COMPUTER AIDED MANUFACTURING (CAM)

UNIT 5

(ROBOTICS)

Motivation

- Intelligent Environments are aimed at improving the inhabitants' experience and task performance
  - Automate functions in the home
  - Provide services to the inhabitants
- Decisions coming from the decision maker(s) in the environment have to be executed.
  - Decisions require actions to be performed on devices
  - Decisions are frequently not elementary device interactions but rather relatively complex commands
    - Decisions define set points or results that have to be achieved
    - Decisions can require entire tasks to be performed

Automation and Robotics in Intelligent Environments

- Control of the physical environment
  - Automated blinds
  - Thermostats and heating ducts
  - Automatic doors
  - Automatic room partitioning
- Personal service robots
  - House cleaning
  - Lawn mowing
  - Assistance to the elderly and handicapped
  - Office assistants
  - Security services

Robots

- Robota (Czech) = A worker of forced labor

  From Czech playwright Karel Capek's 1921 play "R.U.R" ("Rossum's Universal Robots")
- Japanese Industrial Robot Association (JIRA) :

  "A device with degrees of freedom that can be controlled."
  - Class 1 : Manual handling device
  - Class 2 : Fixed sequence robot
  - Class 3 : Variable sequence robot
  - Class 4 : Playback robot
  - Class 5 : Numerical control robot
  - Class 6 : Intelligent robot

A Brief History of Robotics

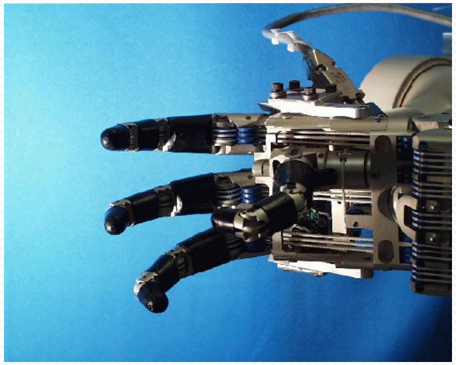
- Mechanical Automata
  - Ancient Greece & Egypt
    - Water powered for ceremonies
  - 14^{th} – 19^{th} century Europe
    - Clockwork driven for entertainment
- Motor driven Robots
  - 1928: First motor driven automata
  - 1961: Unimate
    - First industrial robot
  - 1967: Shakey
    - Autonomous mobile research robot
  - 1969: Stanford Arm
    - Dextrous, electric motor driven robot arm

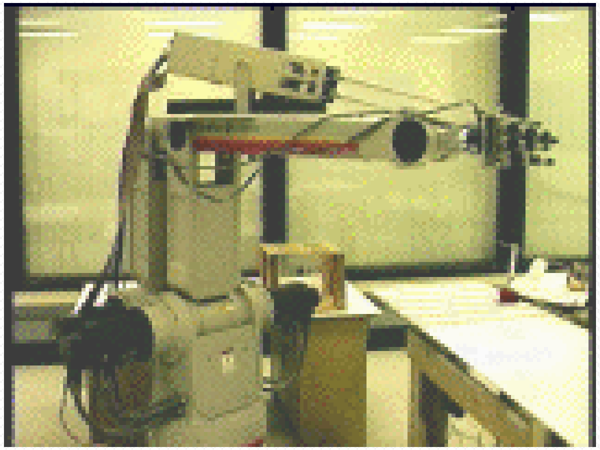
Maillardet's Automaton

Unimate

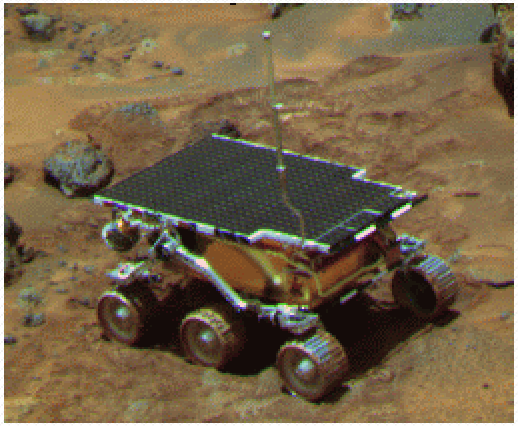
Robots

- Robot Manipulators



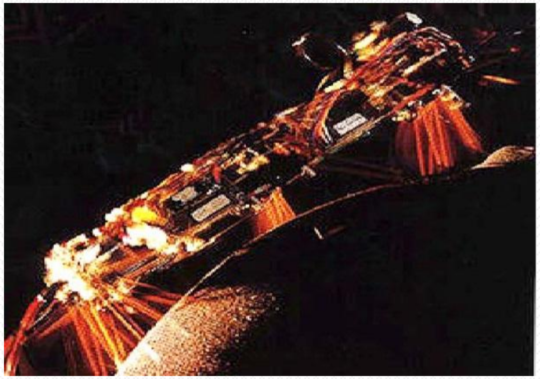


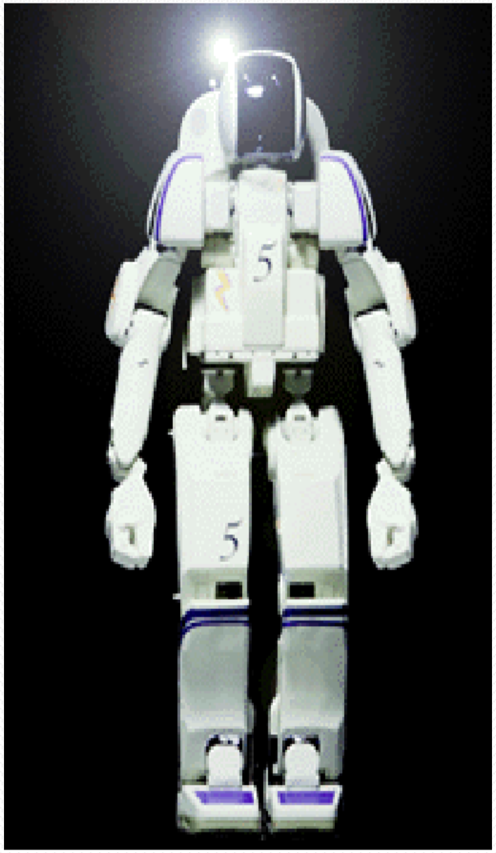
- Mobile Robots



Robots

- Walking Robots





- Humanoid Robots

Autonomous Robots

- The control of autonomous robots involves a number of subtasks
  - Understanding and modeling of the mechanism
    - Kinematics, Dynamics, and Odometry
  - Reliable control of the actuators
    - Closed-loop control
  - Generation of task-specific motions
    - Path planning
  - Integration of sensors
    - Selection and interfacing of various types of sensors
  - Coping with noise and uncertainty
    - Filtering of sensor noise and actuator uncertainty
  - Creation of flexible control policies
    - Control has to deal with new situations

Traditional Industrial Robots

- Traditional industrial robot control uses robot arms and largely pre-computed motions
  - Programming using “teach box”
  - Repetitive tasks
  - High speed
  - Few sensing operations
  - High precision movements
  - Pre-planned trajectories and task policies
  - No interaction with humans

Problems

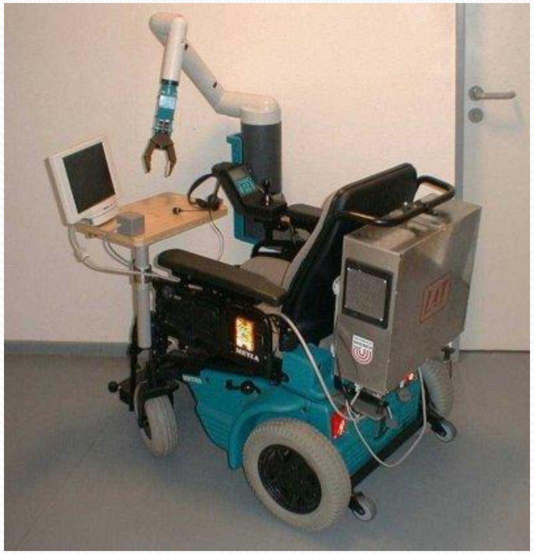
- Traditional programming techniques for industrial robots lack key capabilities necessary in intelligent environments
  - Only limited on-line sensing
  - No incorporation of uncertainty
  - No interaction with humans
  - Reliance on perfect task information
  - Complete re-programming for new tasks

Requirements for Robots in Intelligent Environments

- Autonomy
  - Robots have to be capable of achieving task objectives without human input
  - Robots have to be able to make and execute their own decisions based on sensor information
- Intuitive Human-Robot Interfaces
  - Use of robots in smart homes can not require extensive user training
  - Commands to robots should be natural for inhabitants
- Adaptation
  - Robots have to be able to adjust to changes in the environment

Robots for Intelligent Environments

- Service Robots
  - Security guard
  - Delivery
  - Cleaning
  - Mowing
- Assistance Robots
  - Mobility
  - Services for elderly and People with disabilities

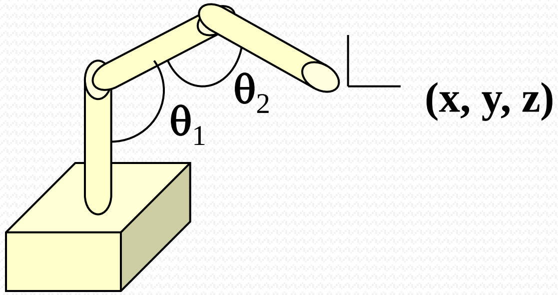


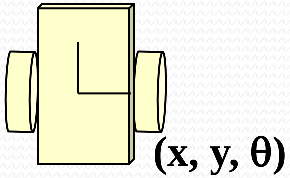
Autonomous Robot Control

- To control robots to perform tasks autonomously a number of tasks have to be addressed:
  - Modeling of robot mechanisms
    - Kinematics, Dynamics
  - Robot sensor selection
    - Active and passive proximity sensors
  - Low-level control of actuators
    - Closed-loop control
  - Control architectures
    - Traditional planning architectures
    - Behavior-based control architectures
    - Hybrid architectures

Modeling the Robot Mechanism

- Forward kinematics describes how the robots joint angle configurations translate to locations in the world





- Inverse kinematics computes the joint angle configuration necessary to reach a particular point in space.
- Jacobians calculate how the speed and configuration of the actuators translate into velocity of the robot

Mobile Robot Odometry

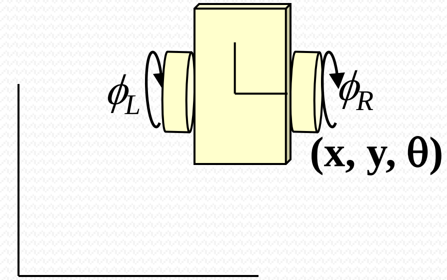
- In mobile robots the same configuration in terms of joint angles does not identify a unique location
  - To keep track of the robot it is necessary to incrementally update the location (this process is called odometry or dead reckoning)

$$\begin{pmatrix} x \\ y \\ \theta \end{pmatrix}^{t+\Delta t} = \begin{pmatrix} x \\ y \\ \theta \end{pmatrix}^{t} + \begin{pmatrix} v_x \\ v_y \\ \varpi \end{pmatrix} \Delta t$$

- Example: A differential drive robot

$$v_x = \cos(\theta)\frac{r(\dot{\phi}_L + \dot{\phi}_R)}{2}, v_y = \sin(\theta)\frac{r(\dot{\phi}_L + \dot{\phi}_R)}{2}$$

$$\varpi = \frac{r}{d}\left(\dot{\phi}_L - \dot{\phi}_R\right)$$



Actuator Control

- To get a particular robot actuator to a particular location it is important to apply the correct amount of force or torque to it.
  - Requires knowledge of the dynamics of the robot
    - Mass, inertia, friction
    - For a simplistic mobile robot: $F = m\,a + B\,v$
  - Frequently actuators are treated as if they were independent (i.e. as if moving one joint would not affect any of the other joints).
  - The most common control approach is PD-control (proportional, differential control)
    - For the simplistic mobile robot moving in the x direction:

$$F = K_P\left(x_{desired} - x_{actual}\right) + K_D\left(v_{desired} - v_{actual}\right)$$

Robot Navigation

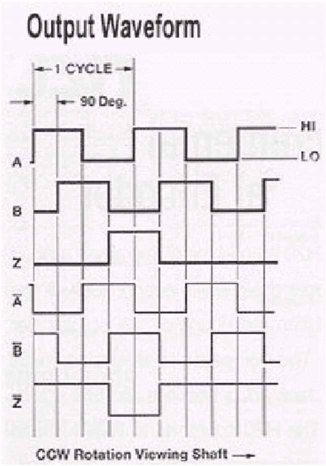
- Path planning addresses the task of computing a trajectory for the robot such that it reaches the desired goal without colliding with obstacles
  - Optimal paths are hard to compute in particular for robots that can not move in arbitrary directions (i.e. nonholonomic robots)
  - Shortest distance paths can be dangerous since they always graze obstacles
  - Paths for robot arms have to take into account the entire robot (not only the endeffector)

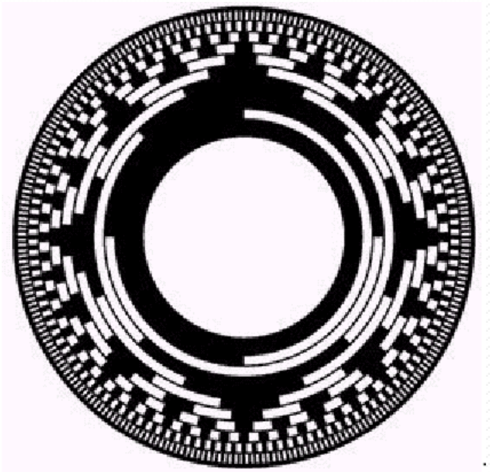
Sensor-Driven Robot Control

- To accurately achieve a task in an intelligent environment, a robot has to be able to react dynamically to changes ion its surrounding
  - Robots need sensors to perceive the environment
  - Most robots use a set of different sensors
    - Different sensors serve different purposes
  - Information from sensors has to be integrated into the control of the robot

Robot Sensors

- Internal sensors to measure the robot configuration
  - Encoders measure the rotation angle of a joint

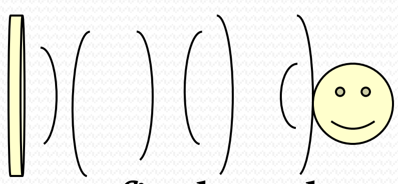




  - Limit switches detect when the joint has reached the limit

Robot Sensors

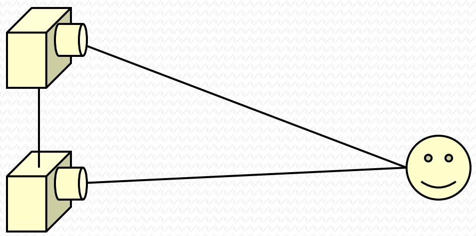
- Proximity sensors are used to measure the distance or location of objects in the environment. This can then be used to determine the location of the robot.
  - Infrared sensors determine the distance to an object by measuring the amount of infrared light the object reflects back to the robot
  - Ultrasonic sensors (sonars) measure the time that an ultrasonic signal takes until it returns to the robot



  - Laser range finders determine dist
measuring either the time it takes for a laser beam to be reflected back to the robot or by measuring where the laser hits the object

Robot Sensors

- Computer Vision provides robots with the capability to passively observe the environment
  - Stereo vision systems provide complete location information using triangulation



  - However, computer vision is very complex
    - Correspondence problem makes stereo vision even more difficult

Uncertainty in Robot Systems

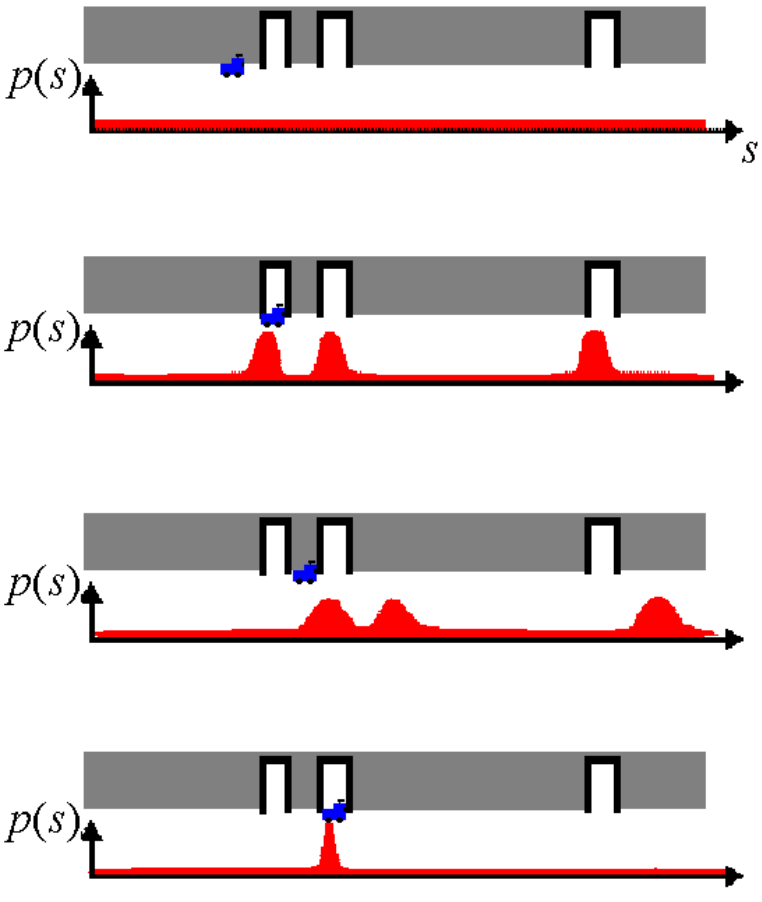
- Robot systems in intelligent environments have to deal with sensor noise and uncertainty
  - Sensor uncertainty
    - Sensor readings are imprecise and unreliable
  - Non-observability
    - Various aspects of the environment can not be observed
    - The environment is initially unknown
  - Action uncertainty
    - Actions can fail
    - Actions have nondeterministic outcomes

Probabilistic Robot Localization

- Explicit reasoning about Uncertainty using Bayes filters:

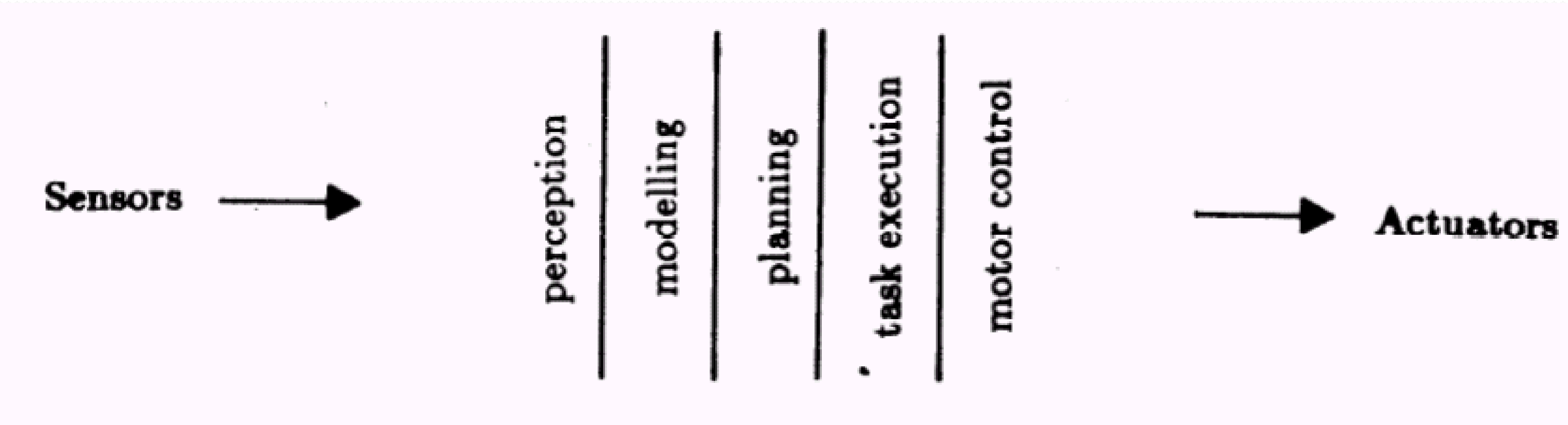
$$b(x_t) = \eta\ p(o_t \mid x_t) \int p(x_t \mid x_{t-1}, a_{t-1})\ b(x_{t-1})\ dx_{t-1}$$

- Used for:
  - Localization
  - Mapping
  - Model building



Deliberative Robot Control Architectures

- In a deliberative control architecture the robot first plans a solution for the task by reasoning about the outcome of its actions and then executes it



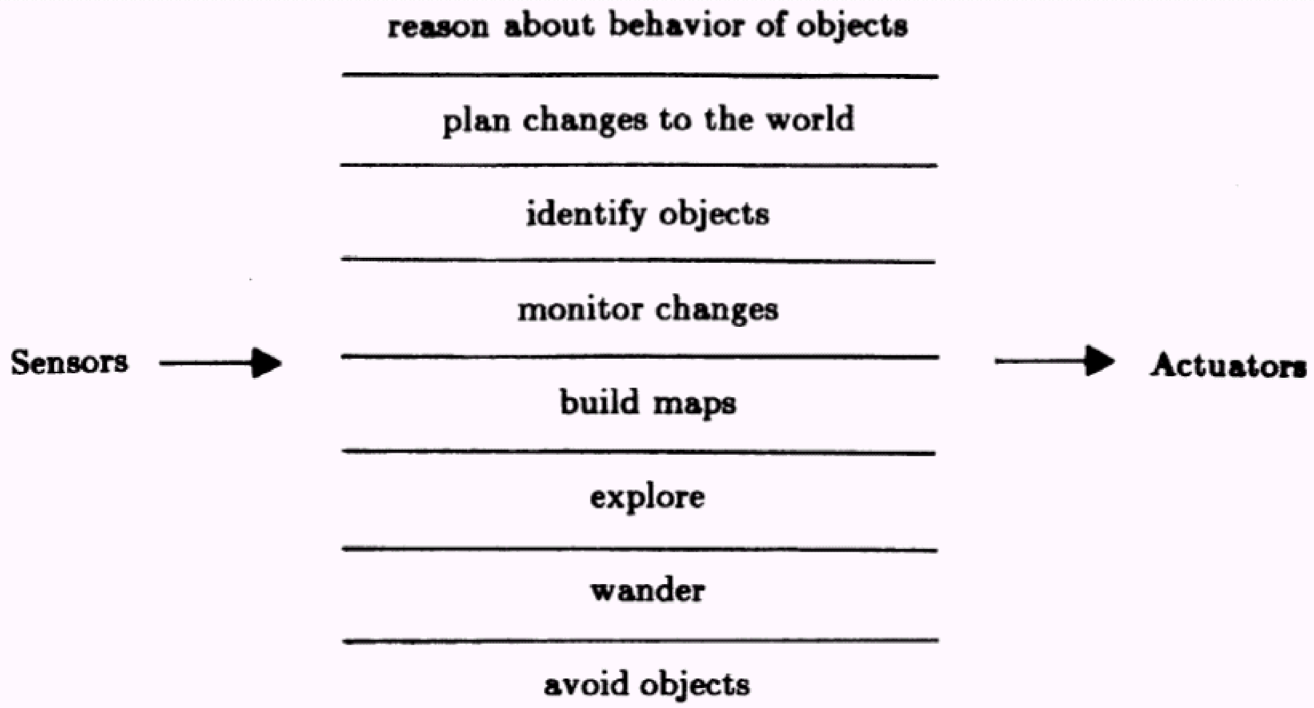
- Control process goes through a sequence of sencing, model update, and planning steps

Deliberative Control Architectures

- Advantages
  - Reasons about contingencies
  - Computes solutions to the given task
  - Goal-directed strategies
- Problems
  - Solutions tend to be fragile in the presence of uncertainty
  - Requires frequent replanning
  - Reacts relatively slowly to changes and unexpected occurrences

Behavior-Based Robot Control Architectures

- In a behavior-based control architecture the robot's actions are determined by a set of parallel, reactive behaviors which map sensory input and state to actions.

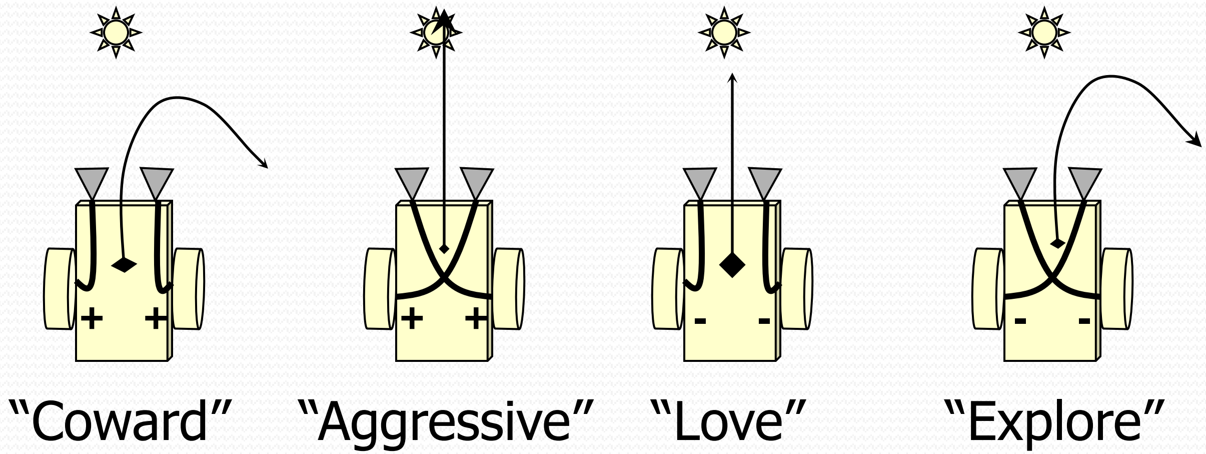


Behavior-Based Robot Control Architectures

- Reactive, behavior-based control combines relatively simple behaviors, each of which achieves a particular subtask, to achieve the overall task.
  - Robot can react fast to changes
  - System does not depend on complete knowledge of the environment
  - Emergent behavior (resulting from combining initial behaviors) can make it difficult to predict exact behavior
  - Difficult to assure that the overall task is achieved

Complex Behavior from Simple Elements: Braitenberg Vehicles

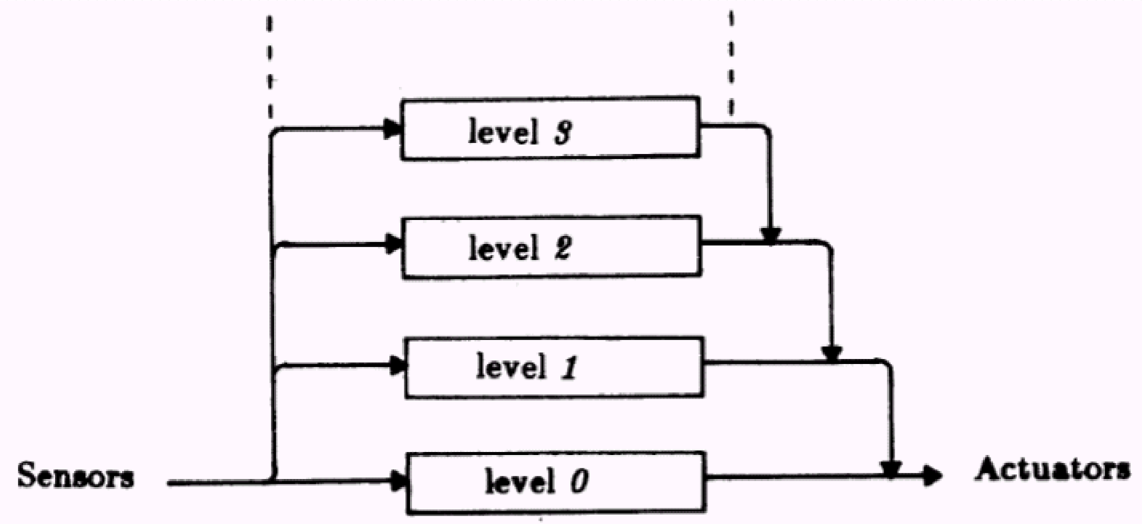
- Complex behavior can be achieved using very simple control mechanisms
  - Braitenberg vehicles: differential drive mobile robots with two light sensors



  - Complex external behavior does not necessarily require a complex reasoning mechanism

Behavior-Based Architectures: Subsumption Example

- Subsumption architecture is one of the earliest behavior-based architectures
  - Behaviors are arranged in a strict priority order where higher priority behaviors subsume lower priority ones as long as they are not inhibited.



Subsumption Example

- A variety of tasks can be robustly performed from a small number of behavioral elements

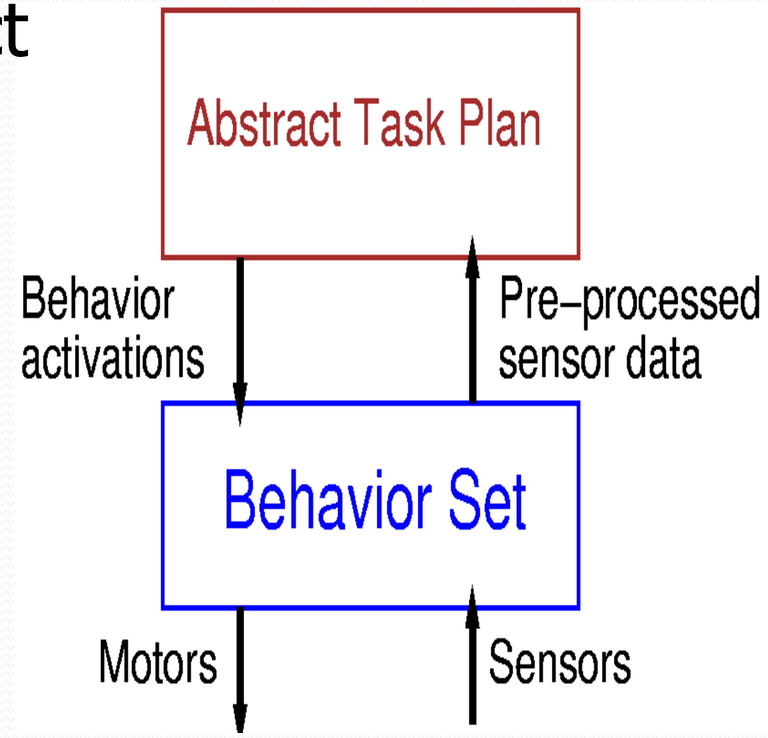
http://www-robotics.usc.edu/~maja/robot-video.mpg

Reactive, Behavior-Based Control Architectures

- Advantages
  - Reacts fast to changes
  - Does not rely on accurate models
    - “The world is its own best model”
  - No need for replanning
- Problems
  - Difficult to anticipate what effect combinations of behaviors will have
  - Difficult to construct strategies that will achieve complex, novel tasks
  - Requires redesign of control system for new tasks

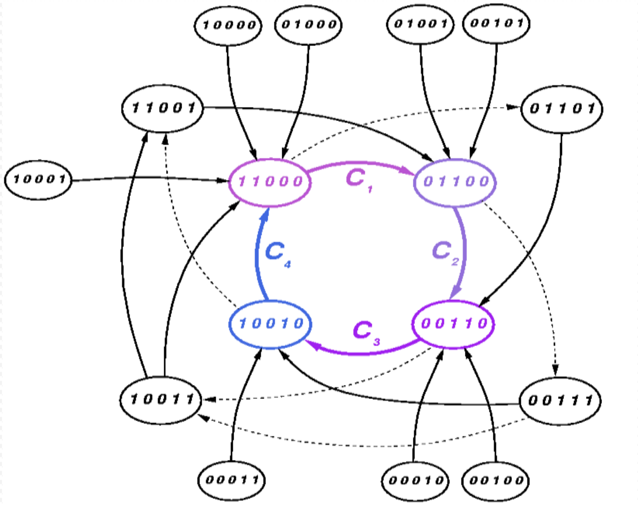
Hybrid Control Architectures

- Hybrid architectures combine reactive control with abstract task planning
  - Abstract task planning layer
    - Deliberative decisions
    - Plans goal directed policies
  - Reactive behavior layer
    - Provides reactive actions
    - Handles sensors and actuators

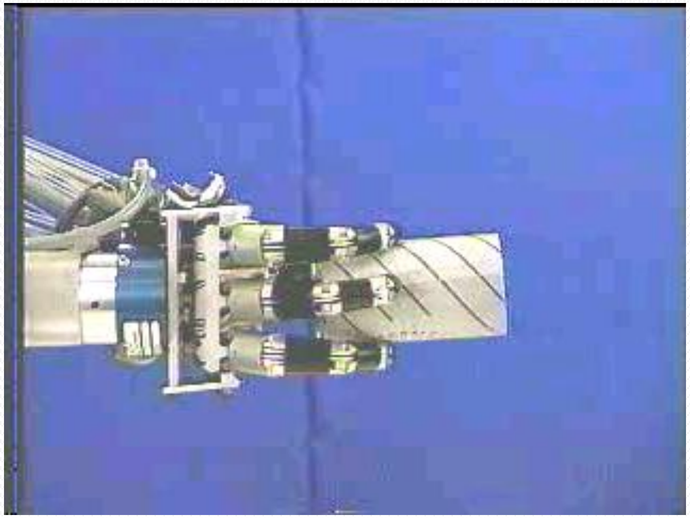


Hybrid Control Policies

Task Plan:



Behavioral Strategy:



Example Task: Changing a Light Bulb

Hybrid Control Architectures

- Advantages
  - Permits goal-based strategies
  - Ensures fast reactions to unexpected changes
  - Reduces complexity of planning
- Problems
  - Choice of behaviors limits range of possible tasks
  - Behavior interactions have to be well modeled to be able to form plans

Traditional Human-Robot Interface: Teleoperation

- Remote Teleoperation: Direct operation of the robot by the user
  - User uses a 3-D joystick or an exoskeleton to drive the robot
    - Simple to install
    - Removes user from dangerous areas
  - Problems:
    - Requires insight into the mechanism
    - Can be exhaustive
    - Easily leads to operation errors

Human-Robot Interaction in Intelligent Environments

- Personal service robot
  - Controlled and used by untrained users
    - Intuitive, easy to use interface
    - Interface has to “filter” user input
      - Eliminate dangerous instructions
      - Find closest possible action
  - Receive only intermittent commands
    - Robot requires autonomous capabilities
    - User commands can be at various levels of complexity
    - Control system merges instructions and autonomous operation
  - Interact with a variety of humans
    - Humans have to feel “comfortable” around robots
    - Robots have to communicate intentions in a natural way

Example: Minerva the Tour Guide Robot (CMU/Bonn)

http://www.cs.cmu.edu/~thrun/movies/minerva.mpg

Intuitive Robot Interfaces: Command Input

- Graphical programming interfaces
  - Users construct policies form elemental blocks
  - Problems:
    - Requires substantial understanding of the robot
- Deictic (pointing) interfaces
  - Humans point at desired targets in the world or
  - Target specification on a computer screen
  - Problems:
    - How to interpret human gestures ?
- Voice recognition
  - Humans instruct the robot verbally
  - Problems:
    - Speech recognition is very difficult
    - Robot actions corresponding to words has to be defined

Intuitive Robot Interfaces: Robot-Human Interaction

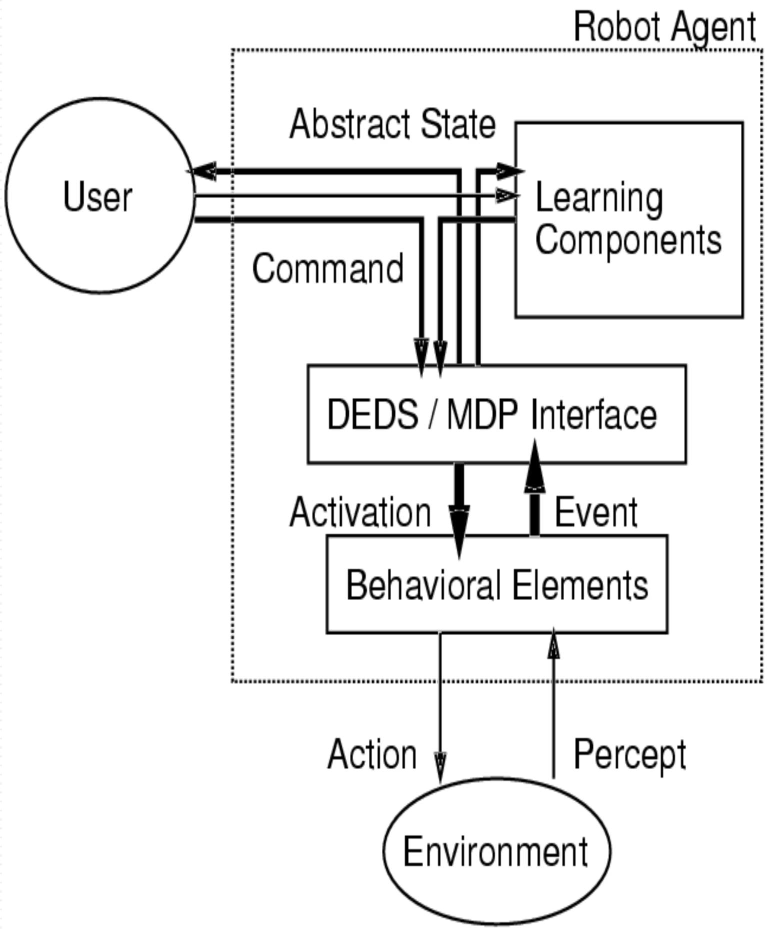
- He robot has to be able to communicate its intentions to the human
  - Output has to be easy to understand by humans
  - Robot has to be able to encode its intention
  - Interface has to keep human's attention without annoying her
- Robot communication devices:
  - Easy to understand computer screens
  - Speech synthesis
  - Robot "gestures"

Human-Robot Interfaces

- Existing technologies
  - Simple voice recognition and speech synthesis
  - Gesture recognition systems
  - On-screen, text-based interaction
- Research challenges
  - How to convey robot intentions ?
  - How to infer user intent from visual observation (how can a robot imitate a human) ?
  - How to keep the attention of a human on the robot ?
  - How to integrate human input with autonomous operation ?

Integration of Commands and Autonomous Operation

- Adjustable Autonomy
  - The robot can operate at varying levels of autonomy
  - Operational modes:
    - Autonomous operation
    - User operation / teleoperation
    - Behavioral programming
    - Following user instructions
    - Imitation
  - Types of user commands:
    - Continuous, low-level instructions (teleoperation)
    - Goal specifications
    - Task demonstrations



Example System

"Social" Robot Interactions

- To make robots acceptable to average users they should appear and behave “natural”
  - "Attentional" Robots
    - Robot focuses on the user or the task
    - Attention forms the first step to imitation
  - "Emotional" Robots
    - Robot exhibits “emotional” responses
    - Robot follows human social norms for behavior
      - Better acceptance by the user (users are more forgiving)
      - Human-machine interaction appears more “natural”
      - Robot can influence how the human reacts

"Social" Robot Interactions

- Advantages:
  - Robots that look human and that show “emotions” can make interactions more “natural”
    - Humans tend to focus more attention on people than on objects
    - Humans tend to be more forgiving when a mistake is made if it looks “human”
  - Robots showing “emotions” can modify the way in which humans interact with them
- Problems:
  - How can robots determine the right emotion ?
  - How can “emotions” be expressed by a robot ?

Human-Robot Interfaces for Intelligent Environments

- Robot Interfaces have to be easy to use
  - Robots have to be controllable by untrained users
  - Robots have to be able to interact not only with their owner but also with other people
- Robot interfaces have to be usable at the human's discretion
  - Human-robot interaction occurs on an irregular basis
    - Frequently the robot has to operate autonomously
    - Whenever user input is provided the robot has to react to it
- Interfaces have to be designed human-centric
  - The role of the robot is it to make the human's life easier and more comfortable (it is not just a tech toy)

Adaptation and Learning for Robots in Smart Homes

- Intelligent Environments are non-stationary and change frequently, requiring robots to adapt
  - Adaptation to changes in the environment
  - Learning to address changes in inhabitant preferences
- Robots in intelligent environments can frequently not be pre-programmed
  - The environment is unknown
  - The list of tasks that the robot should perform might not be known beforehand
    - No proliferation of robots in the home
  - Different users have different preferences

Adaptation and Learning In Autonomous Robots

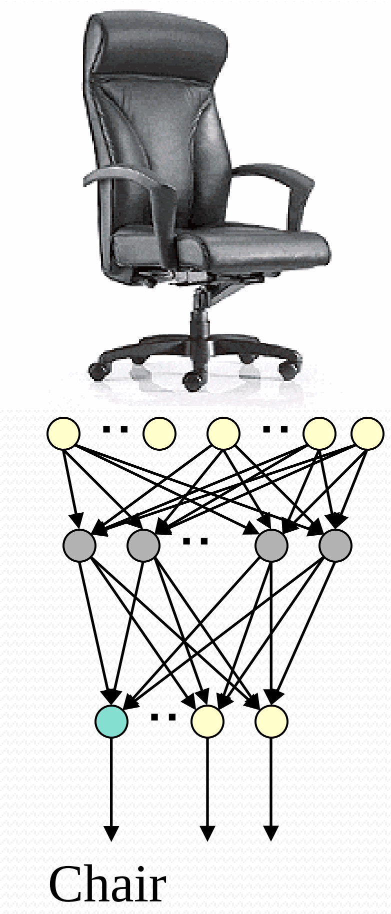
- Learning to interpret sensor information
  - Recognizing objects in the environment is difficult
  - Sensors provide prohibitively large amounts of data
  - Programming of all required objects is generally not possible
- Learning new strategies and tasks
  - New tasks have to be learned on-line in the home
  - Different inhabitants require new strategies even for existing tasks
- Adaptation of existing control policies
  - User preferences can change dynamically
  - Changes in the environment have to be reflected

Learning Approaches for Robot Systems

- Supervised learning by teaching
  - Robots can learn from direct feedback from the user that indicates the correct strategy
    - The robot learns the exact strategy provided by the user
- Learning from demonstration (Imitation)
  - Robots learn by observing a human or a robot perform the required task
    - The robot has to be able to “understand” what it observes and map it onto its own capabilities
- Learning by exploration
  - Robots can learn autonomously by trying different actions and observing their results
    - The robot learns a strategy that optimizes reward

Learning Sensory Patterns

- Learning to Identify Objects
  - How can a particular object be recognized ?
    - Programming recognition strategies is difficult because we do not fully understand how we perform recognition
    - Learning techniques permit the robot system to form its own recognition strategy
  - Supervised learning can be used by giving the robot a set of pictures and the corresponding classification
    - Neural networks
    - Decision trees

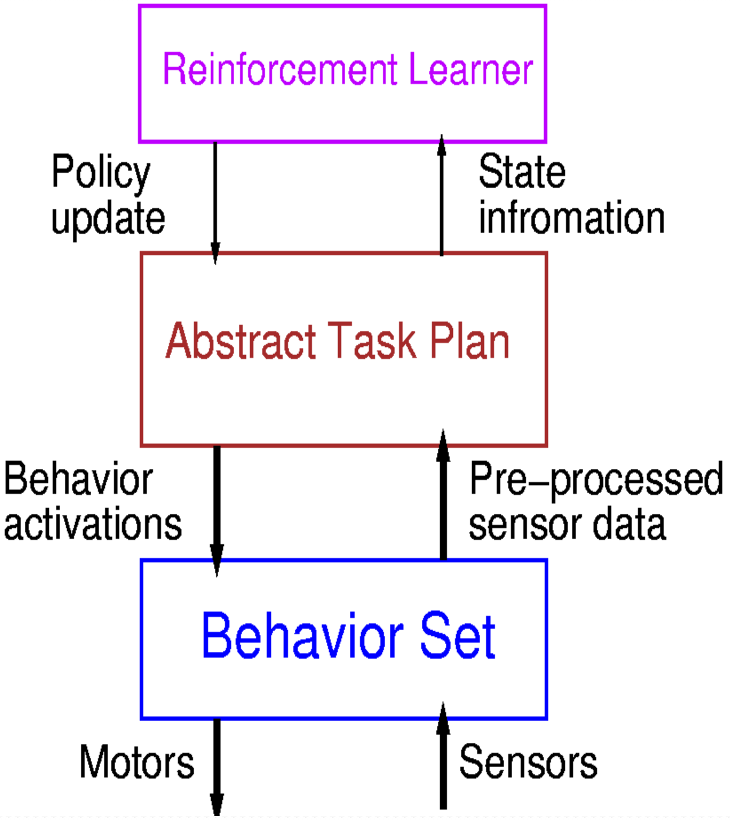


Learning Task Strategies by Experimentation

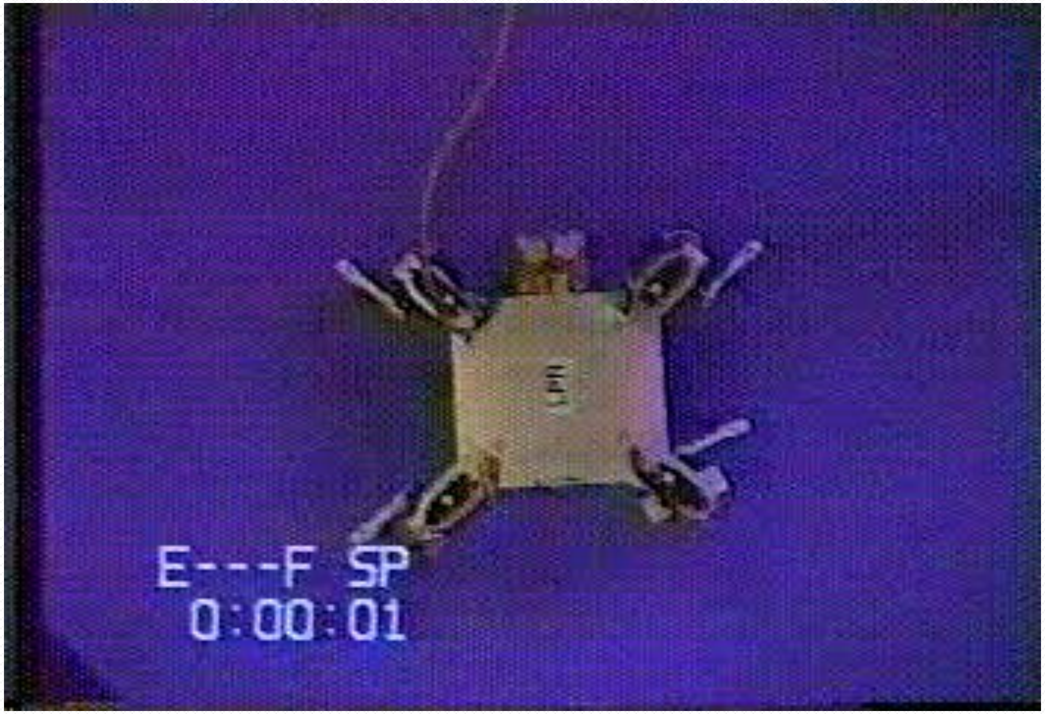
- Autonomous robots have to be able to learn new tasks even without input from the user
  - Learning to perform a task in order to optimize the reward the robot obtains (Reinforcement Learning)
    - Reward has to be provided either by the user or the environment
      - Intermittent user feedback
      - Generic rewards indicating unsafe or inconvenient actions or occurrences
    - The robot has to explore its actions to determine what their effects are
      - Actions change the state of the environment
      - Actions achieve different amounts of reward
    - During learning the robot has to maintain a level of safety

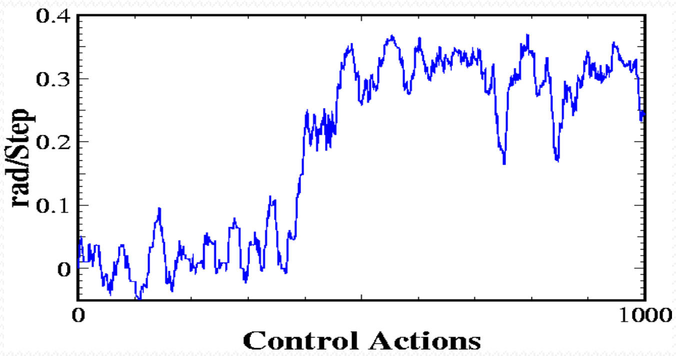
Example: Reinforcement Learning in a Hybrid Architecture

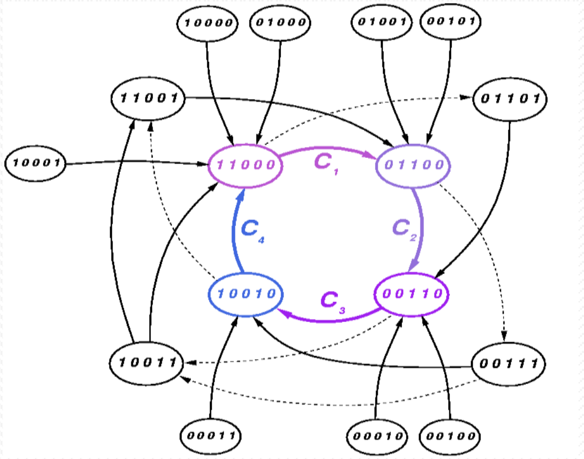
- Policy Acquisition Layer
  - Learning tasks without supervision
- Abstract Plan Layer
  - Learning a system model
  - Basic state space compression
- Reactive Behavior Layer
  - Initial competence and reactivity



Example Task: Learning to Walk







Scaling Up: Learning Complex Tasks from Simpler Tasks

- Complex tasks are hard to learn since they involve long sequences of actions that have to be correct in order for reward to be obtained
- Complex tasks can be learned as shorter sequences of simpler tasks
  - Control strategies that are expressed in terms of subgoals are more compact and simpler
  - Fewer conditions have to be considered if simpler tasks are already solved
  - New tasks can be learned faster
  - Hierarchical Reinforcement Learning
    - Learning with abstract actions
    - Acquisition of abstract task knowledge

Example: Learning to Walk