Path Planning for Point Robots

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(윤성의)

Course URL:
http://sglab.kaist.ac.kr/~sungeui/MPA

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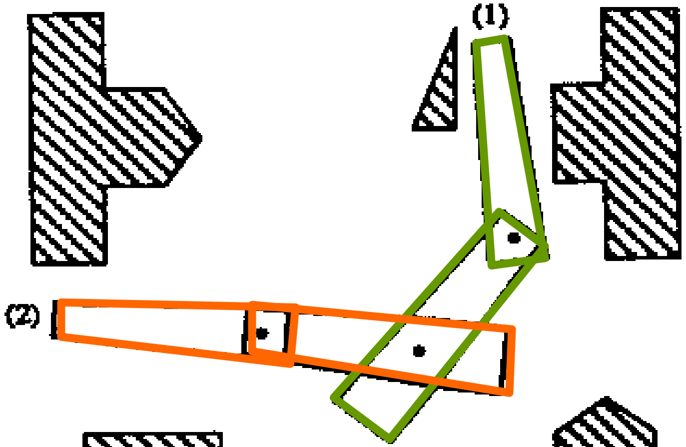
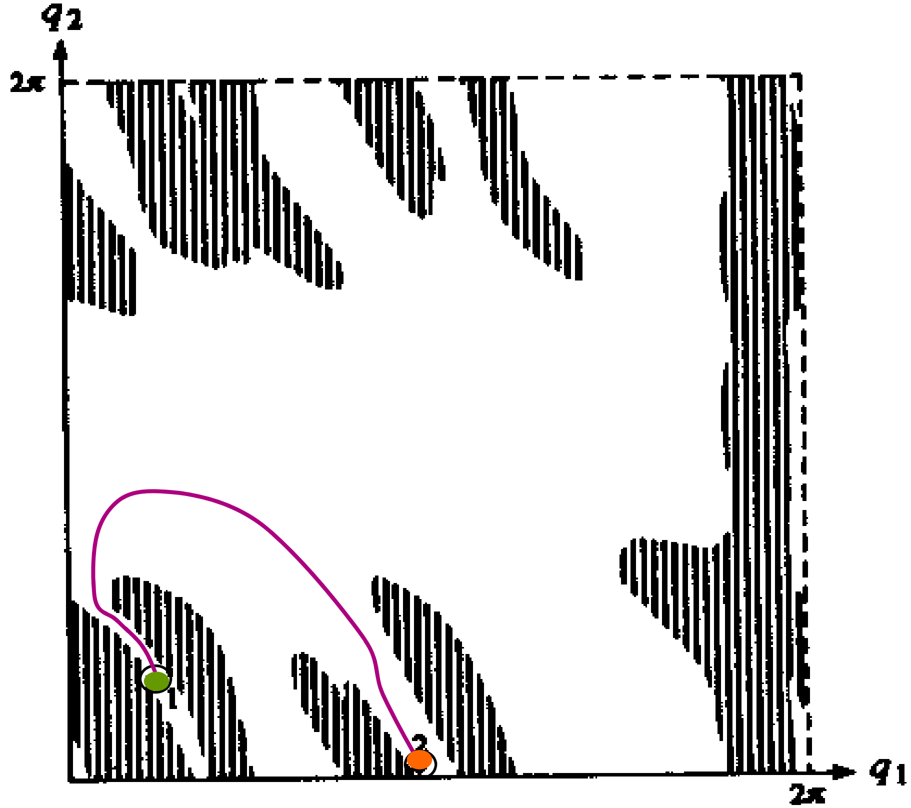
Class Objectives

- Motion planning framework
- Classic motion planning approaches

Configuration Space: Tool to Map a Robot to a Point

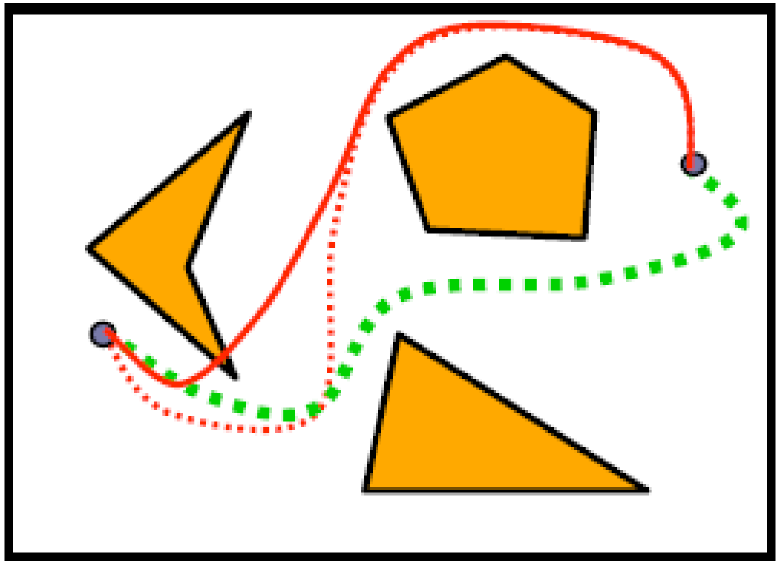




Problem

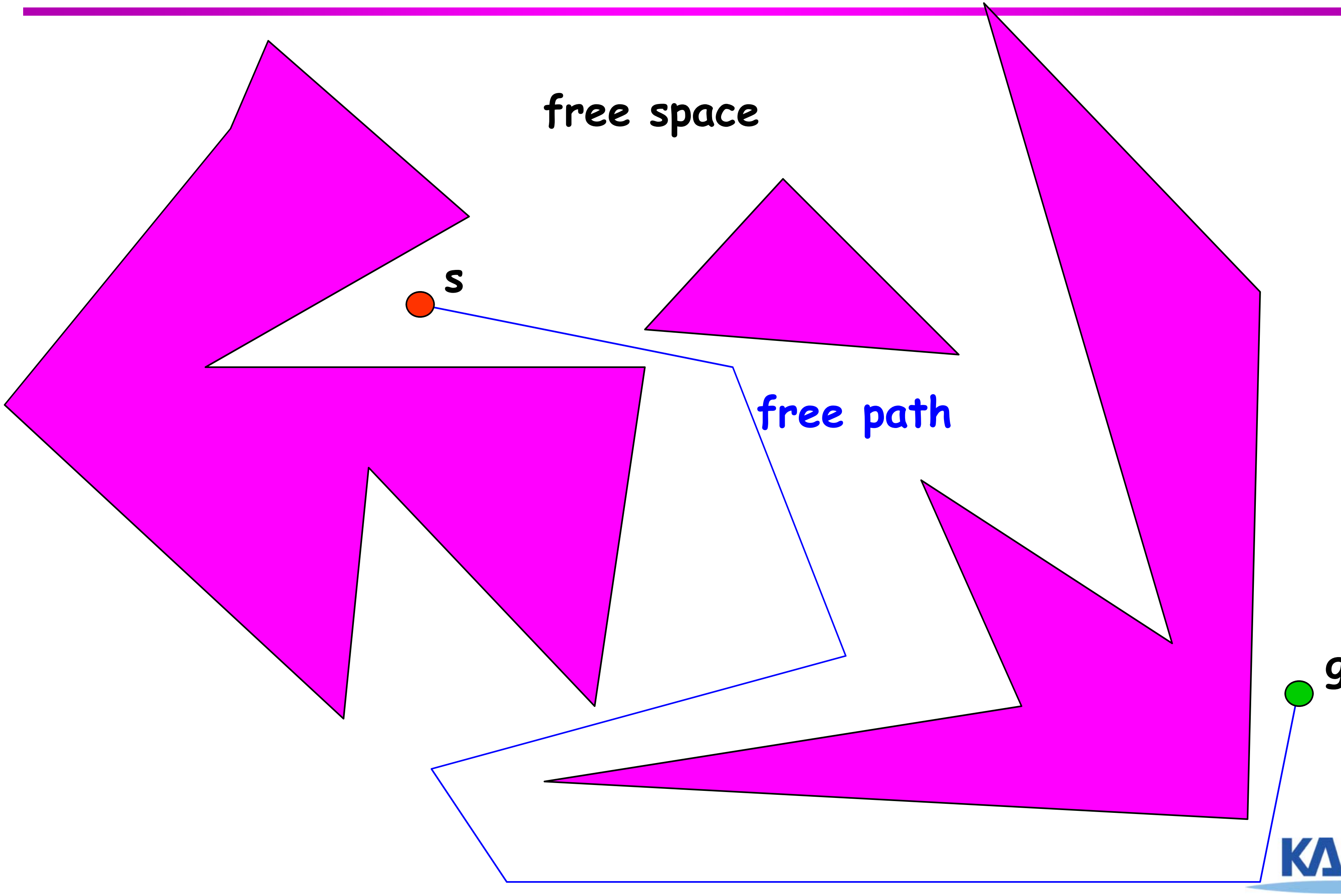
- Input
  - Robot represented as a **point** in the **plane**
  - Obstacles represented as polygons
  - Initial and goal positions
- Output

  A collision-free path between the initial and goal positions

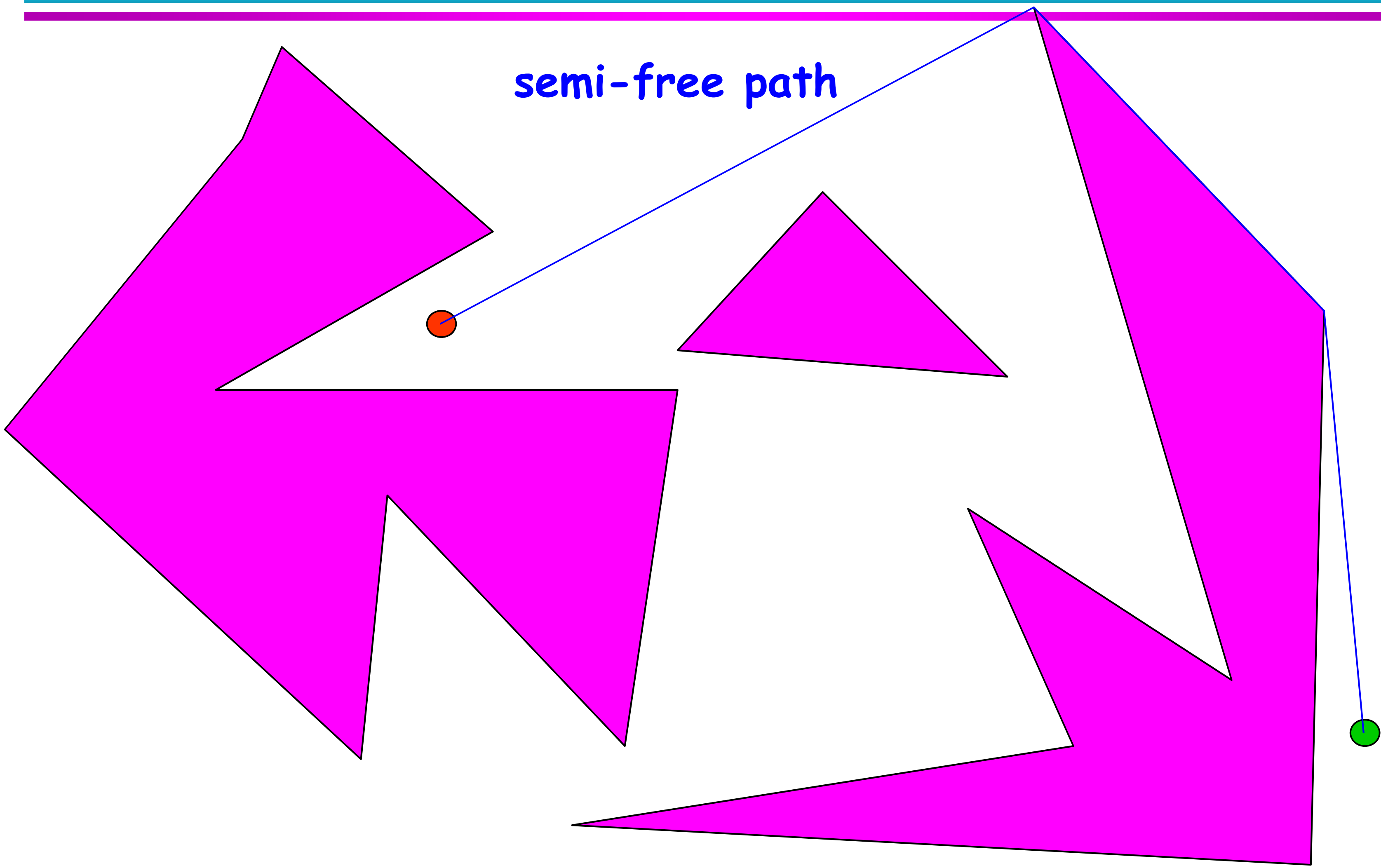


Courtesy of Prof. David Hsu

Problem



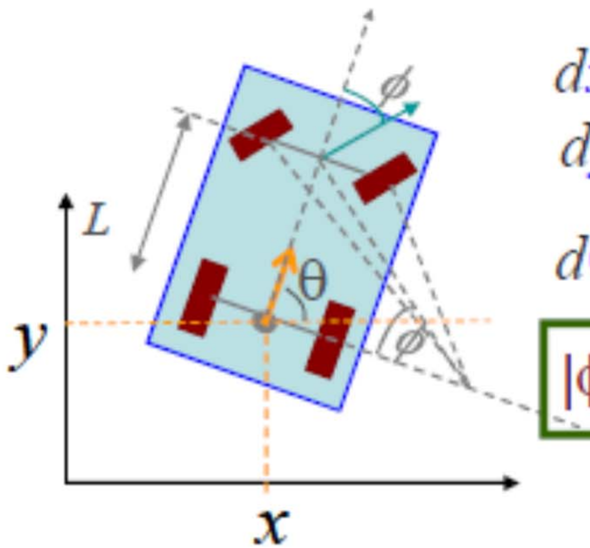
Problem



Types of Path Constraints

- **Local** constraints:
  lie in free space
- **Differential** constraints:
  have bounded curvature
- **Global** constraints:
  have minimal length

Example: Car-Like Robot



$$dx/dt = v \cos\theta, \quad dy/dt = v \sin\theta \;\rightarrow\; dx \sin\theta - dy \cos\theta = 0$$

$$d\theta/dt = (v/L) \tan \phi$$

$$|\phi| \leq \Phi$$

↓

Lower-bounded turning radius

Motion-Planning Framework

Continuous representation

(configuration space formulation)

↓

Discretization

(random sampling, processing critical geometric events)

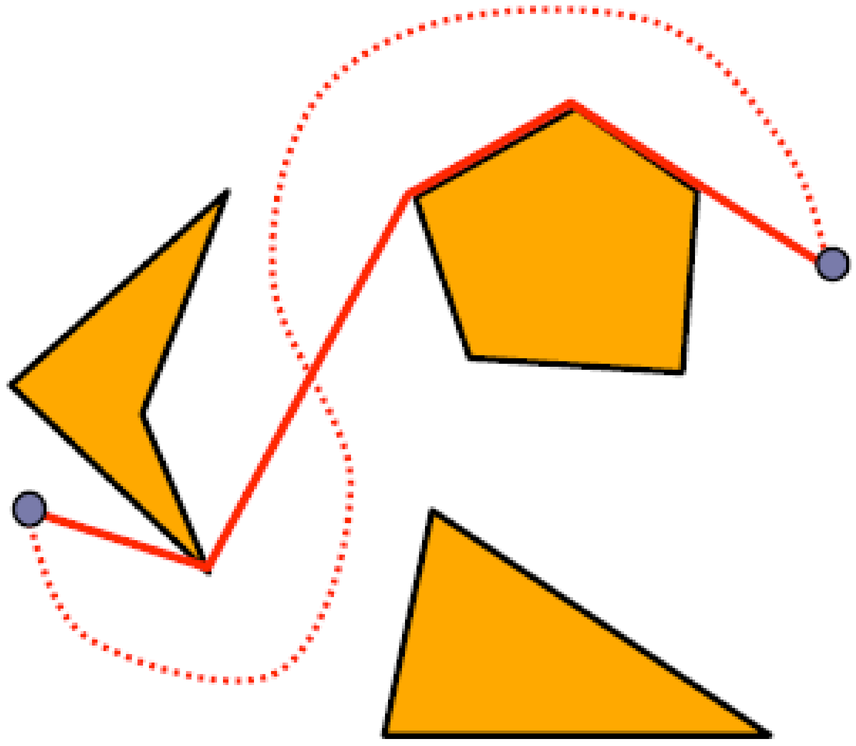
↓

Graph searching

(blind, best-first, A*)

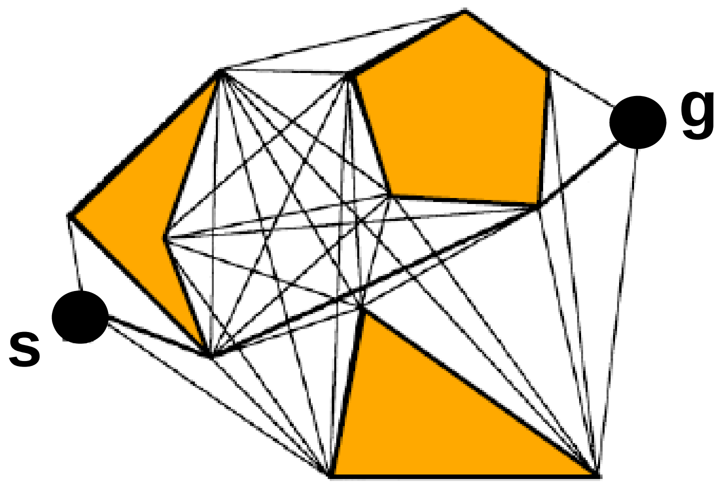
Visibility graph method

- **Observation**: If there is a a collision-free path between two points, then there is a polygonal path that bends only at the obstacles vertices.
- Why?
  Any collision-free path can be transformed into a polygonal path that bends only at the obstacle vertices.



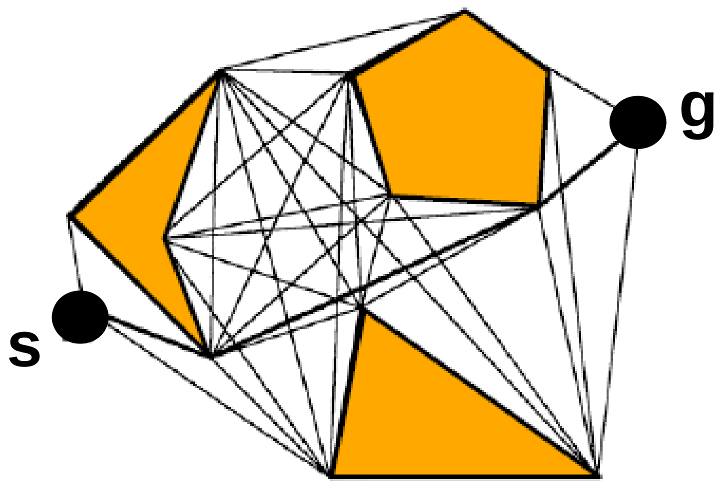
- A **polygonal path** is a piecewise linear curve.

Visibility Graph



- A **visibility graph** is a graph such that
  - Nodes: s, g, or obstacle vertices
  - Edges: An edge exists between nodes u and v if the line segment between u and v is an obstacle edges or it does not intersect the obstacles

Visibility Graph



- A **visibility graph**
  - Introduced in the late 60s
  - Can produce shortest paths in 2-D configuration spaces

Simple Algorithm

- **Input: s, q, polygonal obstacles**
- **Output: visibility graph G**

```
1: for every pair of nodes u, v
2:   if segment (u, v) is an obstacle edge then
3:     insert edge (u, v) into G;
4:   else
5:     for every obstacle edge e
6:       if segment (u, v) intersects e
7:         go to (1);
8:     insert edge (u, v) into G;
9: Search a path with G using A*
```

Computation Efficiency

```
1: for every pair of nodes u, v                          O(n^2)
2:   if segment (u, v) is an obstacle edge then          O(n)
3:      insert edge (u, v) into G;
4:   else
5:      for every obstacle edge e                        O(n)
6:        if segment (u, v) intersects e
7:           go to (1);
8:      insert edge (u, v) into G;
```

- **Simple algorithm: $O(n^3)$ time**
- **More efficient algorithms**
  - **Rotational sweep $O(n^2 \log n)$ time, etc.**
- **$O(n^2)$ space**

Motion-Planning Framework

Continuous representation

(configuration space formulation)

↓

Discretization

(random sampling, processing critical geometric events)

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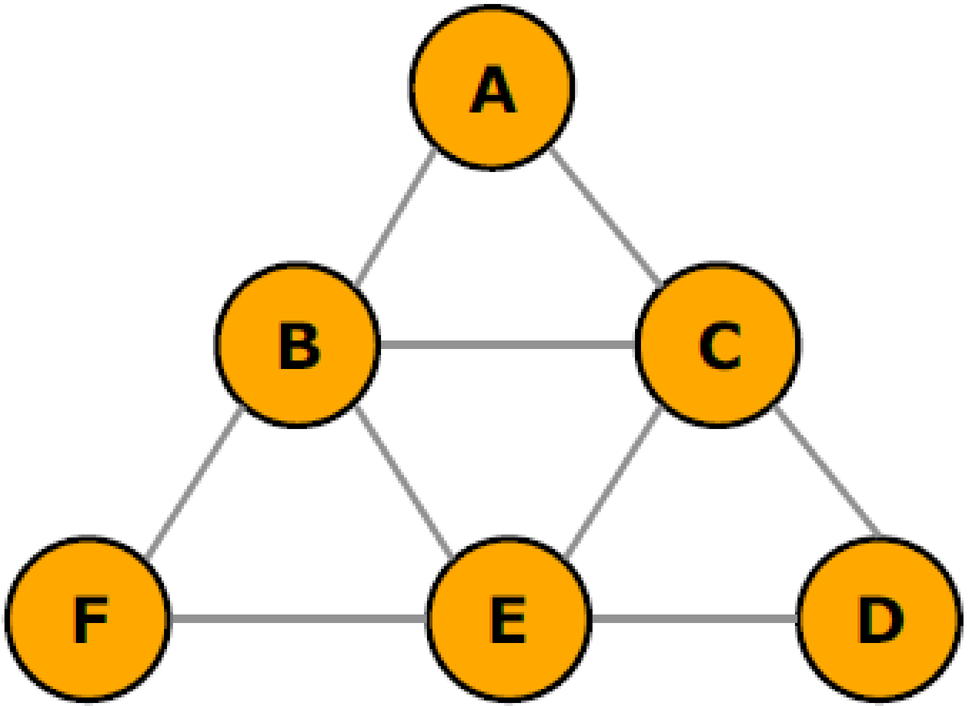
Graph searching

(blind, best-first, A*)

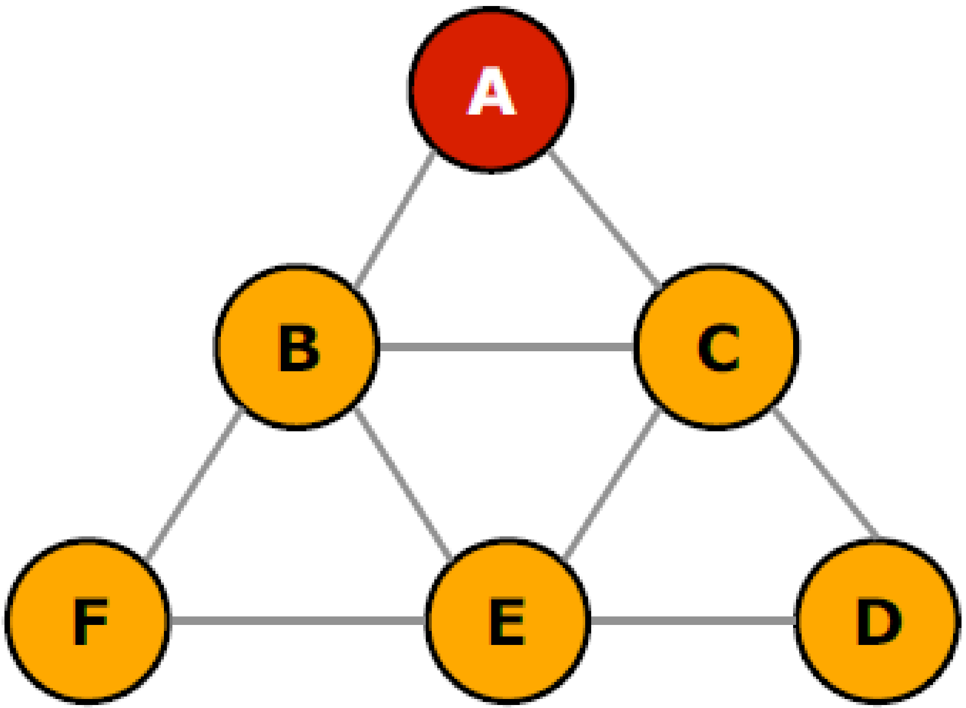
Graph Search Algorithms

- Breadth, depth-first, best-first
- Dijkstra's algorithm
- A*

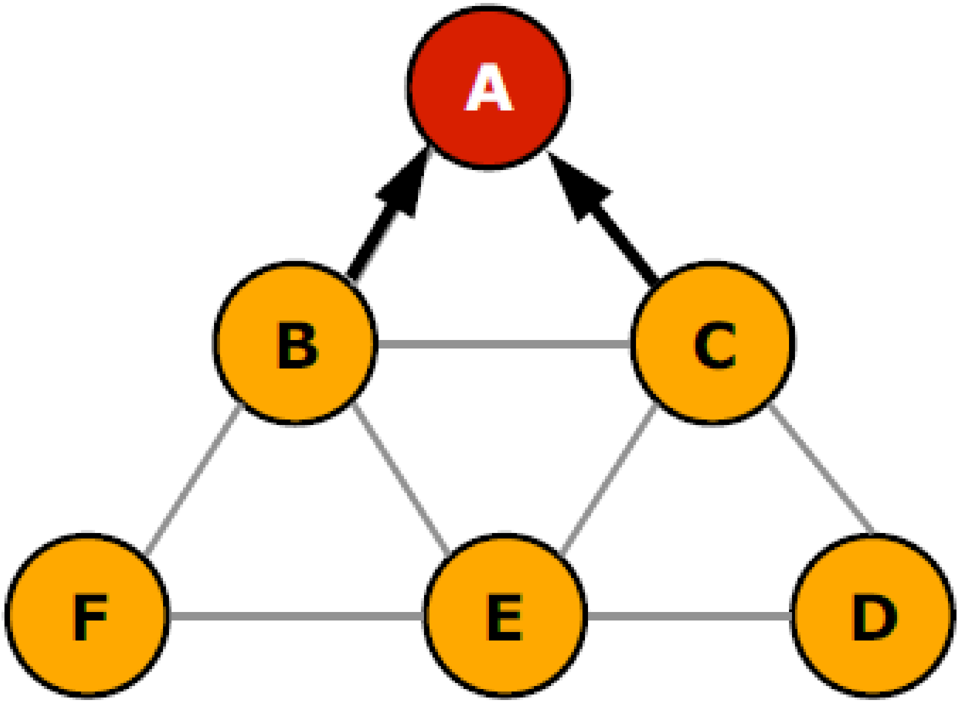
Breadth-first search



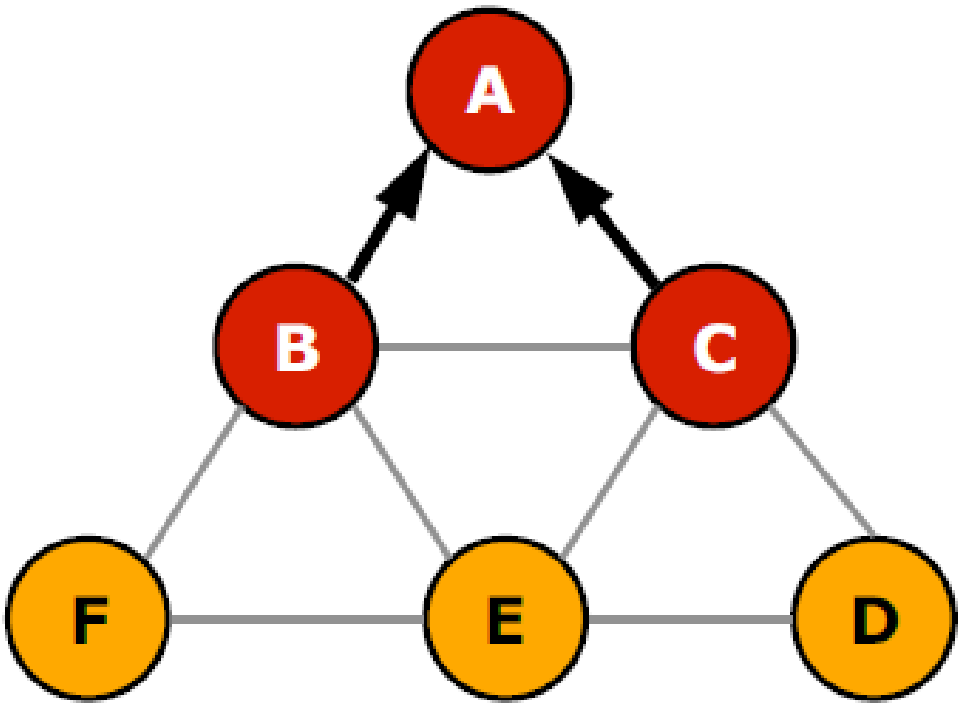
Breadth-first search



Breadth-first search



Breadth-first search



Dijkstra's Shortest Path Algorithm

- Given a (non-negative) weighted graph, two vertices, s and g:
  - Find a path of minimum total weight between them
  - Also, find minimum paths to other vertices
  - Has O (|V| lg|V| + |E|)

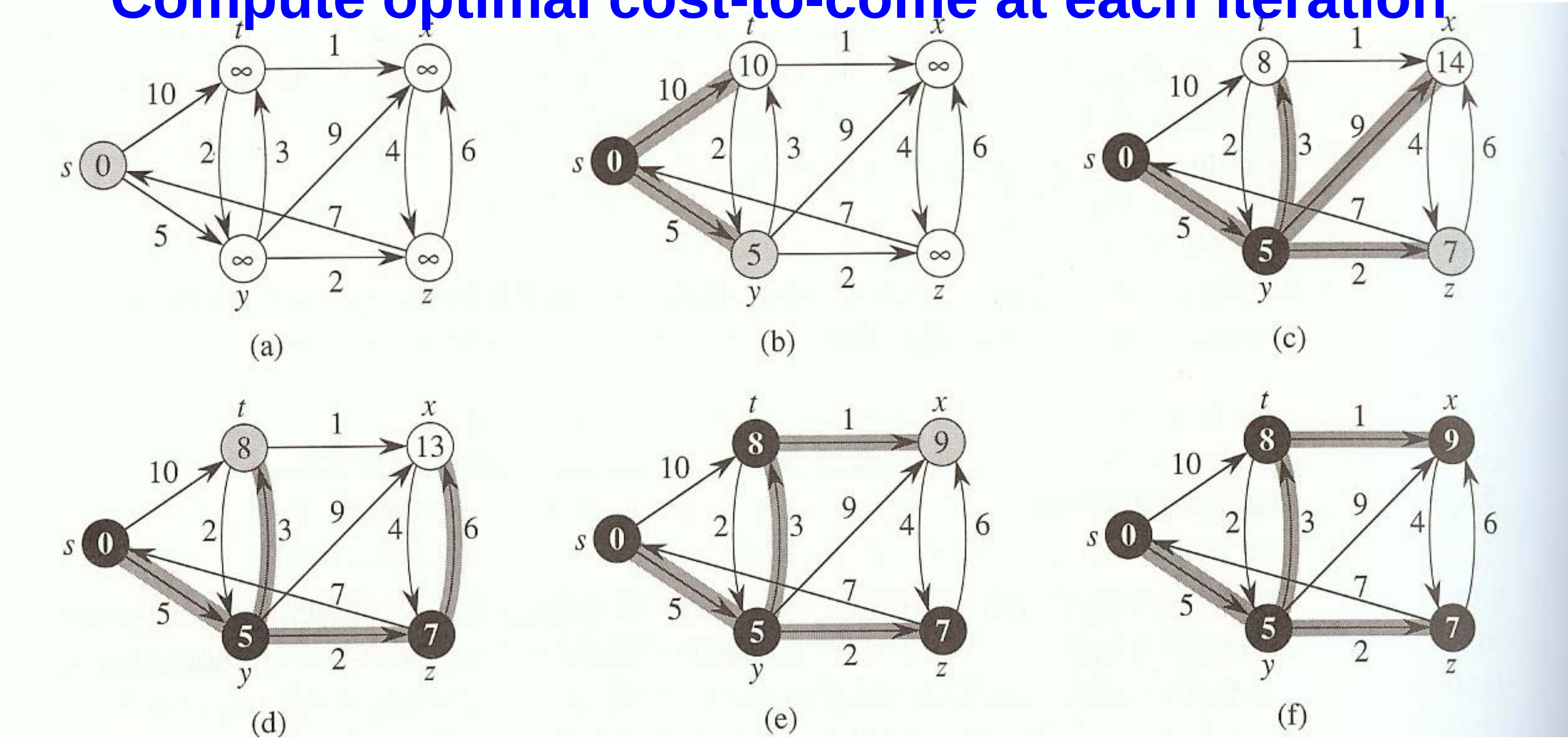
Dijkstra's Shortest Path Algorithm

- **A set S**
  - **Contains vertices whose final shortest-path cost has been determined**

- **DIJKSTRA (G, s)**
  1. Initialize-Single-Source (G, s)
  2. S ← empty
  3. Queue ← Vertices of G
  4. **While** Queue is not empty
  5.   **Do** u ← min-cost from Queue
  6.   S ← union of S and {u}
  7.   **for** each vertex v in Adj [u]
  8.   **do** RELAX (u, v)

Dijkstra's Shortest Path Algorithm

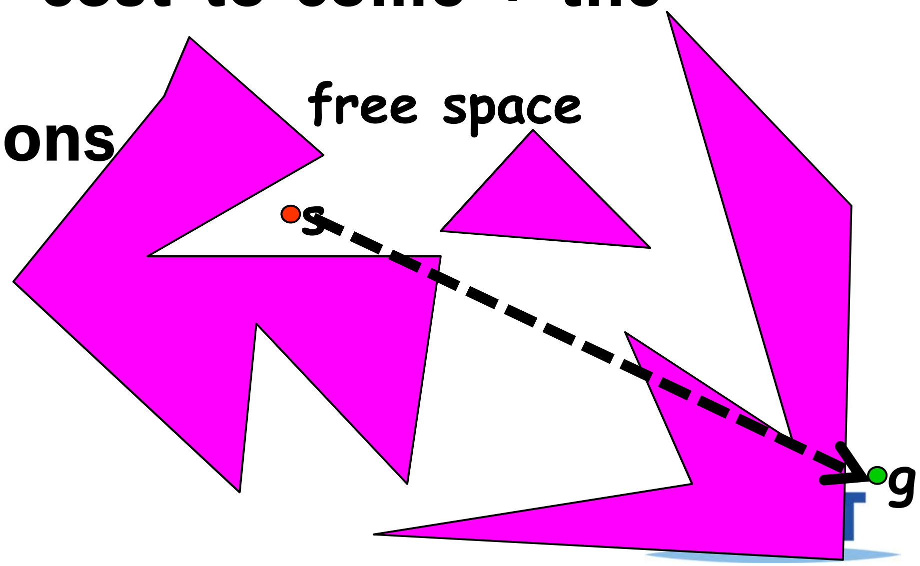
Compute optimal cost-to-come at each iteration



Black vertices are in the set.
White vertices are in the queue.
Shaded one is chosen for relaxation.

A* Search Algorithm

- An extension of Dijkstra's algorithm based on a heuristic estimate
  - Conservatively estimate the cost-to-go from a vertex to the goal
  - The estimate should not be greater than the optimal cost-to-go
  - Sort vertices based on "cost-to-come + the estimated cost-to-go"
  - Can find optimal solutions with fewer steps



Best-First Search

- Pick a next node based on an estimate of the optimal cost-to-go cost
  - Greedily finds solutions that look good
  - Solutions may not be optimal
  - Can find solutions quite fast, but can be also very slow

Framework

continuous representation

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discretization

construct visibility graph

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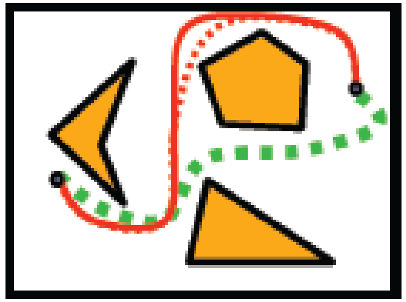
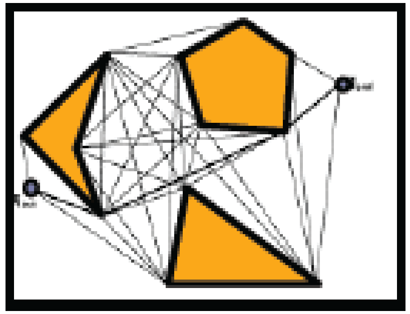
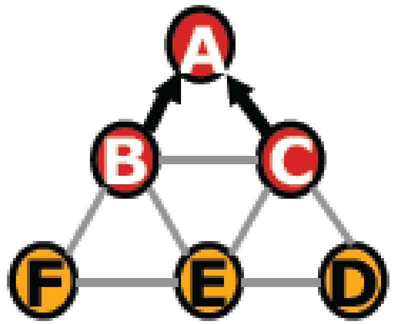
graph searching

breadth-first search







Computational Efficiency

- Running time $O(n^3)$
  - Compute the visibility graph
  - Search the graph
- Space $O(n^2)$

- Can we do better?

Classic Path Planning Approaches

- Roadmap
  - Represent the connectivity of the free space by a network of 1-D curves
- Cell decomposition
  - Decompose the free space into simple cells and represent the connectivity of the free space by the adjacency graph of these cells
- Potential field
  - Define a function over the free space that has a global minimum at the goal configuration and follow its steepest descent

Classic Path Planning Approaches

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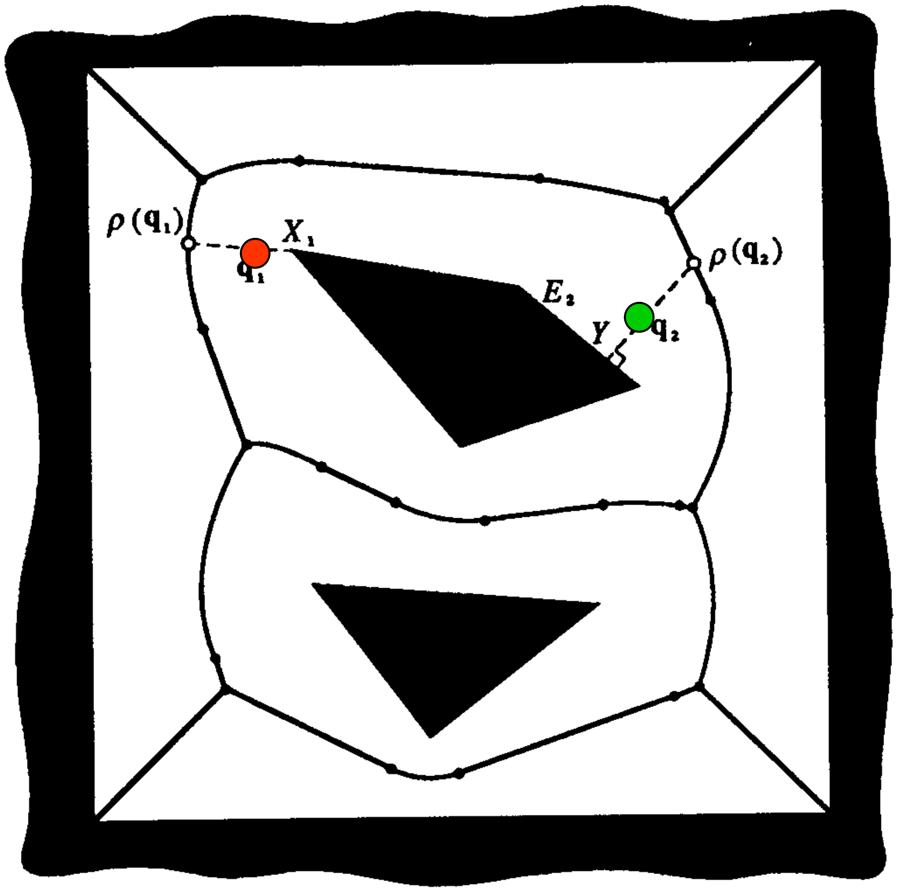
Roadmap Methods

- Visibility Graph
  - Shakey project, SRI [Nilsson 69]
- Voronoi diagram
  - Introduced by computational geometry researchers
  - Generate paths that maximize clearance
  - O(n log n) time and O(n) space



Other Roadmap Methods

- Visibility graph
- Voronoi diagram
- Silhouette
  - First complete general method that applies to spaces of any dimension and is singly exponential in # of dimensions [Canny, 87]
- Probabilistic roadmaps

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Classic Path Planning Approaches

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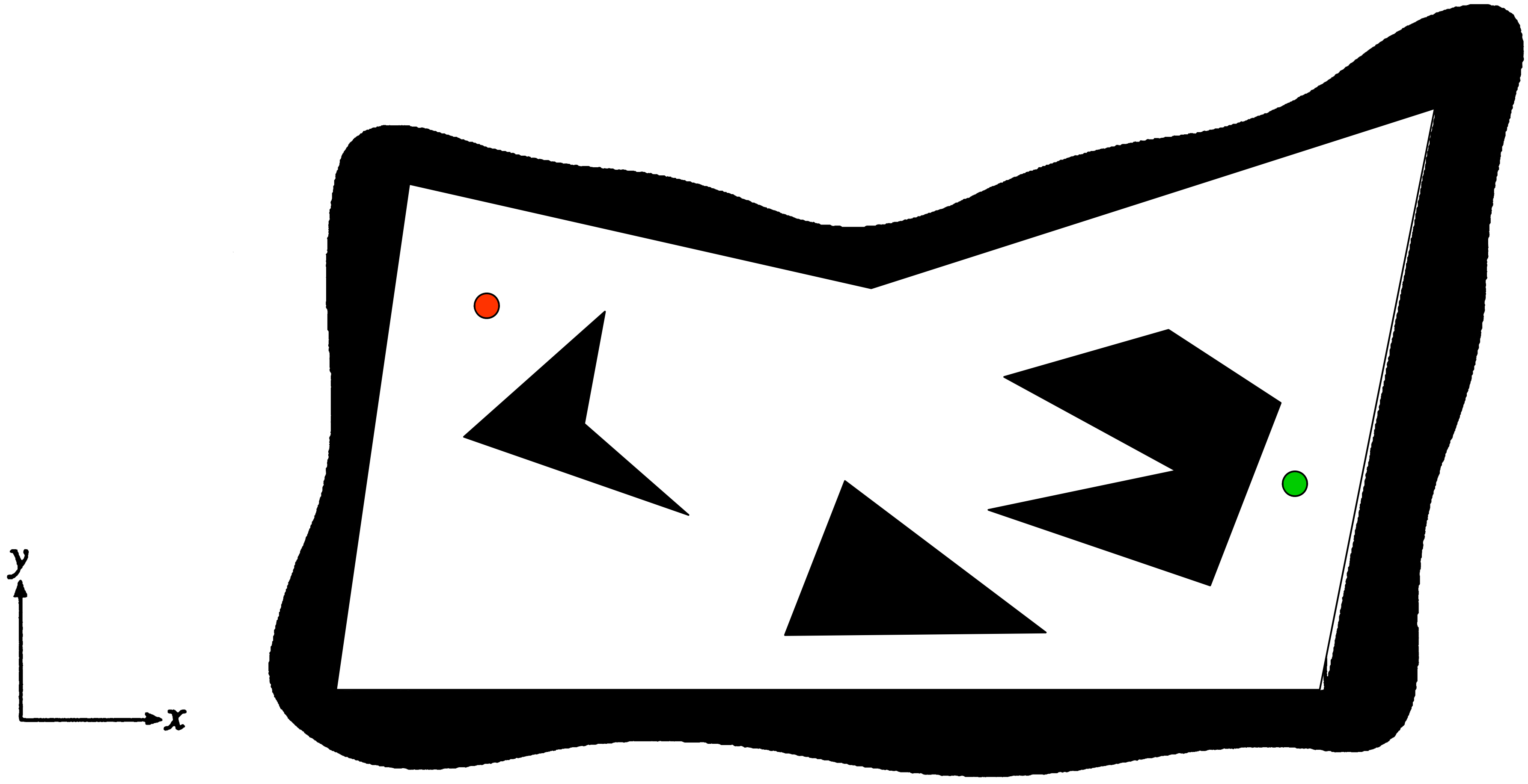
Cell-Decomposition Methods

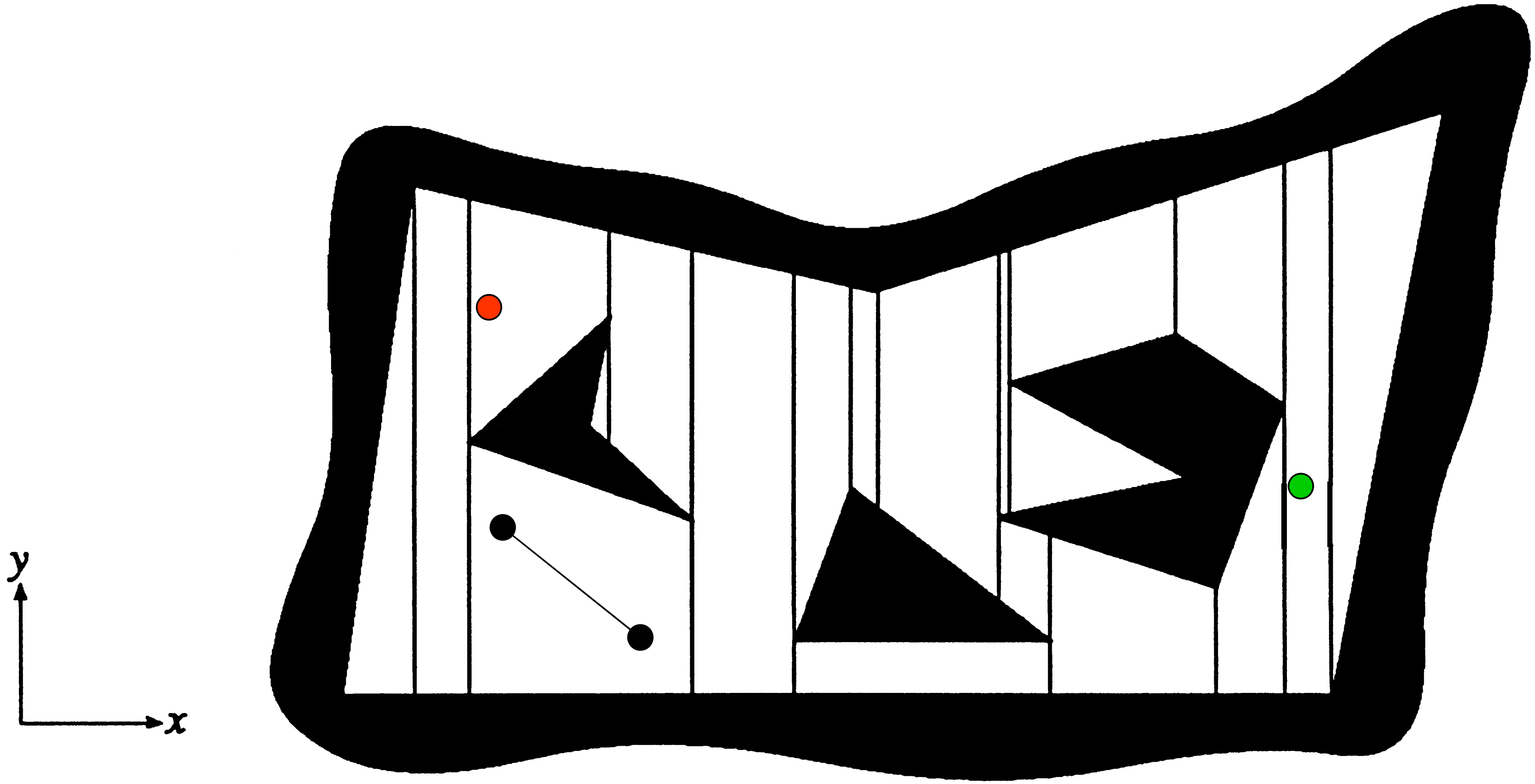
- Two classes of methods:
  - Exact and approximate cell decompositions

- Exact cell decomposition
  - The free space F is represented by a collection of non-overlapping cells whose union is exactly F
  - Example: trapezoidal decomposition

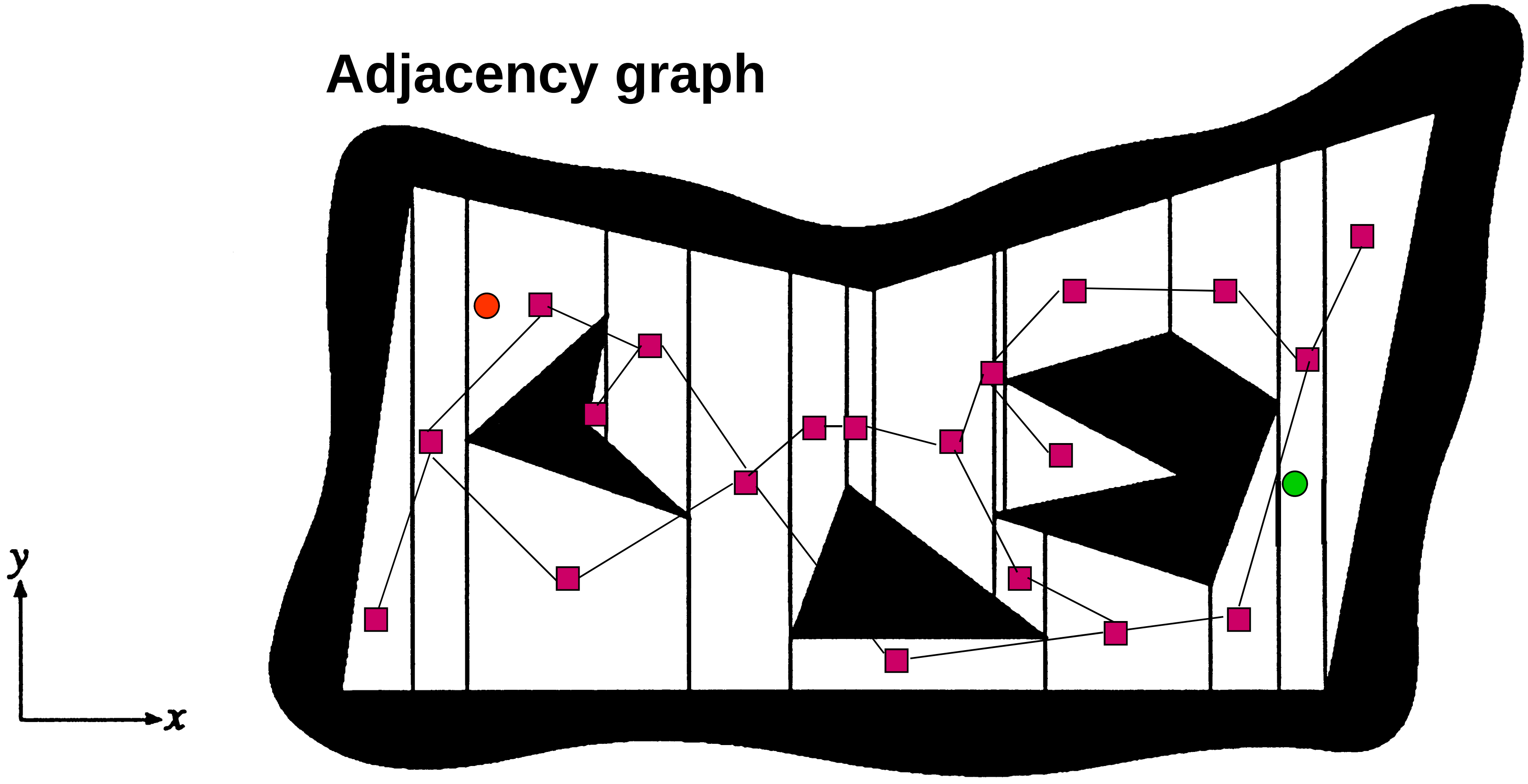
Trapezoidal Decomposition



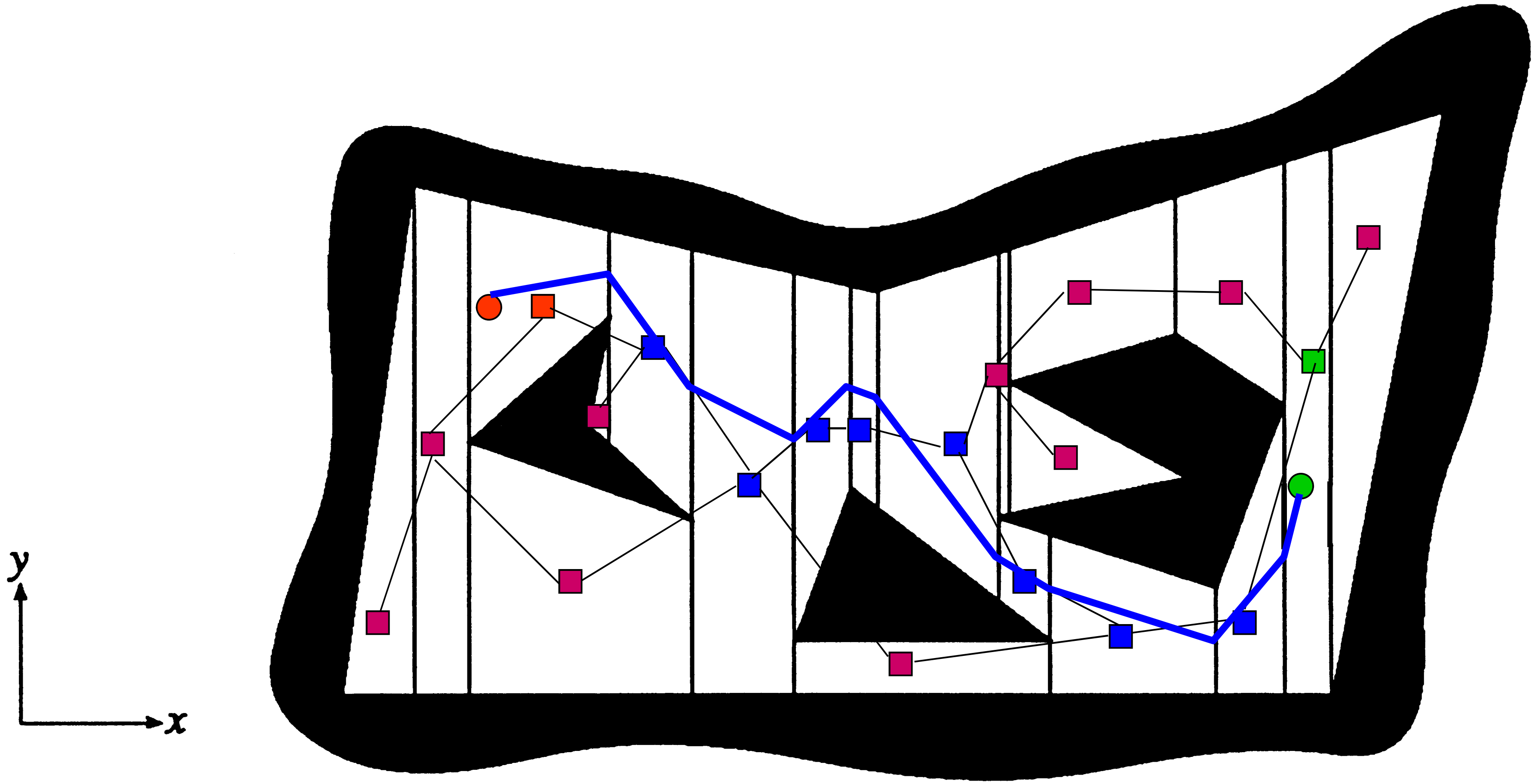
Trapezoidal Decomposition



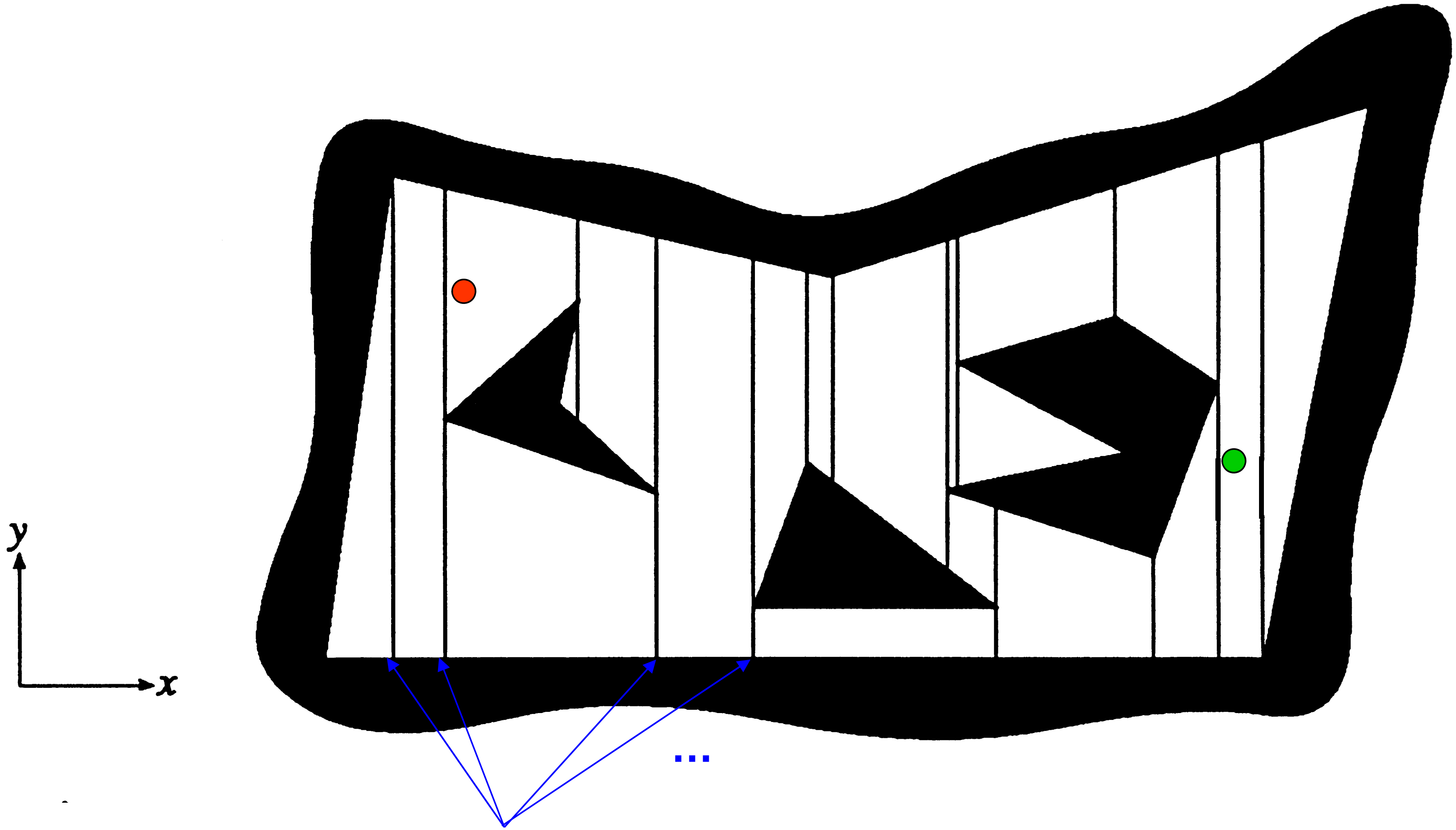
Trapezoidal Decomposition



Trapezoidal Decomposition



Trapezoidal Decomposition



critical events → criticality-based decomposition

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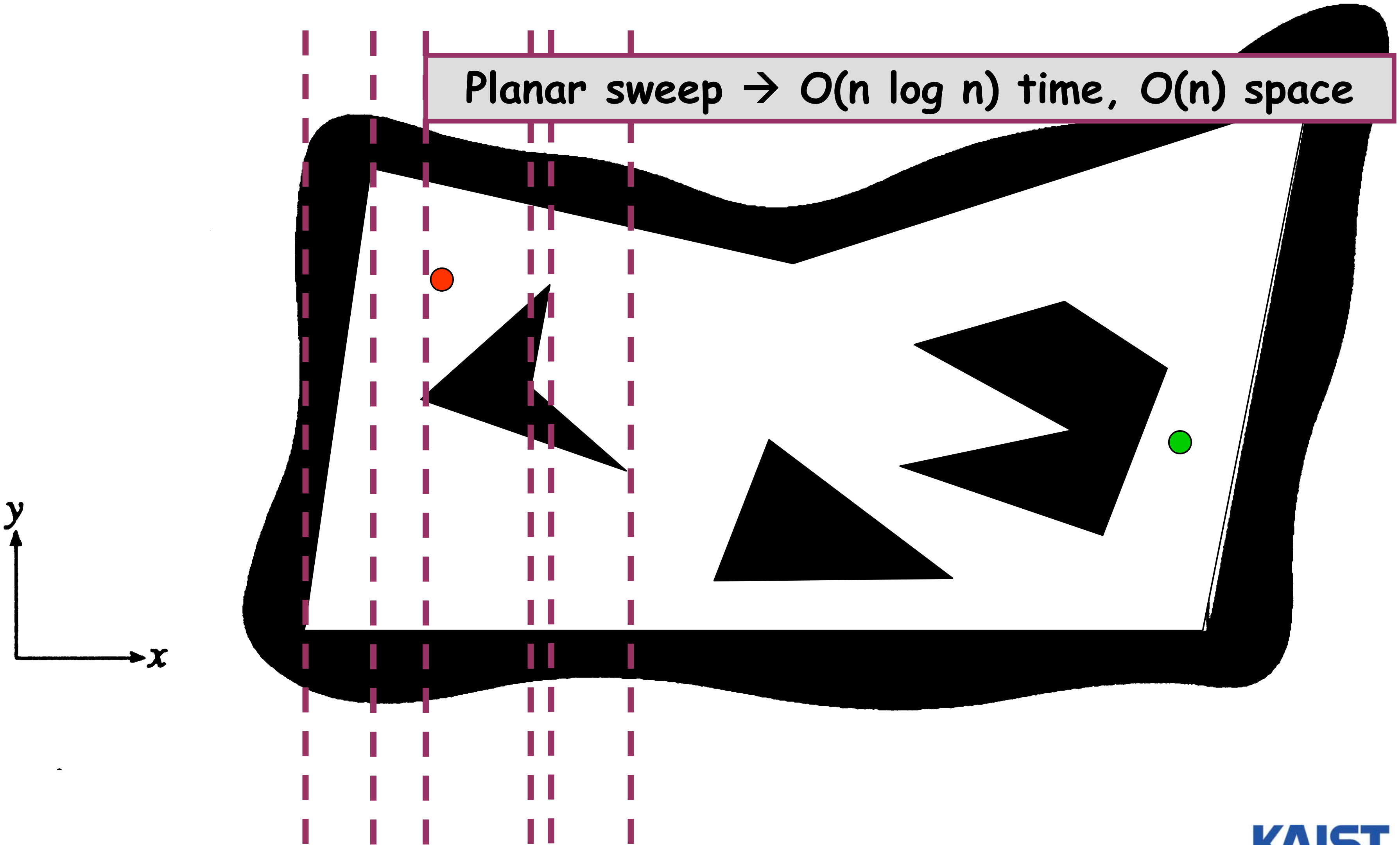
Trapezoidal Decomposition

Planar sweep → O(n log n) time, O(n) space

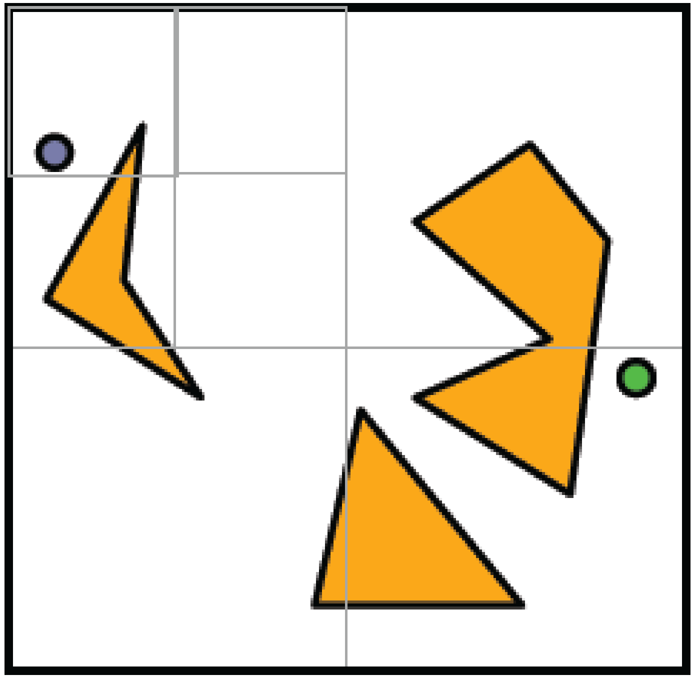


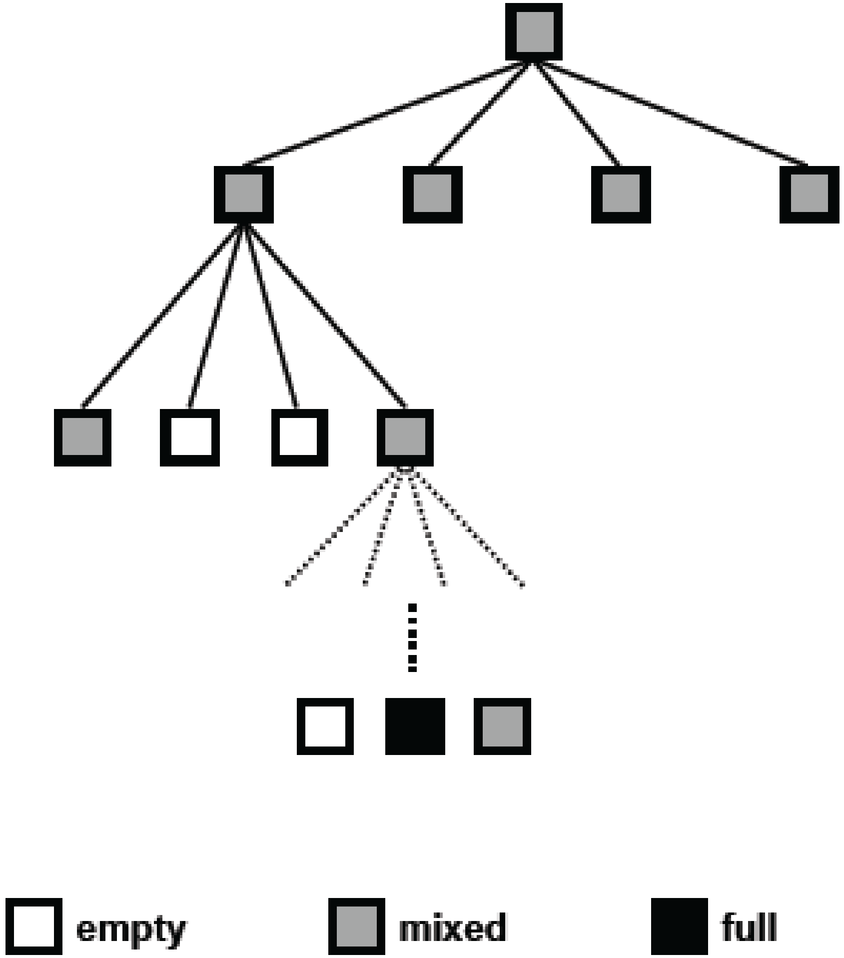
Cell-Decomposition Methods

- **Two classes of methods:**
  - **Exact and approximate cell decompositions**

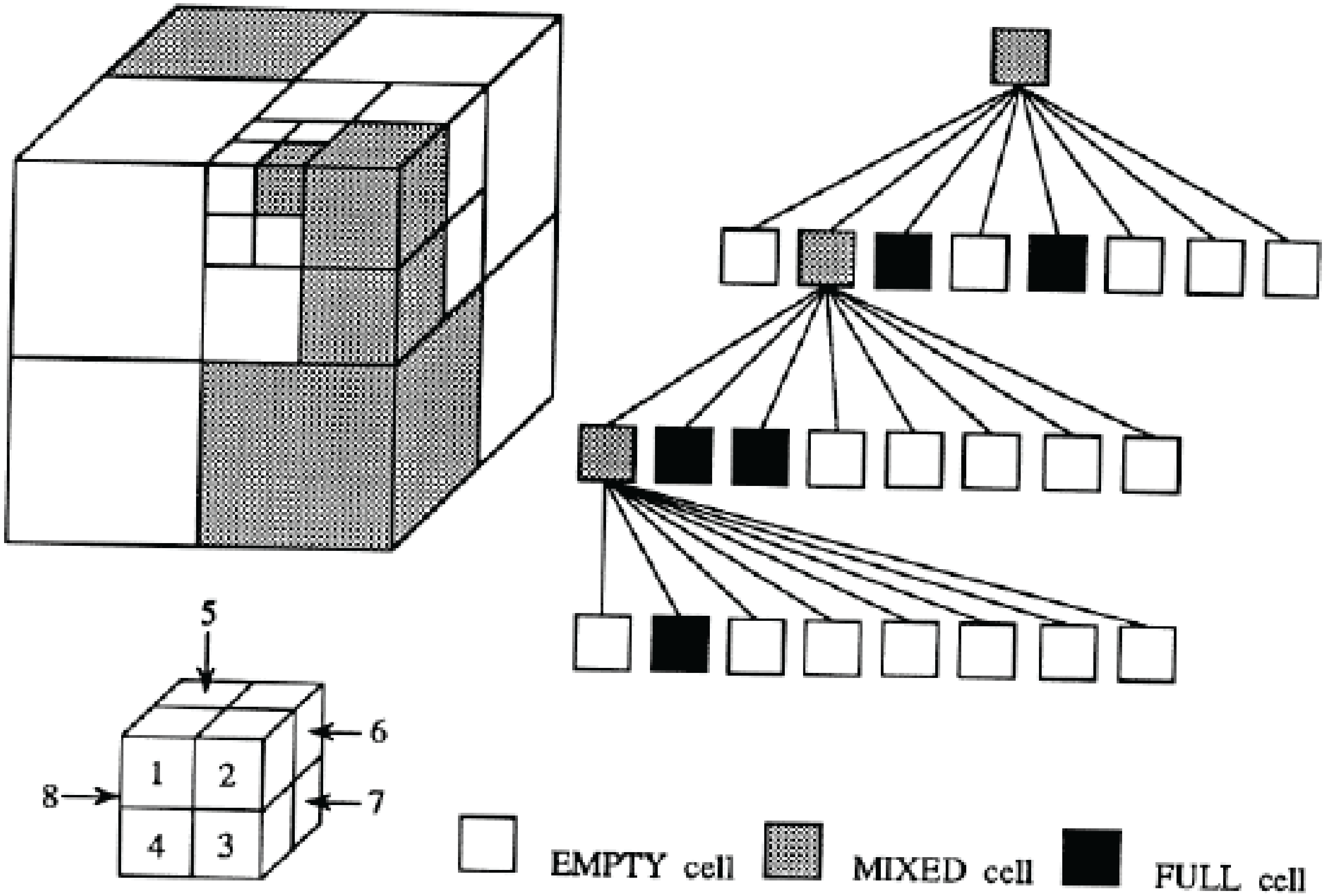
- **Approximate cell decomposition**
  - **The free space F is represented by a collection of non-overlapping cells whose union is contained in F**
  - **Cells usually have simple, regular shapes (e.g., rectangles and squares)**
  - **Facilitates hierarchical space decomposition**

Quadtree decomposition





Octree decomposition



Sketch of Algorithm

1. Decompose the free space F into cells
2. Search for a sequence of mixed or free cells that connect that initial and goal positions
3. Further decompose the mixed
4. Repeat 2 and 3 until a sequence of free cells is found

Classic Path Planning Approaches

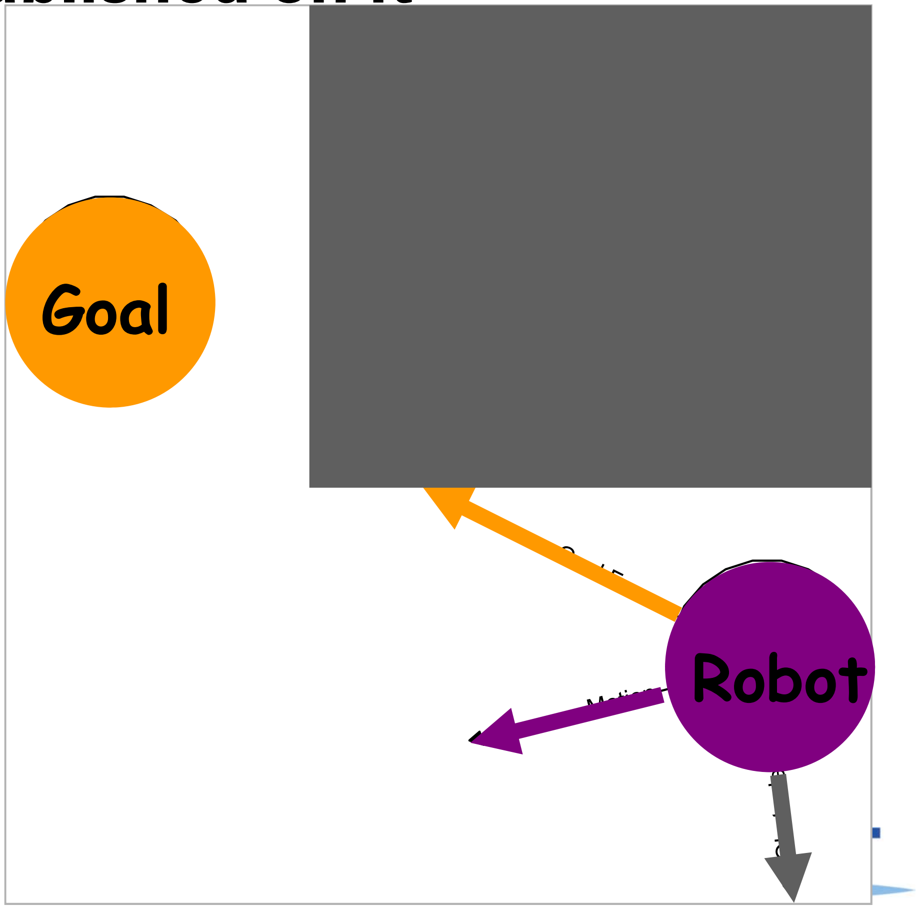
- Roadmap
  - Represent the connectivity of the free space by a network of 1-D curves
- Cell decomposition
  - Decompose the free space into simple cells and represent the connectivity of the free space by the adjacency graph of these cells
- Potential field
  - Define a function over the free space that has a global minimum at the goal configuration and follow its steepest descent

Potential Field Methods

- **Initially proposed for real-time collision avoidance [Khatib, 86]**
  - **Hundreds of papers published on it**

$$F_{Goal} = -k_p (x - x_{Goal})$$

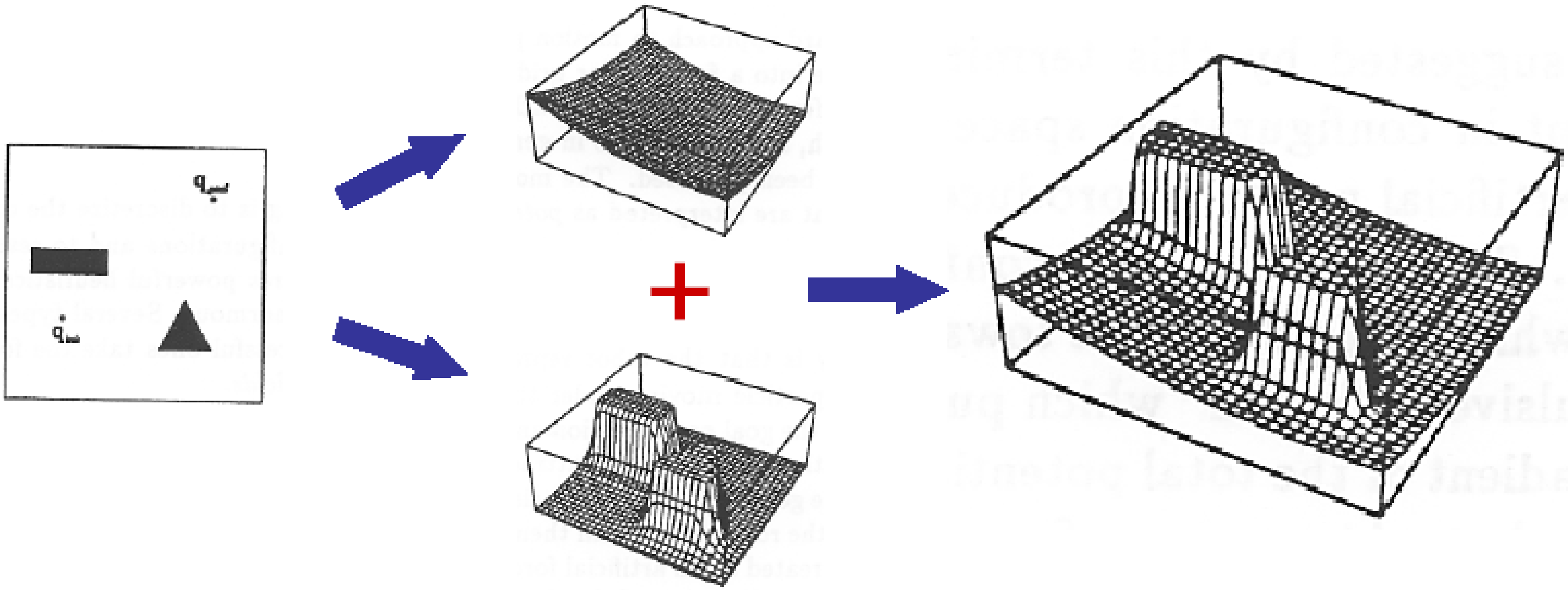
$$F_{Obstacle} = \begin{cases} \eta \left(\frac{1}{\rho} - \frac{1}{\rho_0} \right) \frac{1}{\rho^2} \frac{\partial \rho}{\partial x} & if\ \rho \leq \rho_0, \\ 0 & if\ \rho > \rho_0 \end{cases}$$



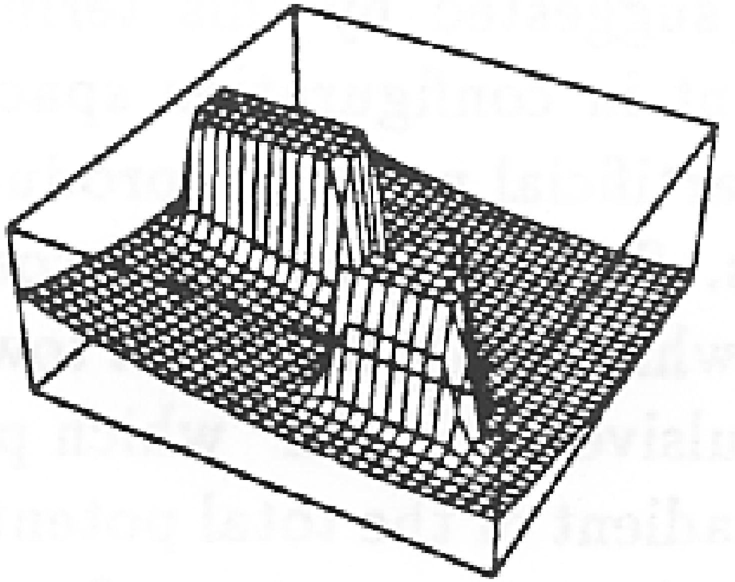
Potential Field

- A scalar function over the free space
- To navigate the robot applies a force proportional to the negated gradient of the potential field
- A navigation function is an ideal potential field that
  - Has global minimum at the goal
  - Has no local minima
  - Grows to infinity near obstacles
  - Is smooth

Attractive and Repulsive fields



Local Minima



- What can we do?
  - Escape from local minima by taking random walks
  - Build an ideal potential field that does not have local minima

Sketch of Algorithm

- Place a regular grid G over the configuration space
- Compute the potential field over G
- Search G using a best-first algorithm with potential field as the heuristic function

Question

- **Can such an ideal potential field be constructed efficiently in general?**

Completeness

- A complete motion planner always returns a solution when one exists and indicates that no such solution exists otherwise
  - Is the visibility algorithm complete? Yes
  - How about the exact cell decomposition algorithm and the potential field algorithm?

Class Objectives were:

- **Motion planning framework**
- **Classic motion planning approaches**

Homework for Every Class

- **Go over the next lecture slides**
- **Come up with one question on what we have discussed today and submit at the end of the class**
  - **1 for typical questions**
  - **2 for questions with thoughts or that surprised me**

- **Write a question at least 10 times**
  - **Do that out of 2 classes**

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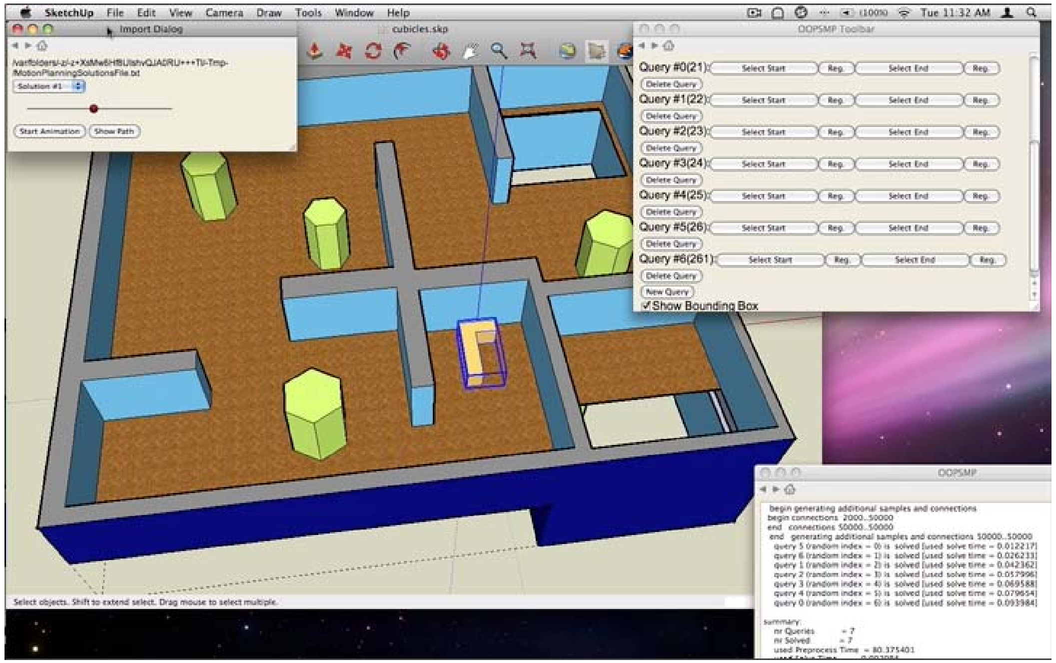
Homework

- Install Open Motion Planning Library (OMPL)
- Create a scene and a robot
- Find a collision-free path and visualize the path



Homework

- Deadline: 11:59pm, Sep.-30
- Delivery: send an email to TA (limg00n@kaist.ac.kr) that contains:
  - An image that shows a scene with a robot with a computed path

- Our TA: 임장관, x7851, N1, 924호

Conf. Deadline

- **ICRA**
  - **Sep., 2013**
- **IROS**
  - **Mar., 2014**

Next Time….

- Configuration spaces