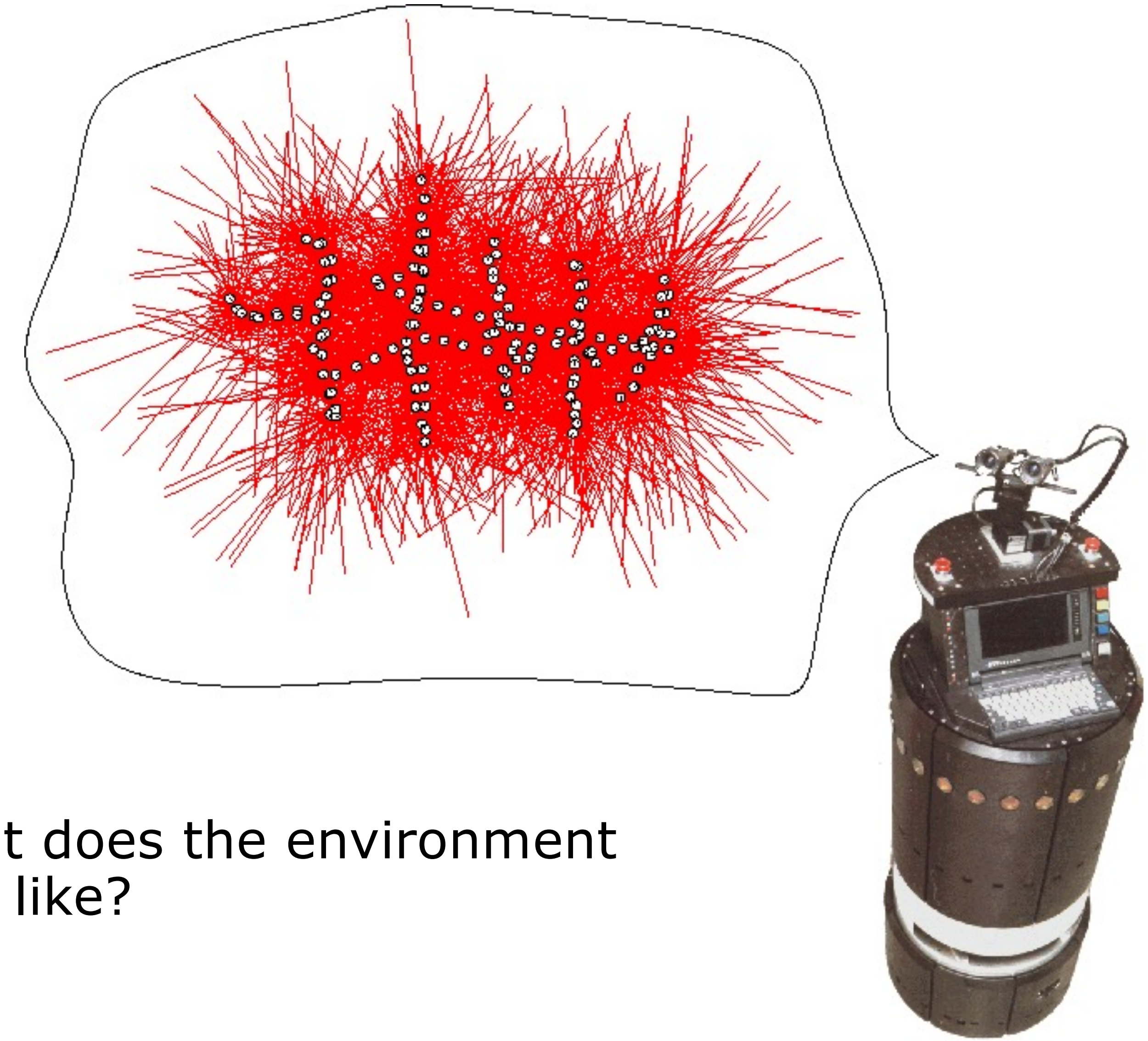
Introduction to Mobile Robotics

Mapping with Known Poses

Why Mapping?

- Learning maps is one of the fundamental problems in mobile robotics
- Maps allow robots to efficiently carry out their tasks, allow localization …
- Successful robot systems rely on maps for localization, path planning, activity planning etc.

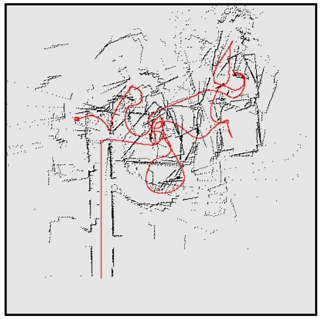
The General Problem of Mapping

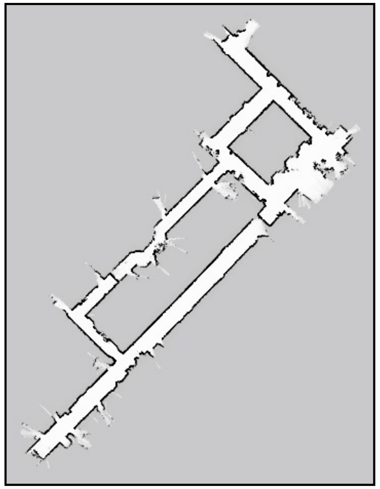


What does the environment look like?

Types of SLAM-Problems

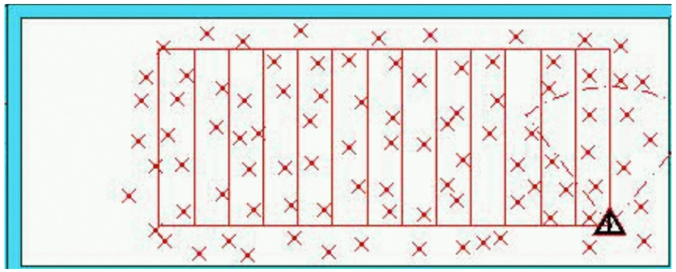
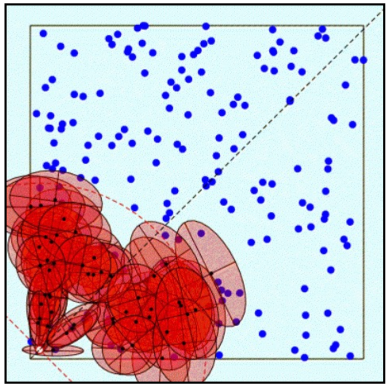
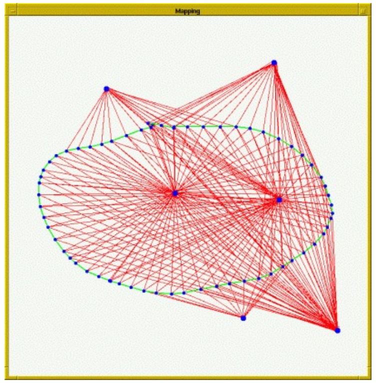
- Grid maps or scans





[Lu & Milios, 97; Gutmann, 98: Thrun 98; Burgard, 99; Konolige & Gutmann, 00; Thrun, 00; Arras, 99; Haehnel, 01;…]

- Landmark-based

[Leonard et al., 98; Castelanos et al., 99: Dissanayake et al., 2001; Montemerlo et al., 2002;…

Problems in Mapping

- Sensor interpretation
  - How do we extract relevant information from raw sensor data?
  - How do we represent and integrate this information over time?

- Robot locations have to be estimated
  - How can we identify that we are at a previously visited place?
  - This problem is the so-called data association problem.

Occupancy Grid Maps

- Introduced by Moravec and Elfes in 1985
- Represent environment by a grid.
- Estimate the probability that a location is occupied by an obstacle.
- Key assumptions
  - Occupancy of individual cells (m[xy]) is independent

$$Bel(m_t) = P(m_t \mid u_1, z_2 \ldots, u_{t-1}, z_t)$$
$$= \prod_{x,y} Bel(m_t^{[xy]})$$

  - Robot positions are known!

Updating Occupancy Grid Maps

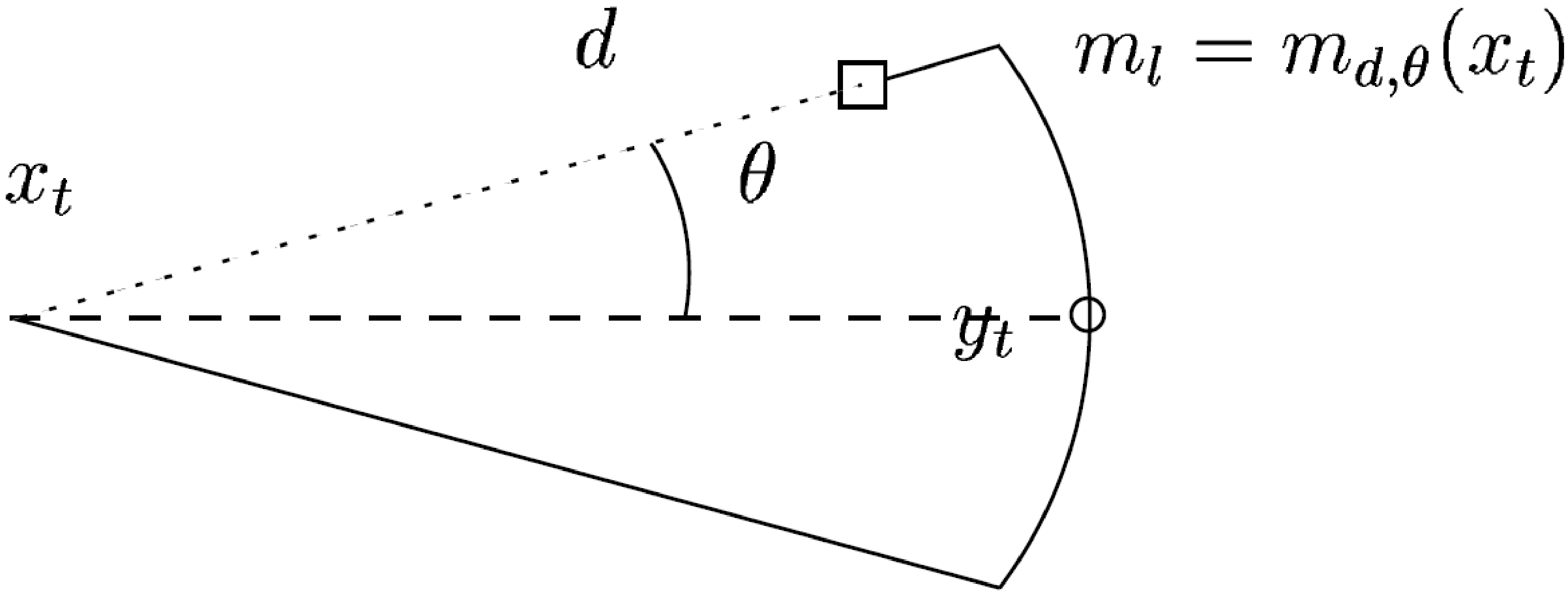
- Idea: Update each individual cell using a binary Bayes filter.

$$Bel(m_t^{[xy]}) = \eta\ p(z_t \mid m_t^{[xy]}) \int p(m_t^{[xy]} \mid m_{t-1}^{[xy]}, u_{t-1}) Bel(m_{t-1}^{[xy]})\, dm_{t-1}^{[xy]}$$

- Additional assumption: Map is static.

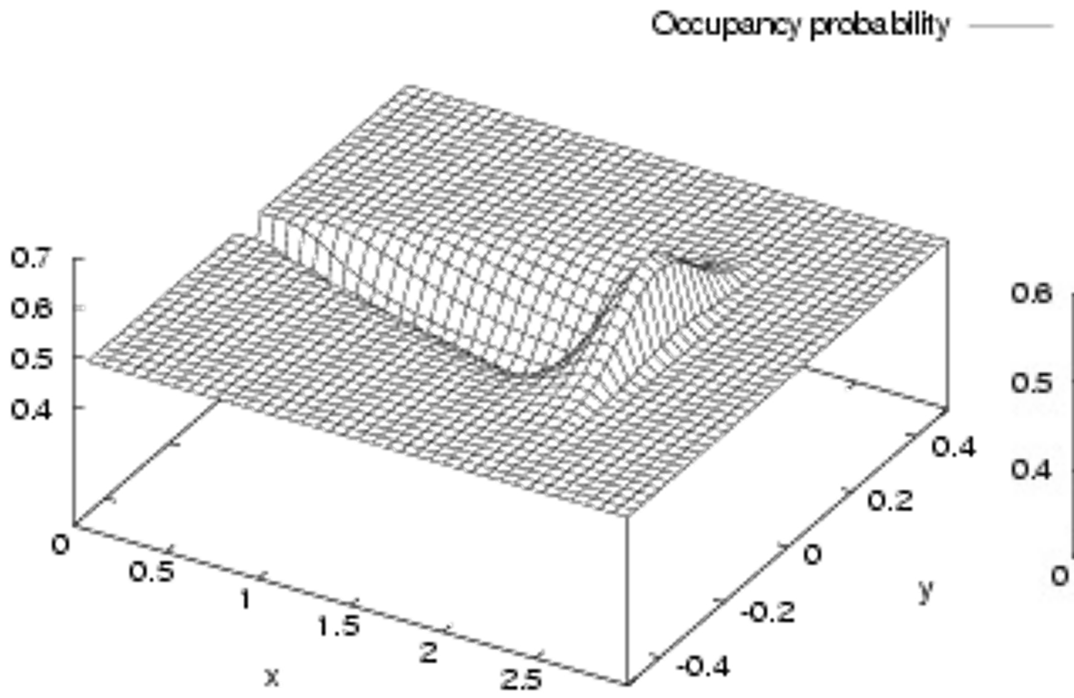
$$Bel(m_t^{[xy]}) = \eta\ p(z_t \mid m_t^{[xy]}) Bel(m_{t-1}^{[xy]})$$

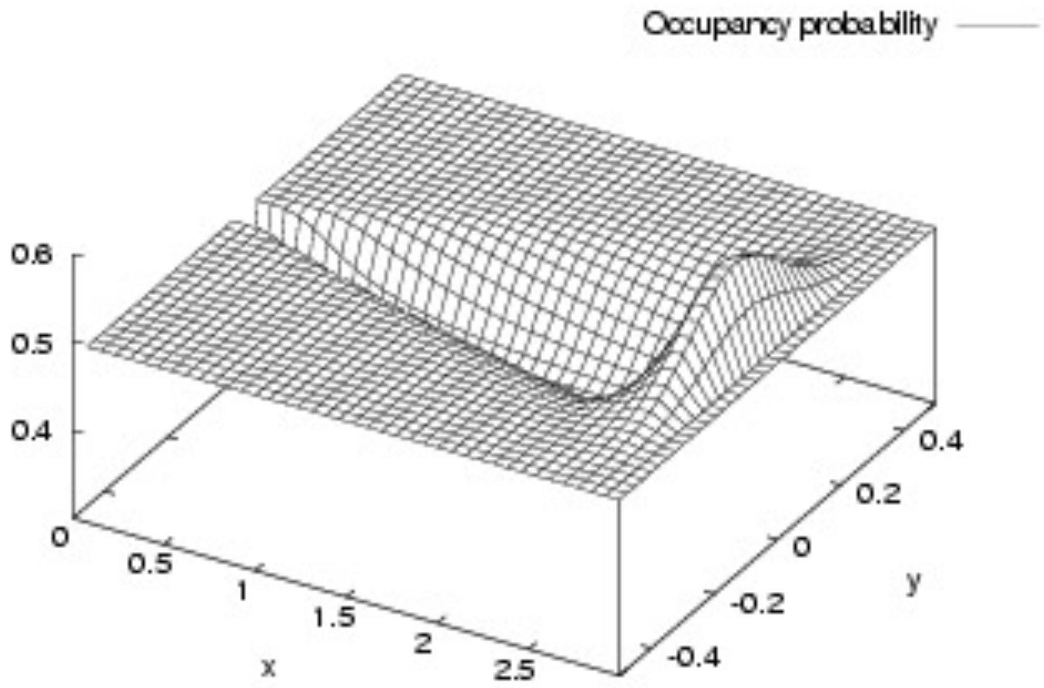
Key Parameters of the Model



Typical Sensor Model for Occupancy Grid Maps

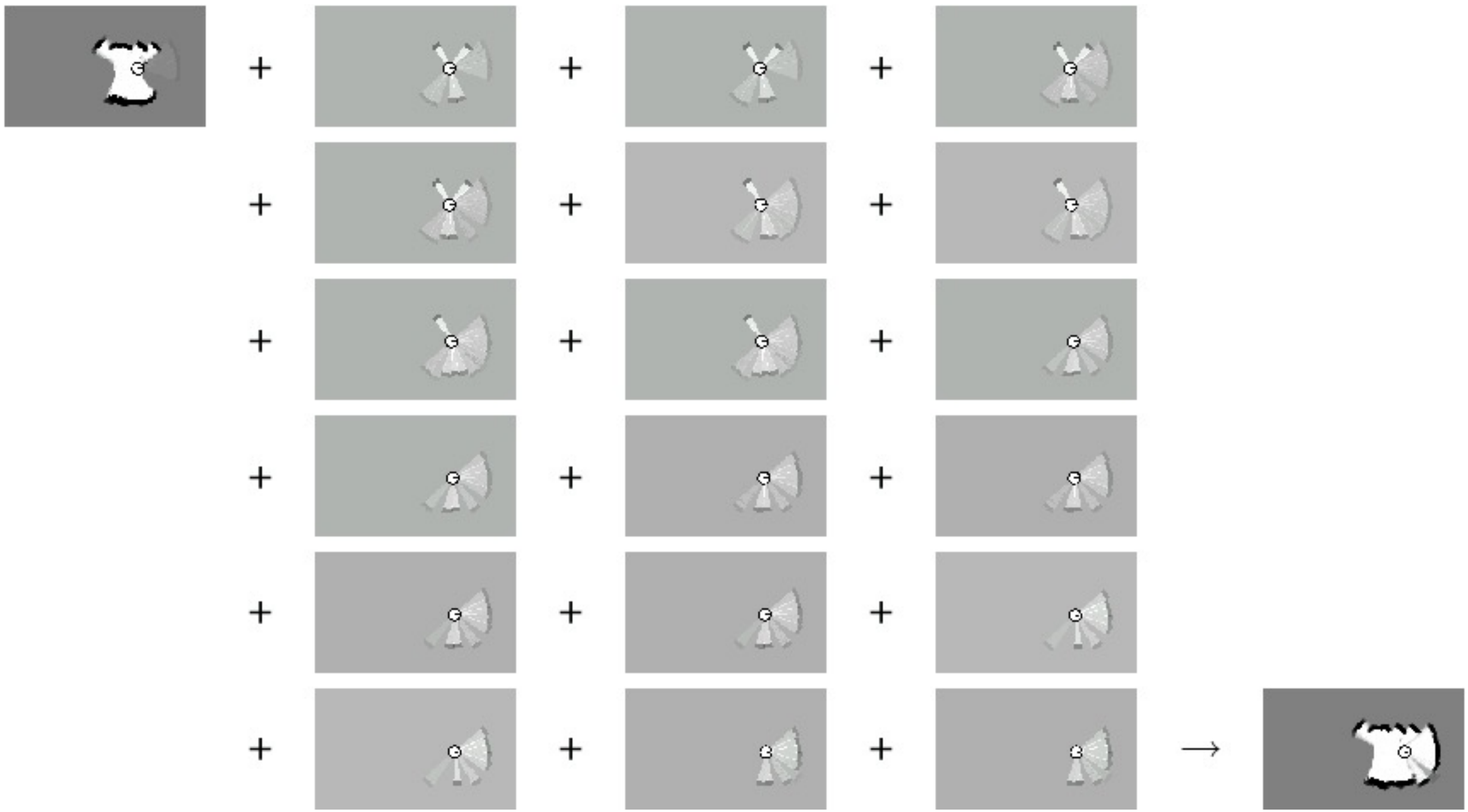
Combination of a linear function and a Gaussian:



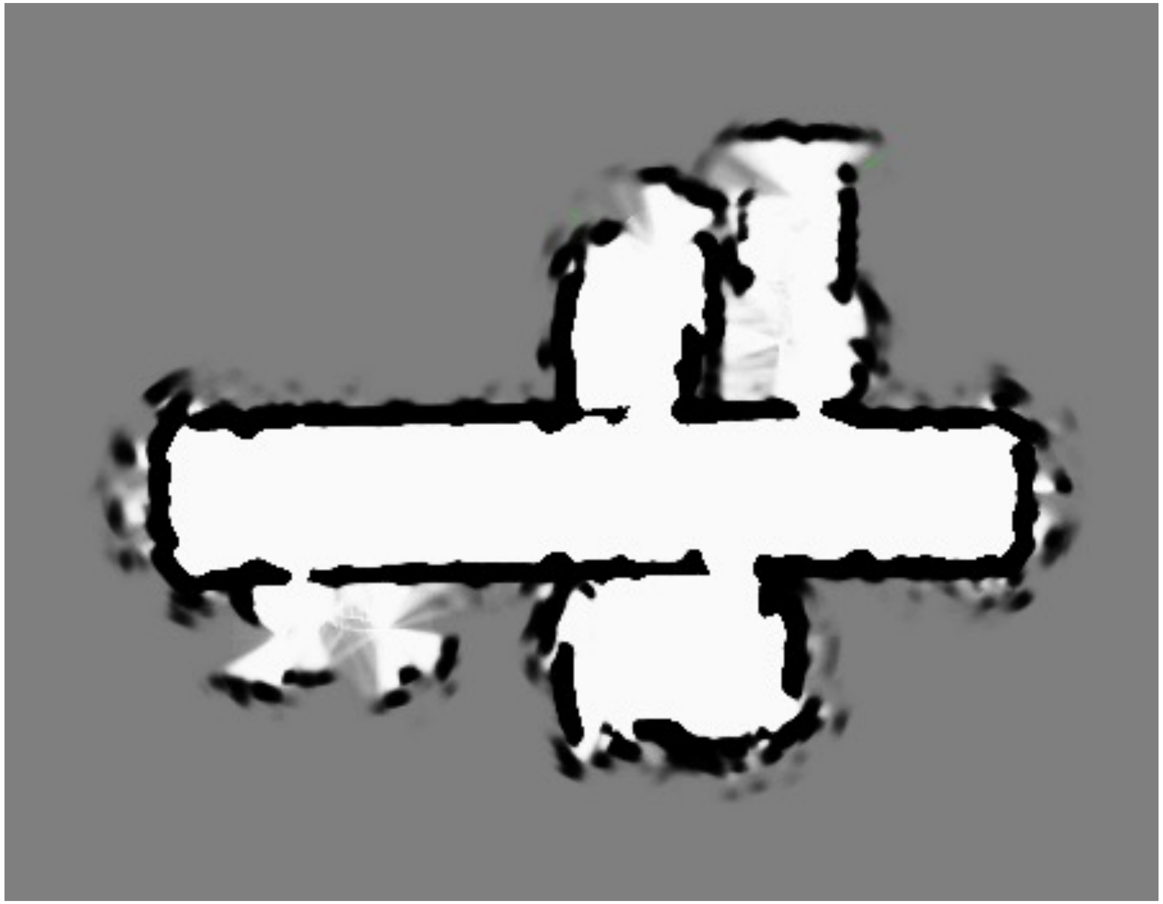


$$\overline{B}\left(m_t^{[xy]}\right) = \log odds\left(m_t^{[xy]} \mid z_t, u_{t-1}\right) - \log odds\left(m_t^{[xy]}\right) + \overline{B}\left(m_{t-1}^{[xy]}\right)$$

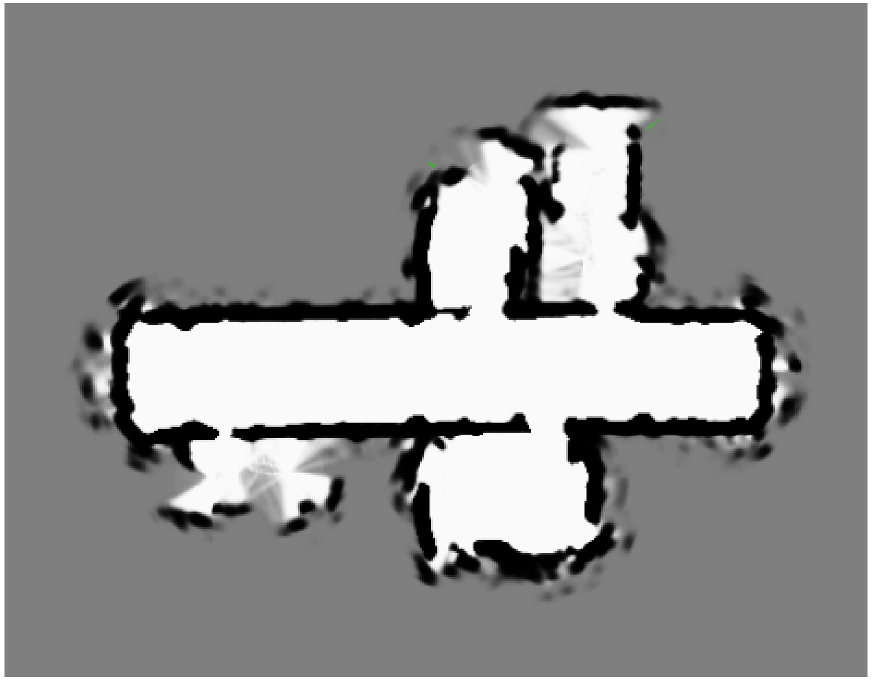
Incremental Updating of Occupancy Grids (Example)

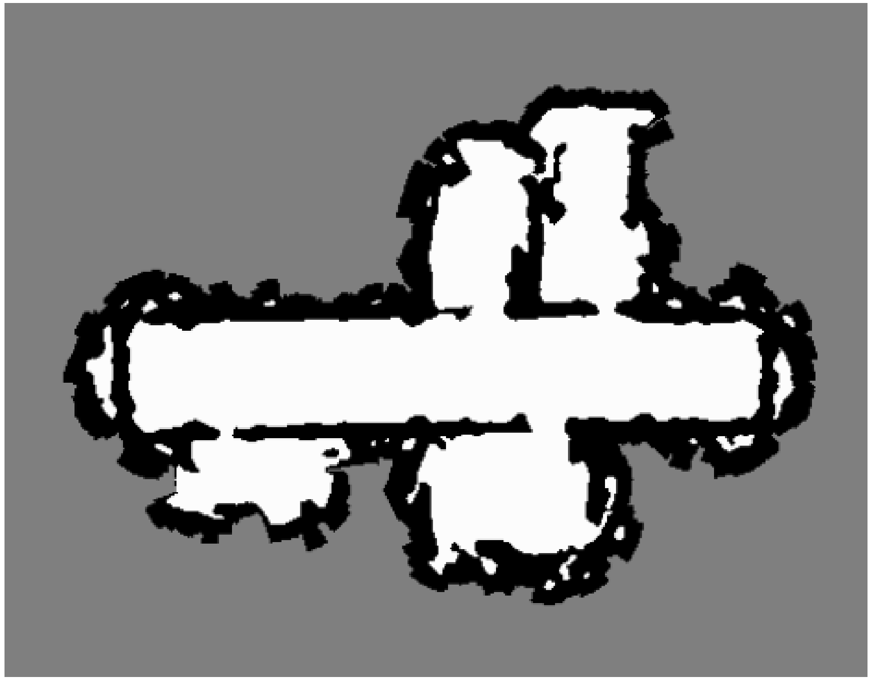


Resulting Map Obtained with Ultrasound Sensors



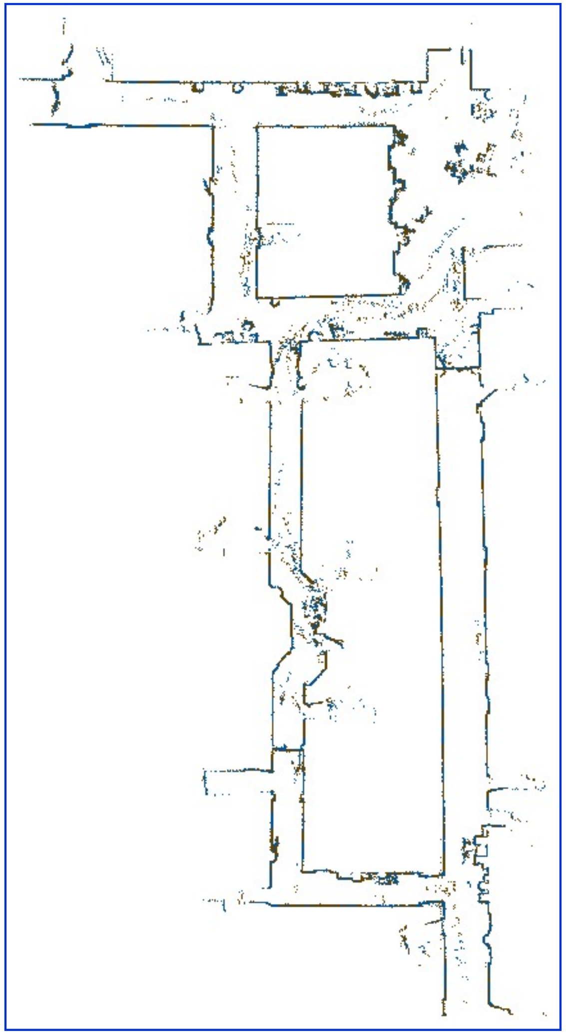
Resulting Occupancy and Maximum Likelihood Map

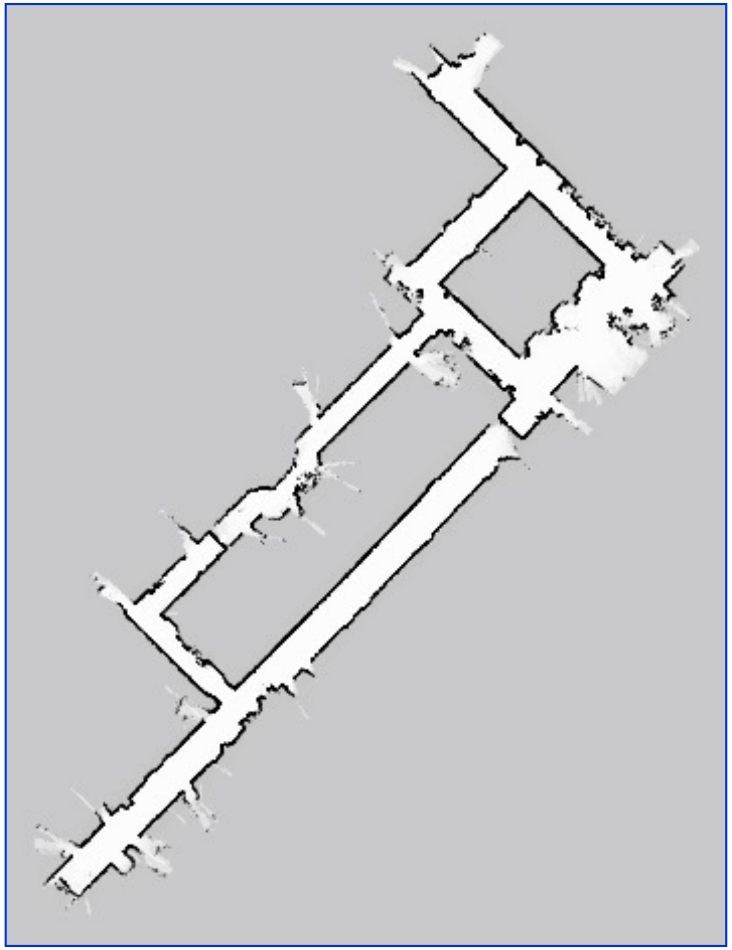




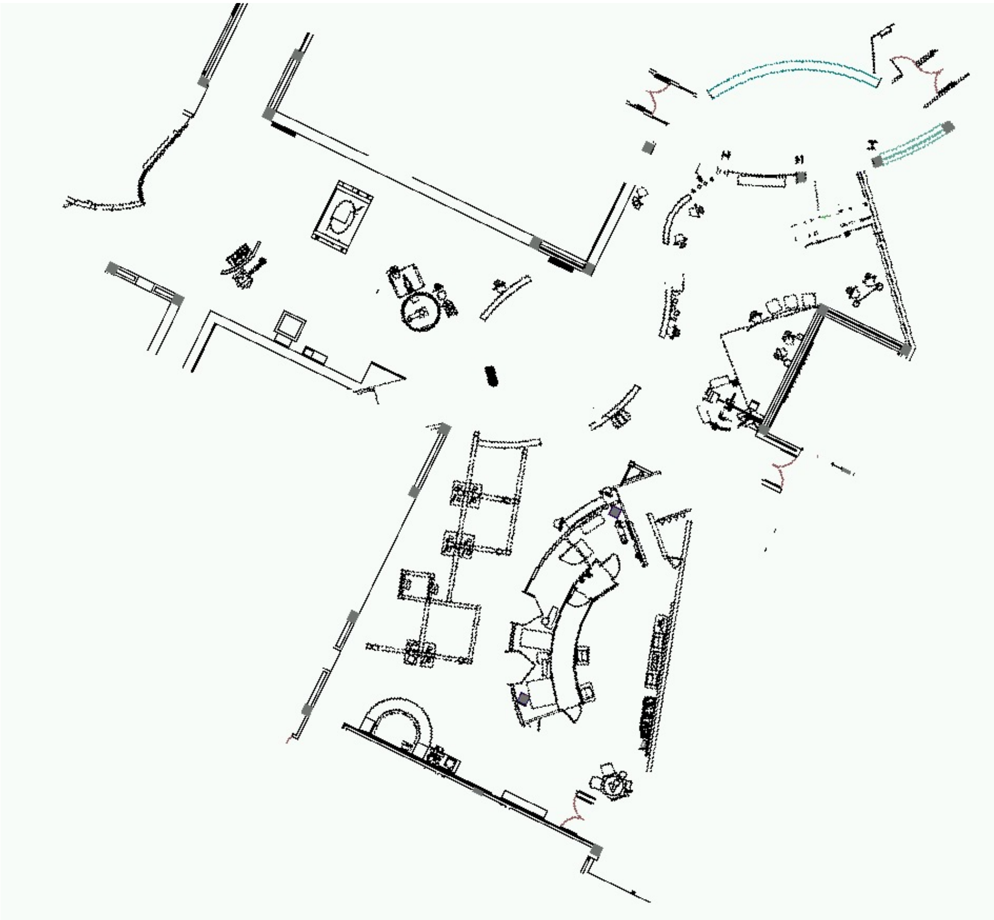
The maximum likelihood map is obtained by clipping the occupancy grid map at a threshold of 0.5

Occupancy Grids: From scans to maps

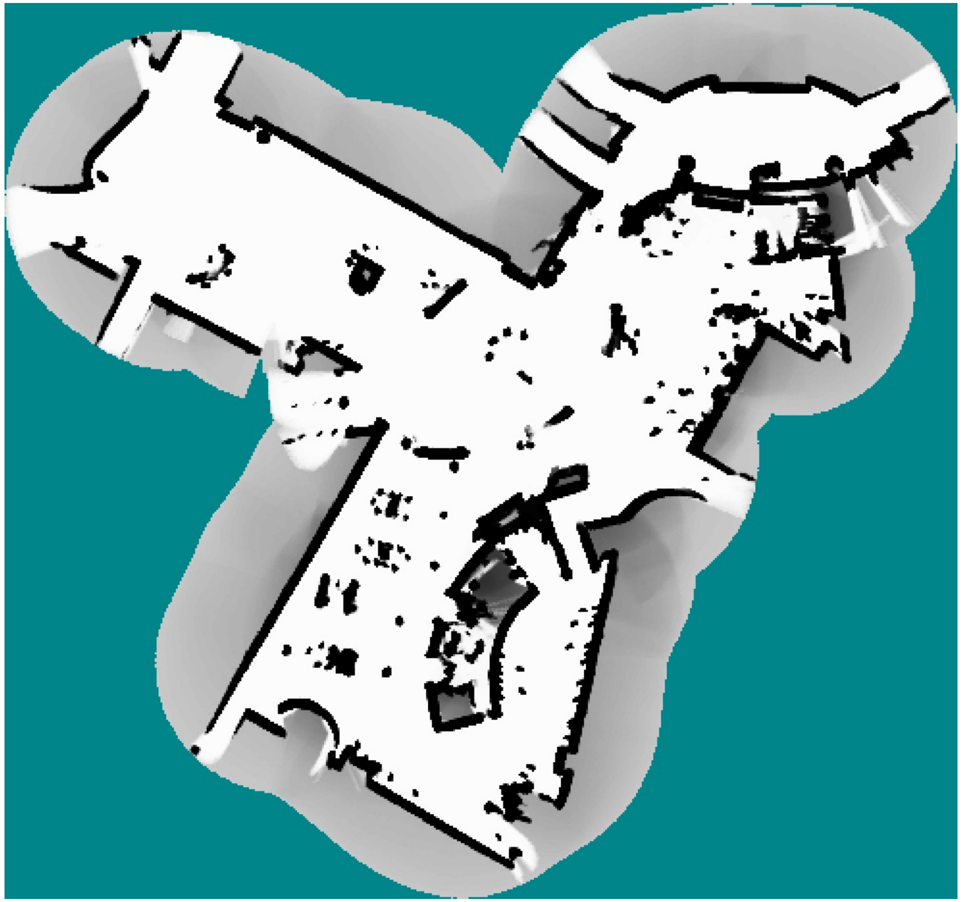




Tech Museum, San Jose



CAD map



occupancy grid map

Alternative: Simple Counting

- For every cell count
  - hits(x,y): number of cases where a beam ended at <x,y>
  - misses(x,y): number of cases where a beam passed through <x,y>

$$Bel(m^{[xy]}) = \frac{\text{hits}(x,y)}{\text{hits}(x,y) + \text{misses}(x,y)}$$

- Value of interest: $P(reflects(x,y))$

Difference between Occupancy Grid Maps and Counting

- The counting model determines how often a cell reflects a beam.
- The occupancy model represents whether or not a cell is occupied by an object.
- Although a cell might be occupied by an object, the reflection probability of this object might be very small.

Example Occupancy Map

Example Reflection Map

Summary

- Occupancy grid maps are a popular approach to represent the environment of a mobile robot given known poses.
- In this approach each cell is considered independently from all others.
- It stores the posterior probability that the corresponding area in the environment is occupied.
- Occupancy grid maps can be learned efficiently using a probabilistic approach.
- Reflection maps are an alternative representation.
- They store in each cell the probability that a beam is reflected by this cell.
- We provided a sensor model for computing the likelihood of measurements and showed that the counting procedure underlying reflection maps yield the optimal map.