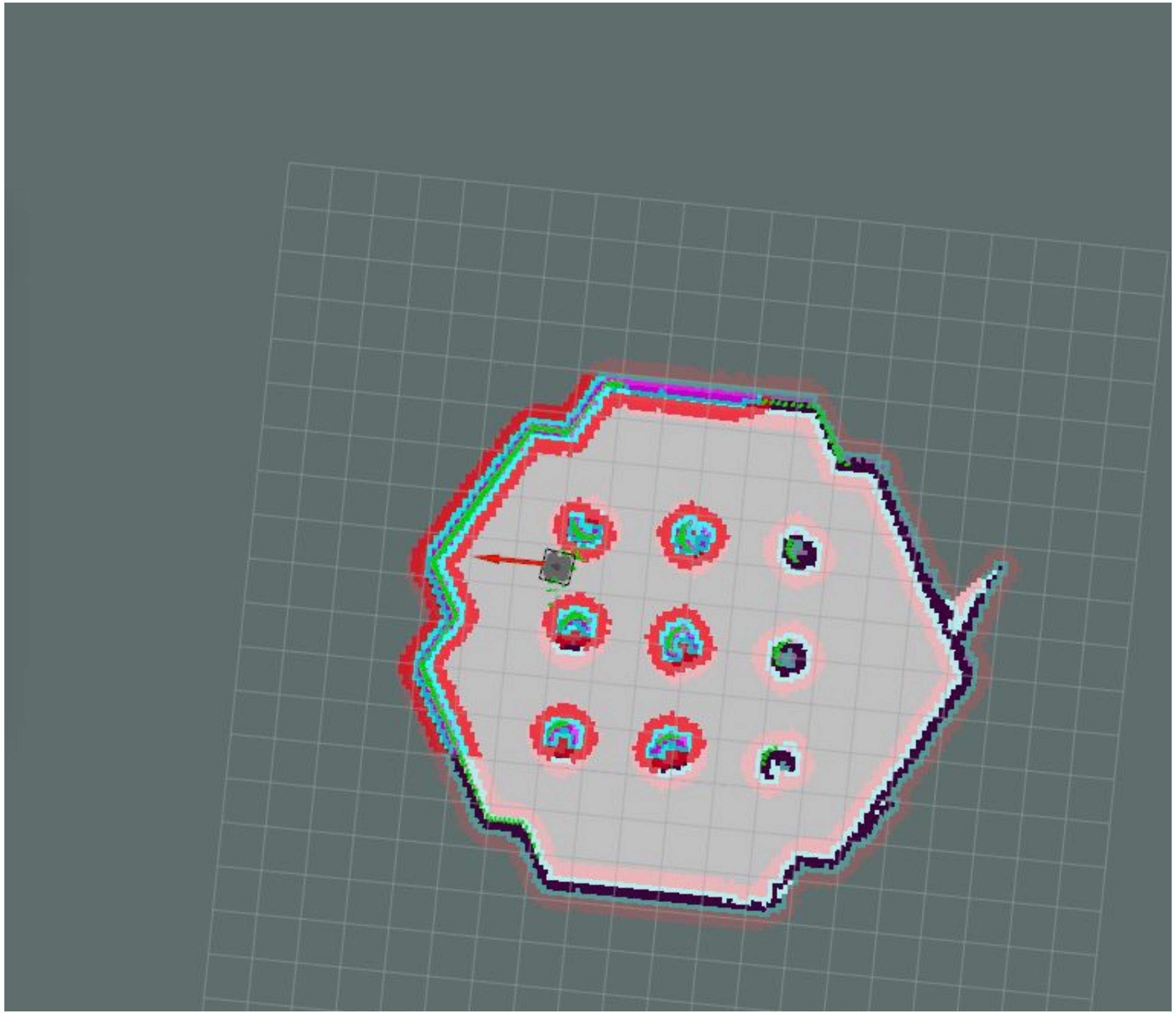
Usiamo il tasto
2D Pose Estimate
per fornire la guess
sulla posizione
iniziale del robot

Navigation Goal



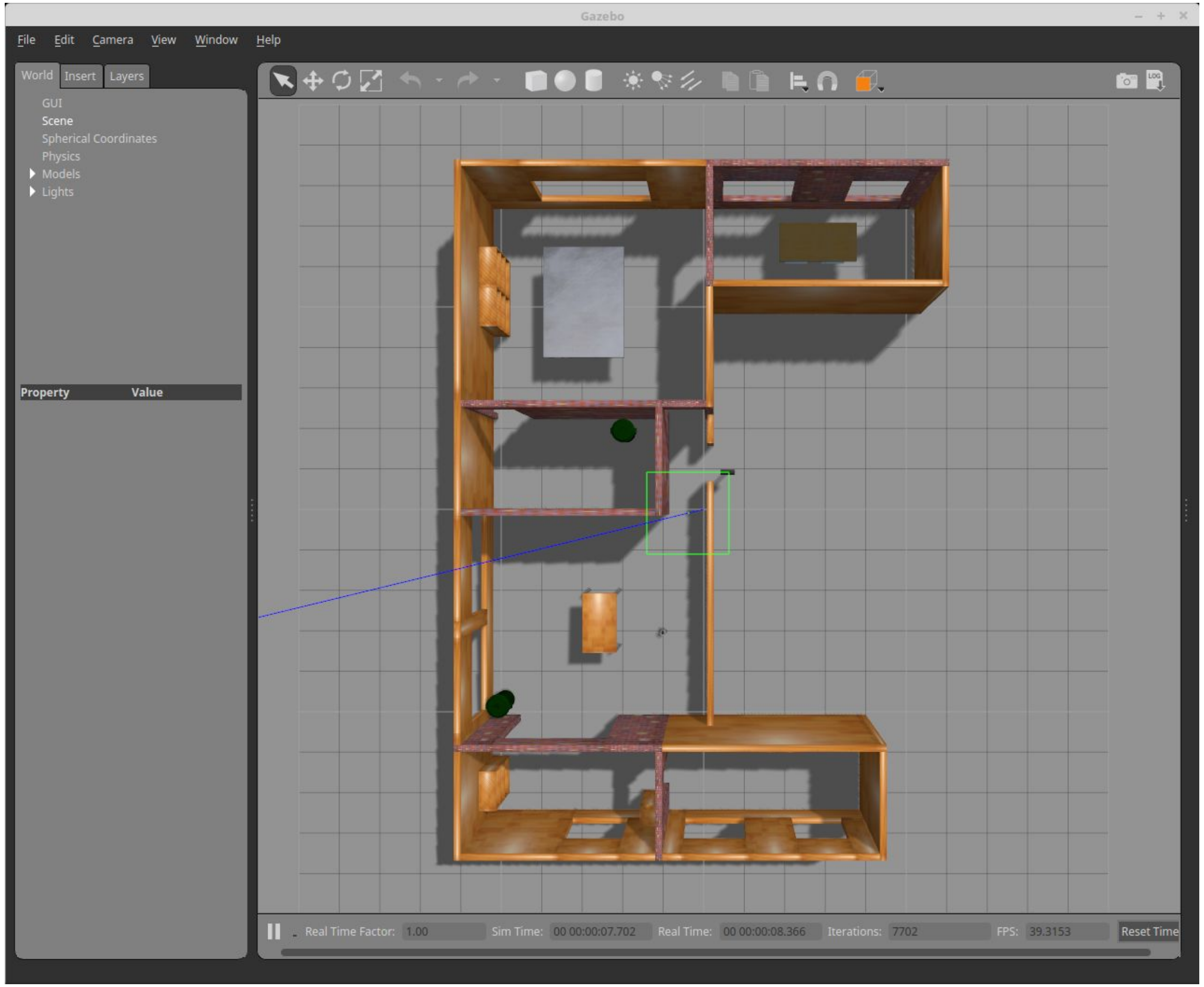
Usiamo il tasto
2D Nav Goal
per fornire la
destinazione
desiderata al robot

Goal raggiunto



Esercizio 1

Creare una mappa dell’ambiente TurtleBot3 House e utilizzarla per far navigare il robot



http://emanual.robotis.com/docs/en/platform/turtlebot3/simulation/

Esercizio 2

1. Provare a creare una mappa dell’ambiente cyber_lab (scaricabile da https://github.com/dbloisi/cyber_lab_gazebo)

2. Utilizzare il TurtleBot3 per navigare autonomamente nel mondo cyber_lab

UNIVERSITÀ DEGLI STUDI DELLA BASILICATA



Corso di Visione e Percezione

Docente

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Navigazione in ROS