

Final Review

CSCI 545 Introduction to Robotics
Instructor: Stefanos Nikolaidis

Linear Programming

- Consider the Linear Program

$$\max z = x_1 + 2x_2$$

s.t.

$$x_1 \leq 3$$

$$x_1 + x_2 \leq 5$$

$$x_1, x_2 \geq 0$$

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- Illustrate graphically:
 - The hyperplanes defined by the constraints
 - The gradient of the cost function
 - The feasible region
 - The optimal solution

Linear Programming

x_2

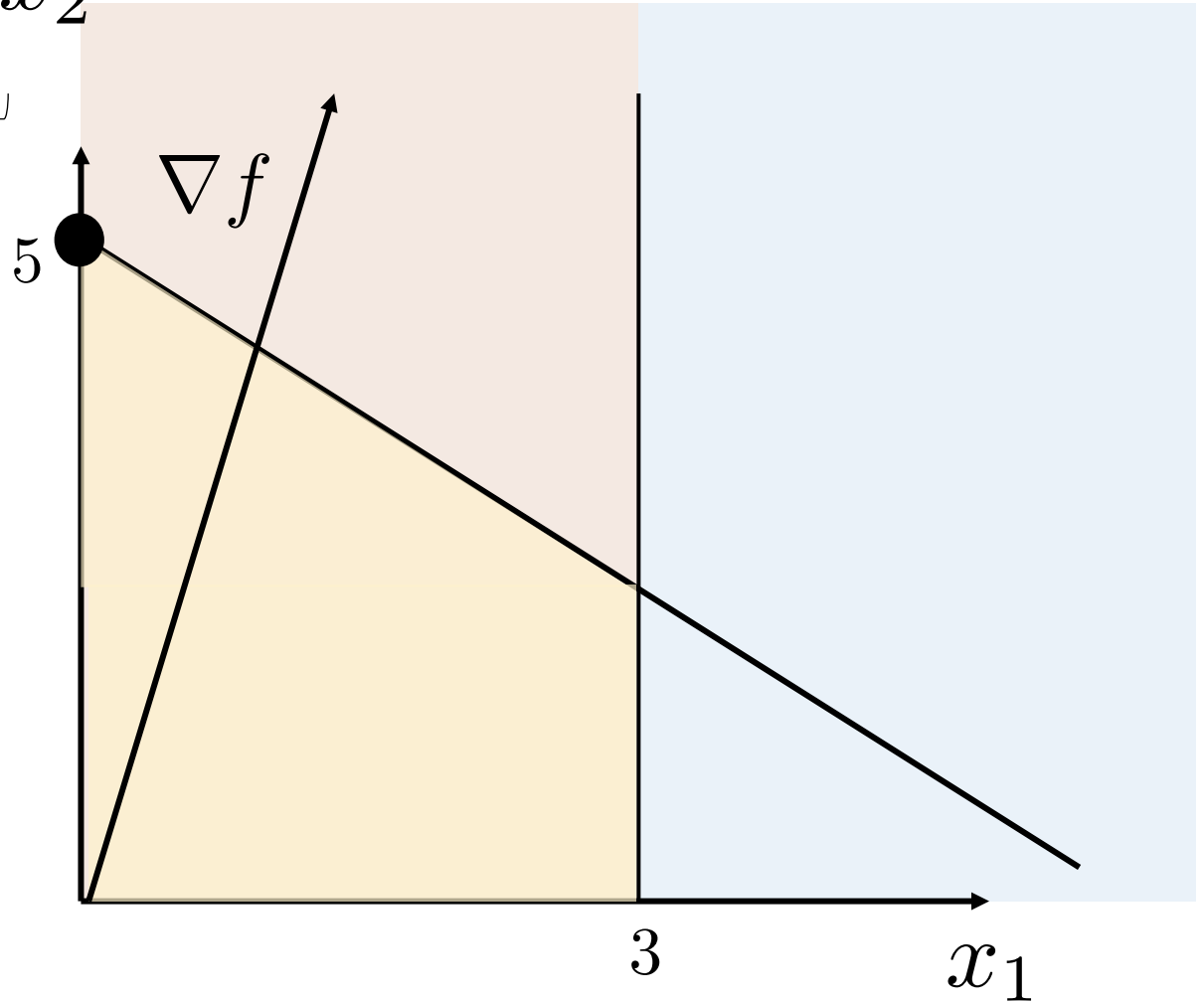
$$\max z = \underbrace{x_1 + 2x_2}_{f(x_1, x_2)}$$

s.t. $f(x_1, x_2)$

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Configuration Spaces

- Match the following robots and configuration spaces

1. Mobile Robot Translating on a plane $SE(2) \times T^2$
2. Mobile robot translating and rotating on a plane $SE(2)$ or $\mathbb{R}^2 \times S^1$
3. A spacecraft \mathbb{R}^2
4. An n-joint revolute arm T^n
5. A mobile planar robot with a two-joint arm $SE(3)$ or $\mathbb{R}^3 \times SO(3)$

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Forward / Inverse Kinematics

- Formally define:
 1. A forward kinematics map for a planar robot

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$$\phi : Q \rightarrow SE(2)$$

$$\text{Phi} : Q \rightarrow SE(2)$$

2. An inverse kinematics map for a planar robot:

Forward / Inverse Kinematics

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$$\phi^{-1} : SE(2) \rightarrow Q$$

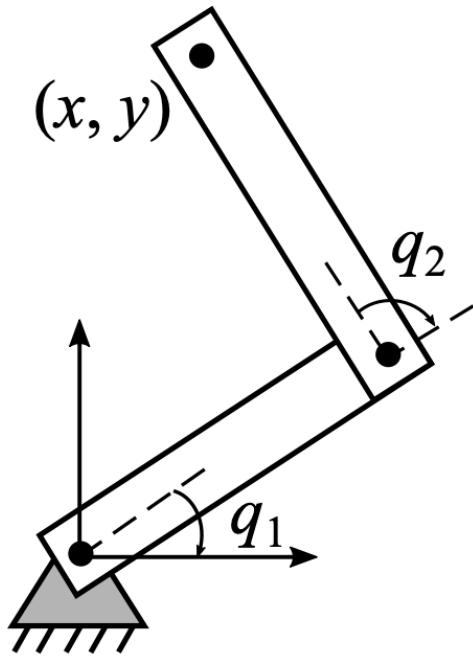
$$\text{Phi}^{-1} : SE(2) \rightarrow Q$$

(or $\phi^{-1} : \mathbb{R}^2 \rightarrow Q$)

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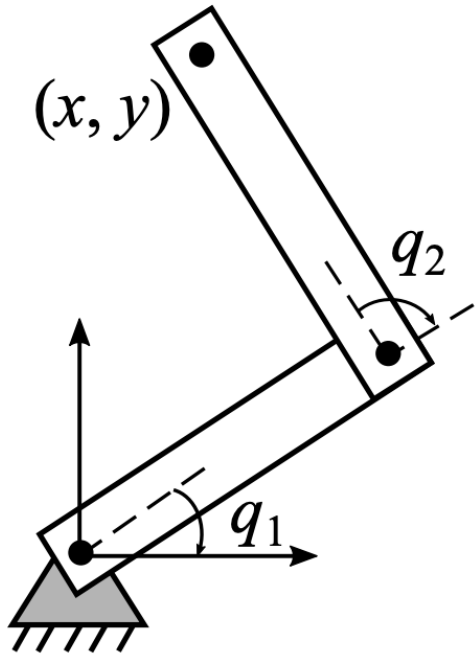
Forward / Inverse Kinematics

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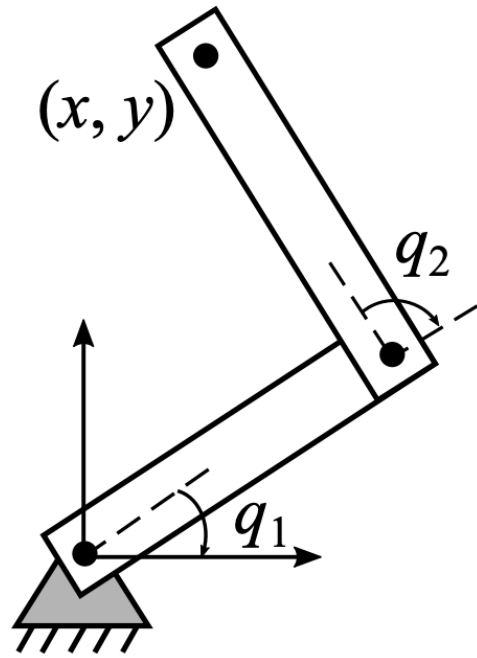


$$\begin{aligned} \begin{bmatrix} x \\ y \end{bmatrix} &= \begin{bmatrix} l_1 \cos(q_1) + l_2 \cos(q_1 + q_2) \\ l_1 \sin(q_1) + l_2 \sin(q_1 + q_2) \end{bmatrix} \\ &= \phi(q_1, q_2) \\ &= \begin{bmatrix} \phi_1(q_1, q_2) \\ \phi_2(q_1, q_2) \end{bmatrix} \end{aligned}$$

$$\begin{aligned} x &= l_1 \cos(q_1) + l_2 \cos(q_1 + q_2) \\ y &= l_1 \sin(q_1) + l_2 \sin(q_1 + q_2) \end{aligned}$$

Forward / Inverse Kinematics

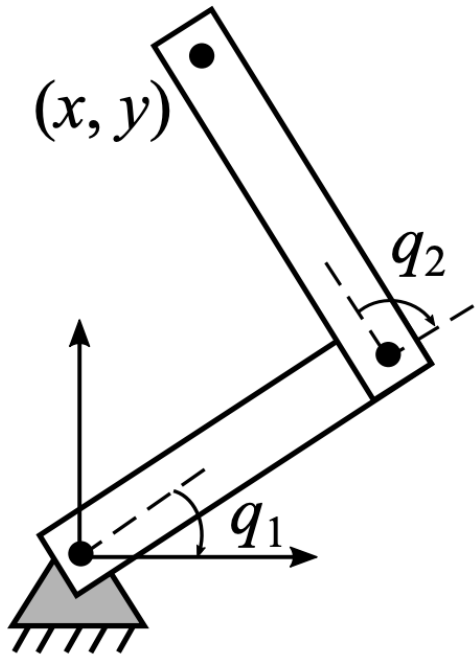
- Compute the velocity of the end-effector for the planar arm:



$$l_1 = l_2 = 1, q_1 = \frac{\pi}{4}, q_2 = \frac{\pi}{2}$$

$$\dot{q}_1 = 1, \dot{q}_2 = 0$$

Example: 2-R Planar Manipulator



$$\begin{aligned}\dot{p} &= \begin{bmatrix} \dot{x} \\ \dot{y} \end{bmatrix} \\ &= J\dot{q} \\ &= \begin{bmatrix} -\sqrt{2} & -\frac{1}{\sqrt{2}} \\ 0 & -\frac{1}{\sqrt{2}} \end{bmatrix} \begin{bmatrix} 1 \\ 0 \end{bmatrix}\end{aligned}$$

$$\begin{bmatrix} -\sqrt{2} & -1/\sqrt{2} \\ 0 & -1/\sqrt{2} \end{bmatrix} = [1;0]$$

Kinematic Singularities

- What are Kinematic Singularities? How can we identify them? What is their effect?

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 - The Jacobian drops rank, mobility of the structure is reduced, small velocities of the end-effector may result in large joint velocities

IK Computation as Optimization Problem

- General Formulation of IK problem of a planar robot with n joints, each with lower and upper limits \bar{l}_i, u_i

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Add obstacle collision constraints!

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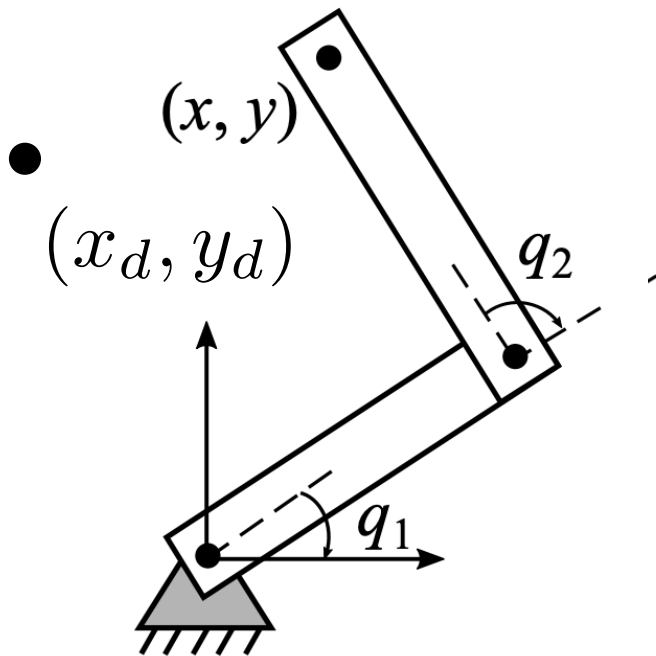
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- Does the starting solution matter?

Inverse Kinematics as Constrained Optimization Problem

$$F = \frac{1}{2} \Delta q^T \Delta q$$

$$\text{s.t: } \Delta p = J \Delta q$$



How to **solve** this optimization problem?

Inverse Kinematics as Constrained Optimization Problem

$$\Delta q = \underbrace{J^T (J J^T)^{-1}}_{J^\#} \Delta p$$

Jacobian Pseudoinverse

Gradient descent:

$$q_{t+1} = q_t + \alpha J^\# \Delta p$$

$$q_{\{t+1\}} = q_{_t} + \alpha J^\# \text{Deltap}$$

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Gradient descent:

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What is the effect of the step size α ?

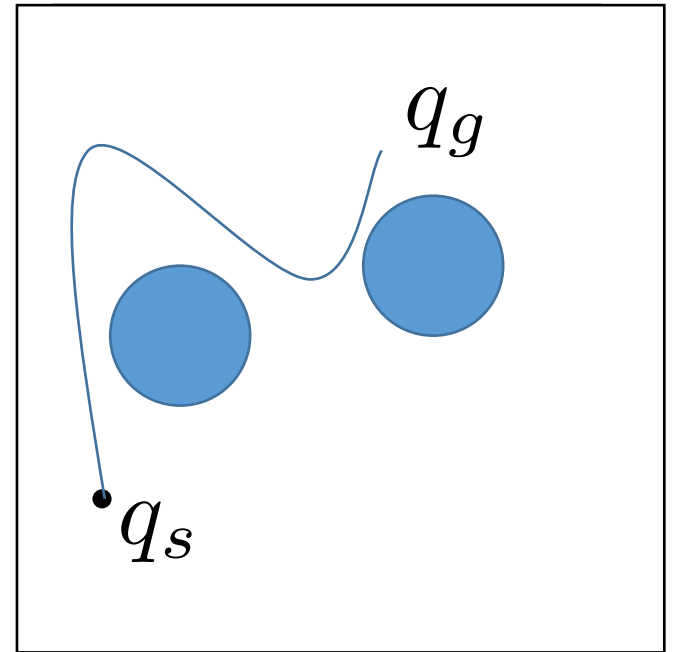
Motion Planning

- Formulate the motion planning problem:

Motion Planning

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1. A world W in \mathbb{R}^2 or \mathbb{R}^3
2. An obstacle region O in W
3. A robot A and its configuration space Q
4. $Q_{free} = Q \setminus Q_{obs}$
5. $q_s \in Q_{free}$: Initial Configuration
6. $q_g \in Q_{free}$: Goal Configuration
7. Compute a path $\tau : [0, 1] \rightarrow Q_{free}$ so that $q_s = \tau(0)$, $q_g = \tau(1)$



Single / Multi Query Algorithms

- What are single / multi-query algorithms?
- What are their advantages / disadvantages?

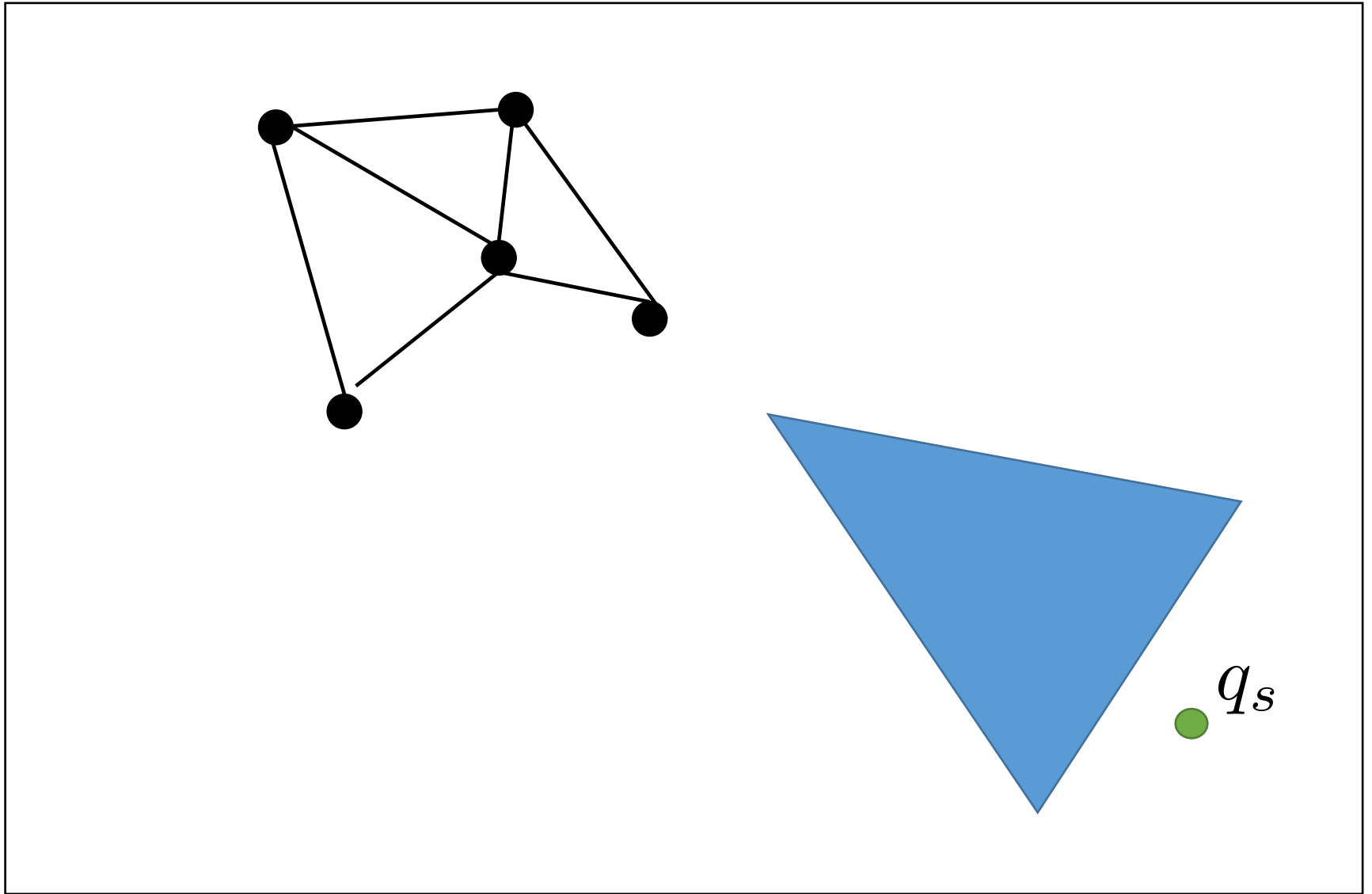
Single/Multi Query Algorithms

- Multi-Query Planning Algorithms
 - Cache roadmap for multiple queries
 - Environment is static
- Single-Query Planning Algorithms
 - Recompute roadmap for each query
 - Environment can change across queries (not within)

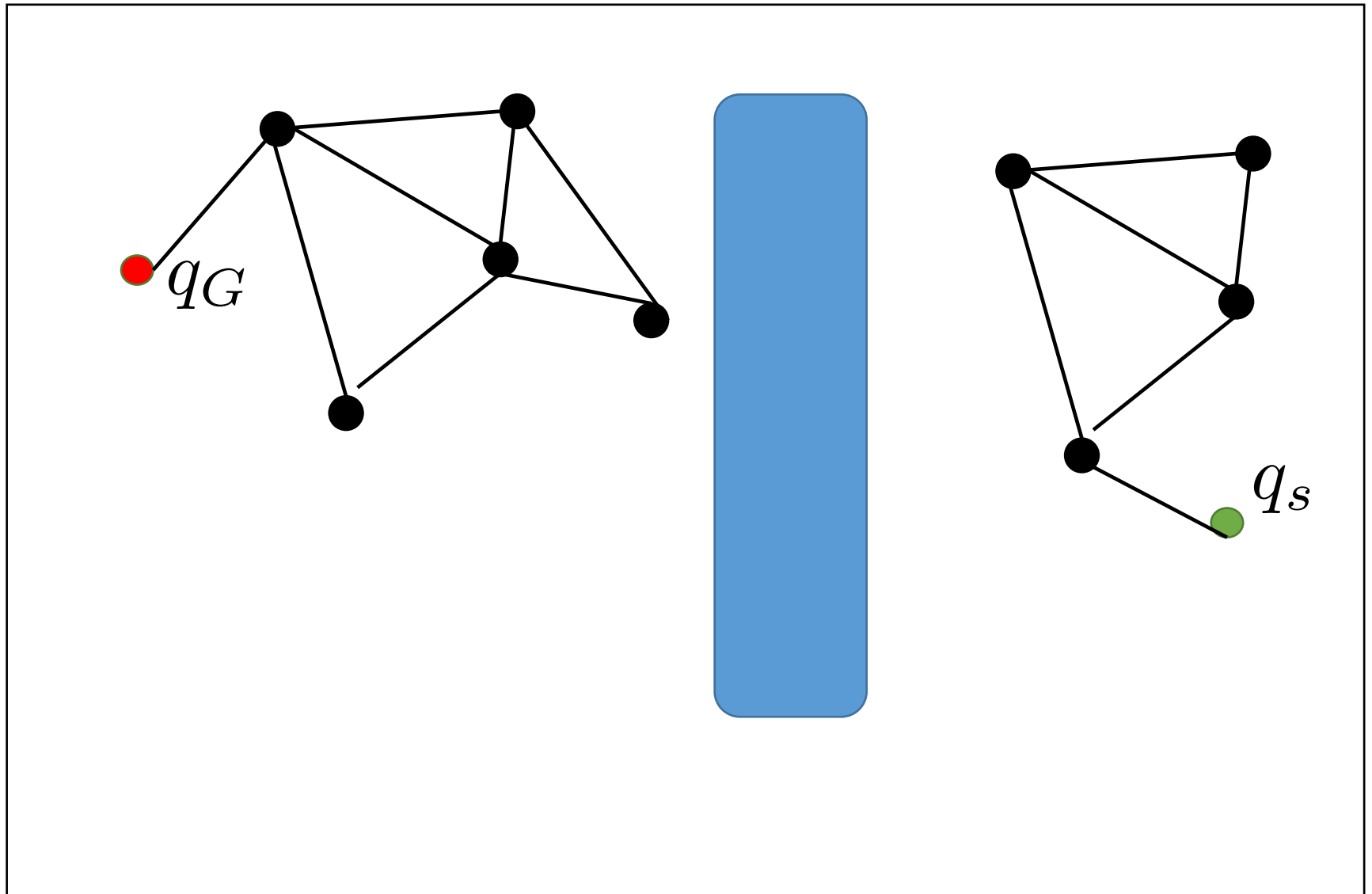
Probabilistic Roadmaps

- What are common reasons of failure of the PRM algorithms?

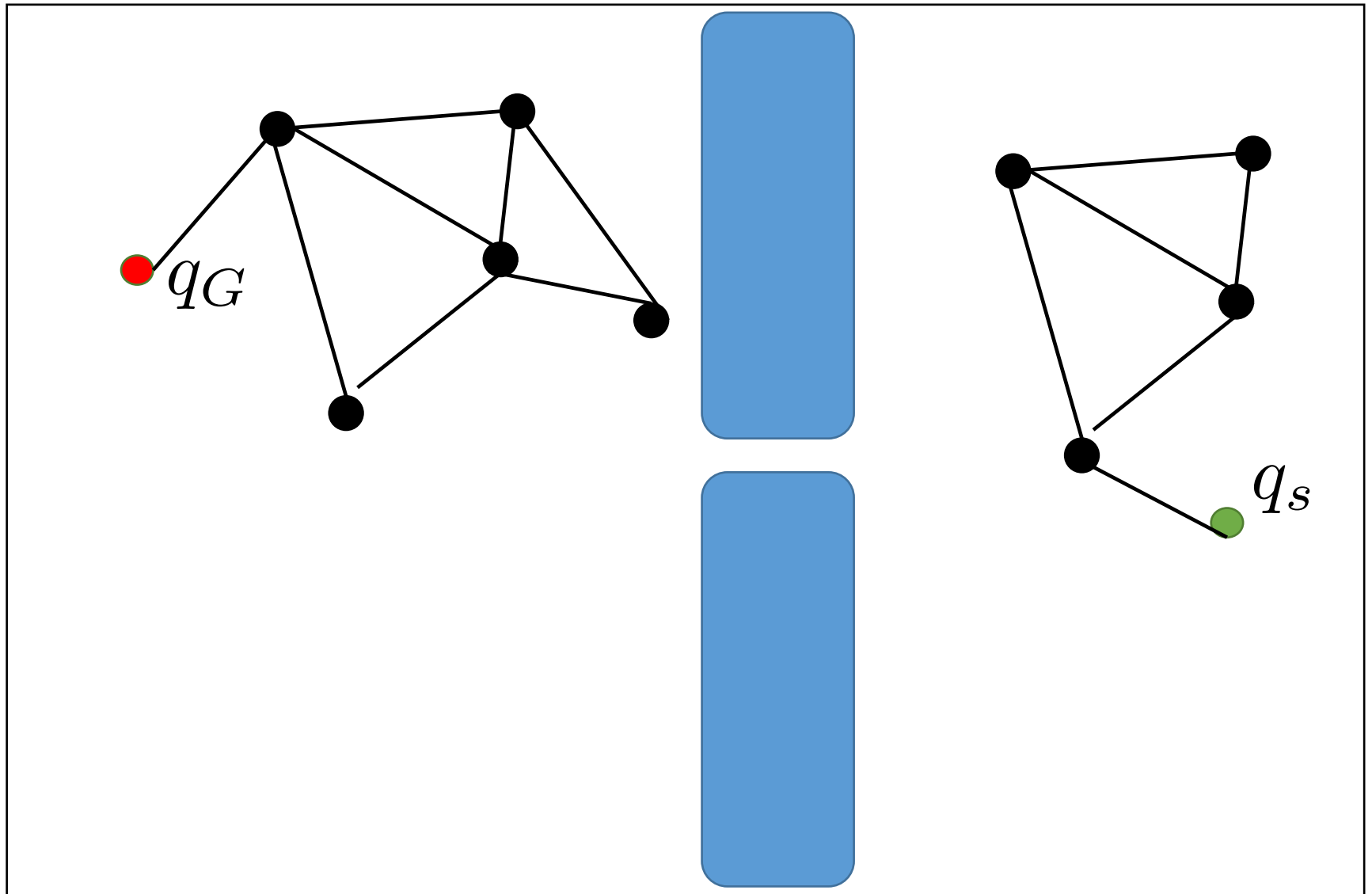
Limitations: Coverage



Limitations: Connectivity



Example: Narrow Passage Problem



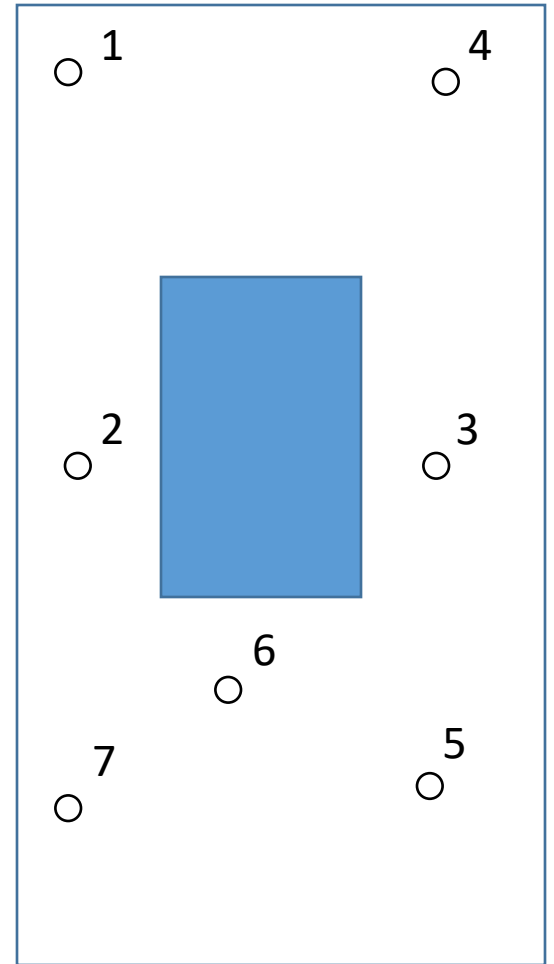
Narrow Passage Problem

- What are solutions for the narrow passage problem?

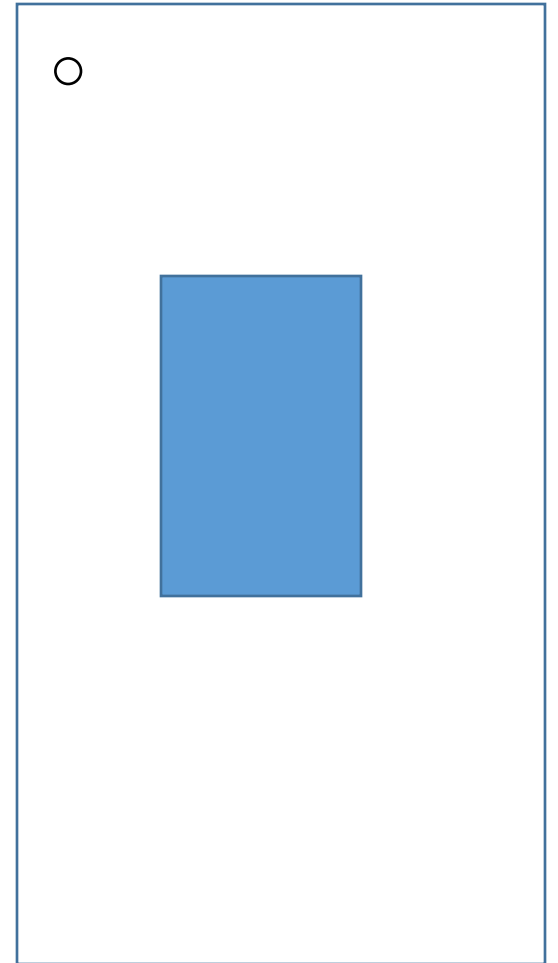
Narrow Passage Problem

- What are solutions for the narrow passage problem?
 - Sample near obstacles
 - Visibility-based PRM

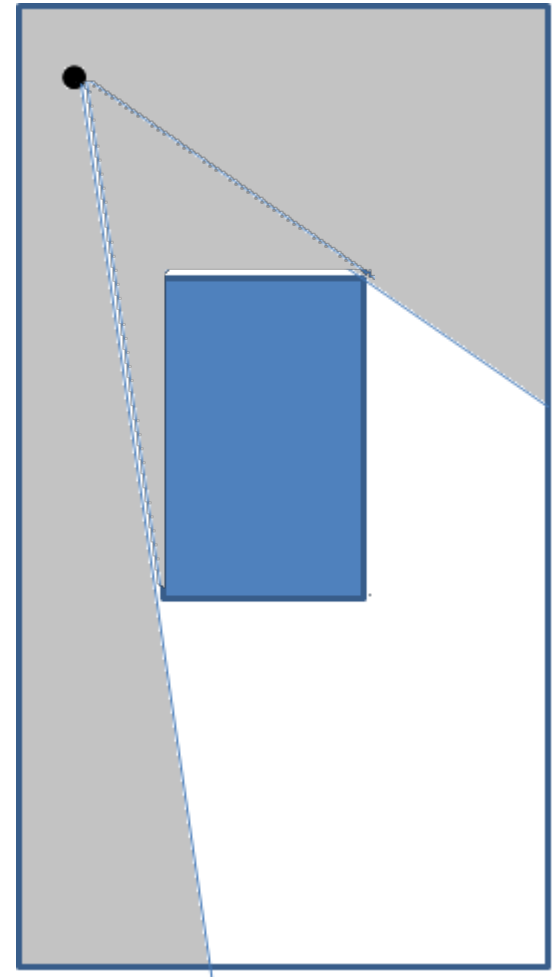
Visibility-Based PRM



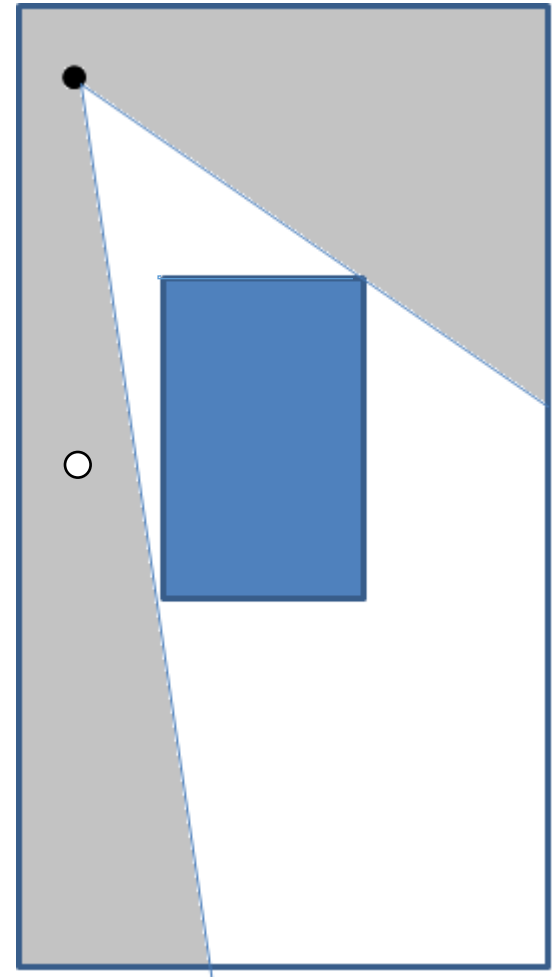
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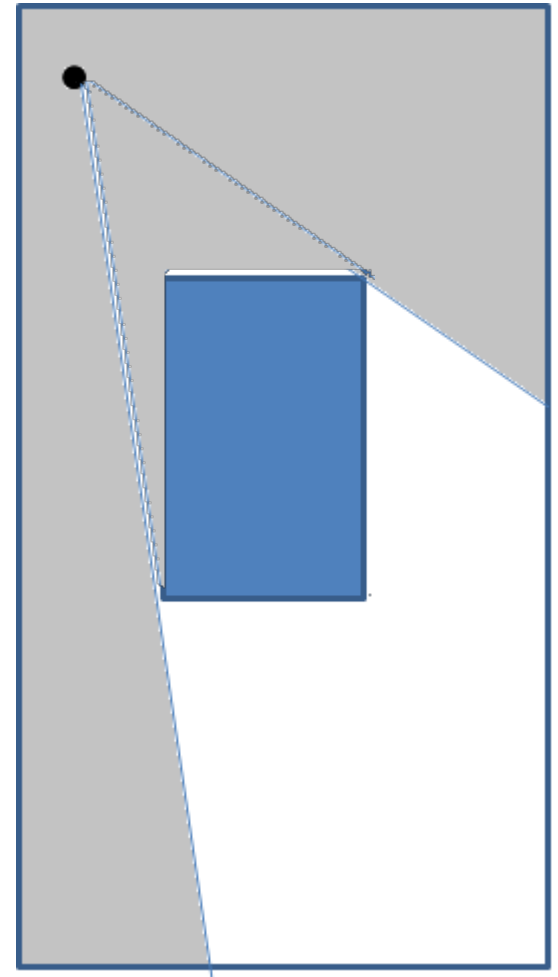
Visibility-Based PRM



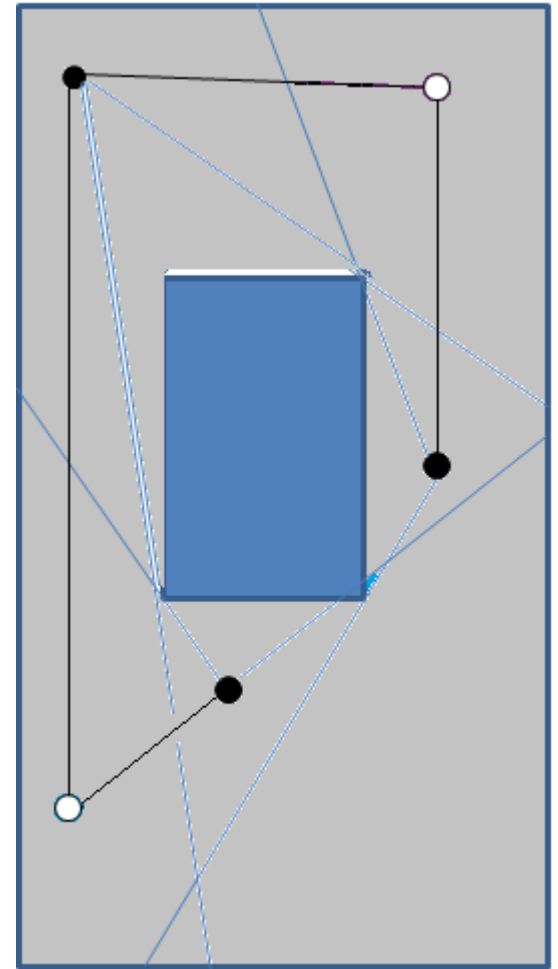
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Visibility-Based PRM



RRTs

- What is the definition of probabilistic completeness?

Probabilistic Completeness

- An algorithm ALG is probabilistically complete if, for any robustly feasible motion planning problem defined by

$$P = (Q_{free}, q_s, q_g)$$

$$\lim_{N \rightarrow \infty} P(ALG \text{ returns a solution to } P) = 1$$

$$\lim (N \rightarrow \text{infty}) P(ALG \text{ returns a solution to } P) = 1$$

RRTs

- What is the definition of probabilistic completeness?
- Is RRT a probabilistically complete algorithm?

RRTs

- What is the definition of probabilistic completeness?
- Is RRT a probabilistically complete algorithm?
- Is the path returned by RRT asymptotically optimal?

RRTs

- One approach that may improve the performance of the RRT algorithm is to sample randomly at the goal and attempt to connect directly to the goal
 - When can this succeed / fail?

RRTs

- Name 3 factors that affect the performance of RRT algorithm
 - Bounds of configuration space
 - Dimensionality of configuration space
 - Obstacles

RRTs

- How can you make the trajectory of an RRT less jerky?

RRTs

- How can you make the trajectory of an RRT less jerky?
 - Shortcutting

Shortcutting

- Output of RRTs is almost unusable.
- Simple Shortcutting Algorithm:
 - Repeat:
 - Select two points randomly
 - Attempt to connect them
 - If path shortest than previous one, replace path

Task Space Regions

- When planning in Task space regions, how would you project samples to the constraint manifold? Write the algorithm in pseudocode

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Algorithm 1: J^+ Projection(q)

```
1 while true do  
2    $\Delta \mathbf{x} \leftarrow \text{DisplacementFromTSR}(q)$ ;  
3   if  $\|\Delta \mathbf{x}\| < \epsilon$  then  
4     return  $q$ ;  
5   end  
6    $\mathbf{J} \leftarrow \text{GetJacobian}(q)$ ;  
7    $\Delta q_{error} \leftarrow \mathbf{J}^T (\mathbf{J}\mathbf{J}^T)^{-1} \Delta \mathbf{x}$ ;  
8    $q \leftarrow (q - \Delta q_{error})$ ;  
9 end
```

Task Space Regions

- When planning in Task space regions, how would you project samples to the constraint manifold? Write the algorithm in pseudocode

1. while true do:
2. $\Delta x \leftarrow \text{DisplacementfromTSR}(q)$
3. if $\|\Delta x\| < \epsilon$ then:
4. return q ;
5. end
6. $J \leftarrow \text{GetJacobian}(q)$;
7. $\Delta q_{\text{error}} \leftarrow J^T (JJ^T)^{-1} \Delta x$
8. $q \leftarrow (q - \Delta q_{\text{error}}$
9. end

Task Space Regions

- Specify the matrix of bounds B^w for a cup

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- Specify the matrix of bounds B^w for a cup



$$B^w = \begin{bmatrix} 0 & 0 \\ 0 & 0 \\ -\alpha & \alpha \\ 0 & 0 \\ 0 & 0 \\ -\pi & \pi \end{bmatrix}$$

$$B = [0,0;0,0;0,0;-a,a;0,0;0,0;-pi,pi]$$

Task Space Regions

- Specify the matrix of bounds B^w for a cup, so that only poses on one side of the cup (e.g., facing the robot) are sampled



Task Space Regions

- Specify the matrix of bounds B^w for a cup, so that only poses on a semicircle around the cup (e.g., facing the robot) are sampled



$$B^w = \begin{bmatrix} 0 & 0 \\ 0 & 0 \\ -\alpha & \alpha \\ 0 & 0 \\ 0 & 0 \\ -\pi/2 & \pi/2 \end{bmatrix}$$

Task Space Regions

- Specify the matrix of bounds B^w for a cup, so that only one **unique** pose is sampled



Task Space Regions

- Specify the matrix of bounds B^w for a cup, so that only one **unique** pose is sampled



$$B^w = \begin{bmatrix} 0 & 0 \\ 0 & 0 \\ \alpha & \alpha \\ 0 & 0 \\ 0 & 0 \\ \beta & \beta \end{bmatrix}$$

Dynamics

- What is the physical meaning behind each term in the dynamics equation?

$$B(q)\ddot{q} + C(q, \dot{q})\dot{q} + G(q) = \tau$$

Dynamics

- What is the forward dynamics problem? Why is it useful?
- What is the inverse dynamics problem?

Forward Dynamics

$$B(q)\ddot{q} + C(q, \dot{q})\dot{q} + G(q) = \tau$$

We can determine \ddot{q} given τ

$$\ddot{q} = B(q)^{-1} (\tau - C(q, \dot{q})\dot{q} - G(q))$$

$$\begin{aligned} \ddot{q} &= B(q)^{-1} (\tau - C(q, \dot{q})\dot{q} \\ &\quad - G(q)) \end{aligned}$$

Inverse Dynamics

$$B(q)\ddot{q} + C(q, \dot{q})\dot{q} + G(q) = \tau$$

Given. \ddot{q} , \dot{q} , q compute the torques.

Control

What is decentralized control? When can it fail?

- Independent PD control for each joint, fails when we have significant coupling terms

Control

Will PD control work well for moving a robotic manipulator to a desired position with gravity? Propose two solutions

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Will PD control work well for moving a robotic manipulator to a desired position with gravity? Propose two solutions

- PID
- PD with Gravity Compensation (feedback linearization)

Control

Is the system stable when we apply PD with Gravity Compensation? Justify your answer

Upcoming at Spring 2021

CSCI 699: Computational Human-Robot Interaction