

Eurathlon 2013

Scenario Application Paper (SAP) – Review Sheet

Team/Robot Space Applications

Scenario Reconnaissance and surveillance in urban structures (USAR)

For each of the following aspects, especially concerning the team's approach to scenario-specific challenges, please give a short comment whether they are covered adequately in the SAP.

Keep in mind that this evaluation, albeit anonymized, will be published online; private comments to the organizers should be sent separately.

Robot Hardware

The vehicle is a clearpath robotics vehicle with a Husky 6DOF arm. It is being developed as part of a number of FP7 projects. The vehicle integrates state of the art sensing and processing techniques such as SLAM and autonomous manipulation. The platform is a 4 wheel drive vehicle of around 50Kg that can climb steep slopes up to 45%.

Processing

Mini ITX PC that will be upgraded to an I7 for the competition.

Communication

2.4Ghz wireless Lan. The vehicle is designed to be autonomous but control can be taken through LAN. Effective range of 280m but not qualified against harder conditions.

Localization

Based on IMU and GPS and odometry. Ability to build a map and use it for navigation using open source SLAM solution such as Gmapping. 3D maps building available using laser and stereo vision.

Sensing

Laser, Cameras, LIDAR, GPS, IMU. The team also demonstrated they know what to do with the sensors. Integration does not seem to be completed yet.

Vehicle Control

Fully autonomous based on sensors and autonomous map building. very ambitious in its aims. The team however recognises that manual control might be necessary in some instances.

System Readiness

System designed as part of a number of EU projects. Integration status is a question mark. I would say around TRL4/5 based on the document received.

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Overall Adequacy to Scenario-Specific Challenges

The vehicle is ideal for the scenario and the team ambitious in their endeavour. It will enable the competition to benchmark state of the art (or close to it) autonomous solutions for navigation, map-building and manipulation. This team should definitely be allowed to compete. No H&S issues.



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1.1 History

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1.2 General Approach

The approach adopted by the team from Space Applications Services centers around human in the loop control, with shared deliberative (and functional) capabilities between the base station (operator control interface) and the mobile robot platform.

Ideally, the operator uses high level commands such as local exploration or go-to-waypoint(s) to command the robot through a user centric graphical interface. Products of on board perception are sent from the robot to the base station, where more complex processing – such as 6D SLAM resulting in accurate 3D maps - may take place. Such high level commanding with on board autonomy allows the mobile robot to explore regions with intermittent communication while allowing a remote operator to make critical decisions and view the collected data in a timely manner. This approach will be complemented by a nominal approach allowing full tele-operation with minimal (obstacle avoidance) or no on board intelligence.

Two approaches for manipulation will be implemented – autonomous grasping based on detection of the object using vision, and tele-manipulation using a haptic capable interface.

2 Robot Platform

The platform used by the team from Space Applications Services will be the Clearpath Husky A200 (provisionally named 'MILOU'). The Husky is a ruggedized, outdoor robot with significant mobility capabilities in highly unstructured environments resulting from a 4x4 drivetrain, and a high payload capacity.

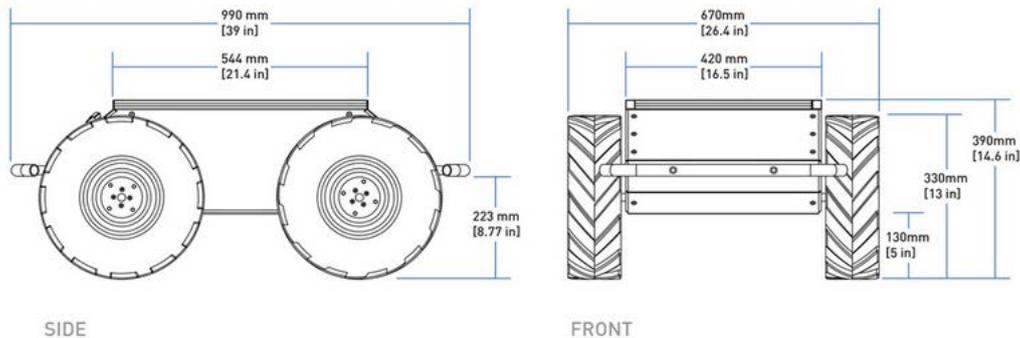


Figure 1. Diagrammatic representation of the Husky A200 [Source: Clearpath Website]

Table 1. Technical Specifications of the Husky A200

Weight & Dimensions	
External Dimensions	0.99 m x 0.67 m x 0.39 m
Weight	49.8 kg (without payload) / ~ 70kg (with payload/sensors)
Ground Clearance	0.13 m
Payload	75 kg (maximum) / 20kg (all terrain)
Performance	
Speed	1 m/s (mximum)
Max. Climb Grade	45 degrees (100% slope)
Max. Traversal Grade	30 degrees (58% slope)
Power Autonomy	8 hrs (basic usage) / ~ 1.5 hrs (driving + payload/sensors)
Operating Temperature	-10 C to 30 C
Environmental Protection	IP 54

The basic Husky platform has been customized to support some of the payloads by the addition of an all-weather plate and a mast. The next subsections will describe some of the payload elements that are expected to be used during the Eurathlon 2013.



2.1 On board Computer

Currently, the on board computer for the mobile robot is a MiniITX PC allowing basic sensor data processing and autonomy on the robot itself. For Eurathlon 2013, we are considering replacing this with a high performance laptop (potentially a Sony Vaio Z series or a Dell Latitude E6530) in an attempt to allow greater processing power and increase the power autonomy. A final decision will be made based on the final on board processing load and the possibility of interfacing with various sensors and actuators.

2.2 Manipulator

The Husky payloads will include the 6 DOF ARM2.0 from Invenscience LC with a two finger (pincer) gripper. Technical specifications can be seen in Table 2. While this will primarily be used for the manipulation challenge, the possibility to use a wrist mounted camera to look over large obstacles is being considered.

Table 2. Technical Specifications of the manipulator

Weight	10.6 kg
Reach	2.74m diameter
Lift	5 – 18 kg
Environmental Protection	IP 63



Figure 2. Invenscience ARM 2.0

2.3 Pan Tilt Actuator

An actuated pan-tilt mechanism will be used with the SICK LMS151 and / or the BumbleBee XB3 (see Section 2.4 for sensor details) mounted. The purpose will be to retrieve 3D point clouds of the environment and look in detail at specific regions (operator controlled) for advanced perception and tele-manipulation.

2.4 Sensors

The possible sensor payload for the robot includes:

- PointGrey BumbleBee XB3 (Stereo Camera): used for 3D perception
- SICK LMS151 Laser Range Finder: used for 2D/3D perception
- XSens MTi: Inertial Measurement Unit
- Hokuyo URG-04LX Laser: used for obstacle avoidance
- Septentrio AsteRx2i HDC: used in outdoor environments for localization, with RTK if available
- Logitech Webcam(s): Additional cameras for perception and tele-manipulation

Additionally, if available on loan the Dräger X-am 7000 chemical sensor will be included to identify points of interest.

3 Base Station

The base station (robot command and control center) is a centralized system that provides a visualization of the scenario and incoming sensor data and robot status, and allows management of operations through online configuration of robot autonomy. It hosts maps with different layers of the area, allows for automated and manual planning of missions, high level and teleoperated control of robots, acquisition and fusion of sensor data from robots. This center comprises of a rugged laptop, mouse, joystick and haptic capable interface.



3.1 Novint Falcon

The base station will include a Novint Falcon haptic feedback interface. This device will be used to provide the operator with 3DOF control of the end effector position.

4 Communication

Communication between the base station and robot platform will be based on the use of the Ubiquiti UniFi Outdoor Access Point operating in the 2.4GHz that is compliant with the applicable provisions of Directive 199/5/EC. It implements a 2x MIMO system, allowing the use of 40MHz bandwidth for higher data rates, and has an effective range of ~180m.

Two network architectures are under consideration: the first with the access point at the base station, and the second where the access point is deployed in the field by the robot platform (e.g. at the entrance) increasing the effective communication range.

On loss of communication, on board autonomy will allow the rover to immediately backtrack its path to recover communication, or achieve local goals before returning to communication range.

5 Perception & System Autonomy

5.1 Localization & Mapping

Primary means of acquiring localization information will be the GPS device (for outdoor usage), the XSens MTi IMU and wheel odometry, which will be fused to give a single pose estimate using an Extended Kalman Filter.

On board localization and mapping will focus on the utilization of the open source GMapping library to perform 2D SLAM. For this purpose, EKF outputs will be used as a priori pose estimates, and roll/pitch corrected laser scans (laser scans projected into the horizontal frame). This approach has been previously demonstrated by the robotics group at Jacobs University Bremen during the RoboCup Rescue Virtual League.

This will be complemented by the creation of local elevation maps from 3D data for local navigation.

Corrected pose from the 2D SLAM will be used to generate 3D maps. The 3D scans and 6DOF pose estimates will be transmitted to the base station where a 3D map will be built in an off line manner for use by the operator.

5.2 Navigation

Navigation is considered as two separate platforms – global navigation and local navigation.

Global navigation is addressed on the base station, where potential routes to a distant target location (potentially set by the operator) are broken down as a traverse graph – a directed graph with potential straight line paths between vertices. Nominally, this will be done by the operator though it might be done in an automated manner if sufficient implementation time is available.

Local navigation represents motion to the next waypoint using the local elevation map. A path to the local goal is planned using D^* , with trajectory fitting used to generate drive commands.

5.3 Exploration

Apart from operator generated goals, frontier exploration based on the 2D map will be used for exploration of unknown environments.

6 Scenario Specific Challenges

Reconnaissance and surveillance in urban environments adds a number of specific challenges for a robotic system. Some of these are identified and addressed here.

Navigation in unstructured urban environments: While some urban structures such as steep ramps or stairs would pose a locomotion problem to the Husky, it is capable of crossing uneven terrain such as rubble piles and potentially some concave obstacles. Autonomy is based on path planning from elevation maps, allowing the inclusion of 3D information into the process.

Localization without GPS: While a high accuracy GPS system is included in the system payload, the robot localization is based on fusion with odometry estimates (wheel, inertial and potentially visual) and SLAM.

Mapping on non-level ground: The approach to SLAM, based on reprojection of laser scans, has been shown to be effective in uneven terrain in the Robocup Rescue competitions.

Dynamic environments: While no explicit care has been taken to deal with dynamic environments, the underlying mapping is based on bayesian updates of occupancy probability allowing a dynamic obstacle to disappear and reappear given sufficient evidence. Navigation, as far as possible, will be based on elevation maps constructed from the latest data with teleoperation as a backup.

Communication loss: Communication loss will be nominally addressed by onboard autonomy allowing the robot to return to the last location it had communication. Additionally, methods to allow the robot to autonomously execute local exploration in the absence of communication (with reporting of sensor data once communication is restored) is being investigated.

7 System Readiness

Most of the hardware and software elements that comprise the proposed system are being developed and validated in ongoing FP7 projects, and have a basis in widely known technologies and concepts that have been previously validated. While some of the advanced perception and autonomy aspects might not perform as expected during the competition, a back-up operation schema of full teleoperation supported by onboard autonomy for communication recovery will always be available.



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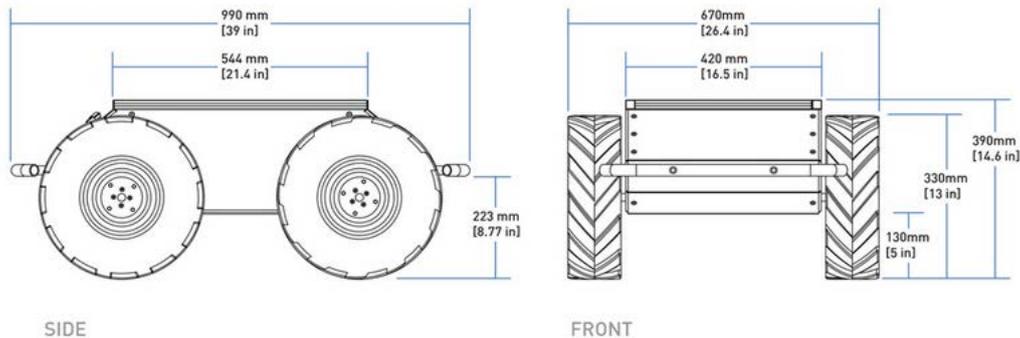


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Eurathlon 2013 Scenario Application Paper – Reconnaissance and surveillance

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