

Robot Autonomy Lecture Note 3.6

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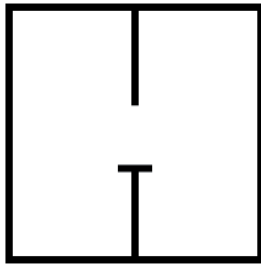
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1 Hybrid-System

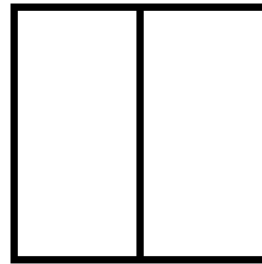
Hybrid system is a mixture of discrete and continuous variable.

1. World $W = R^2$ or R^3

2. Model Space M with modes m



$m = \text{open}$
 $x = ((x,y), \text{open})$



$m = \text{closed}$

3. An obstacle region $O(m) \subset W$

4. A robot $A(m)$ for each mode m

5. State Space $X = C \times A$

$x = (q, m)$ e.g. $x = ((x, y), OPEN)$

$X_{obs} = \{(q, m) \in X | A(q, m) \cap O(m) \neq \phi\}$

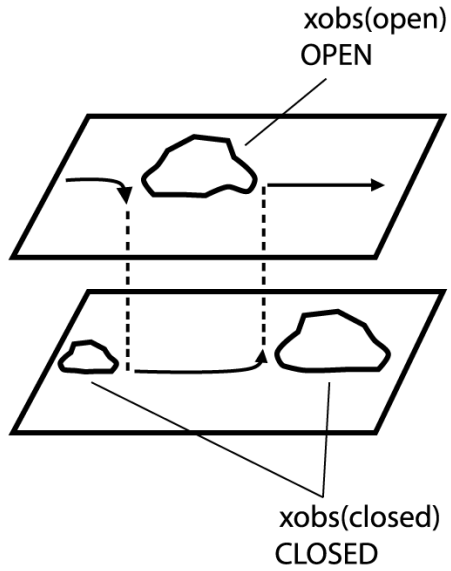
6. For each state x , define a finite action space $U(x)$

Example: Open Door/ Close Door

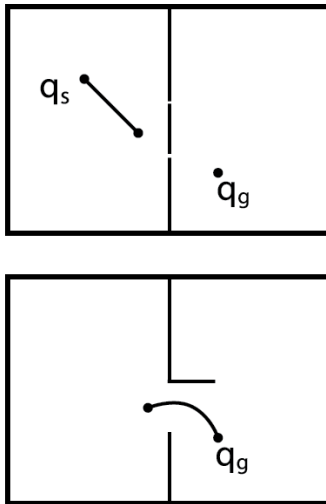
7. Mode transition function

$f_m((q, \underline{OPEN}), \underline{CloseDoor}) = \underline{Closed}$
mode action mode

8. State transition function



$f(x, u) = (q, f_m(x, u))$
 Example: $f((q, OPEN), CloseDoor) = (q, Close)$

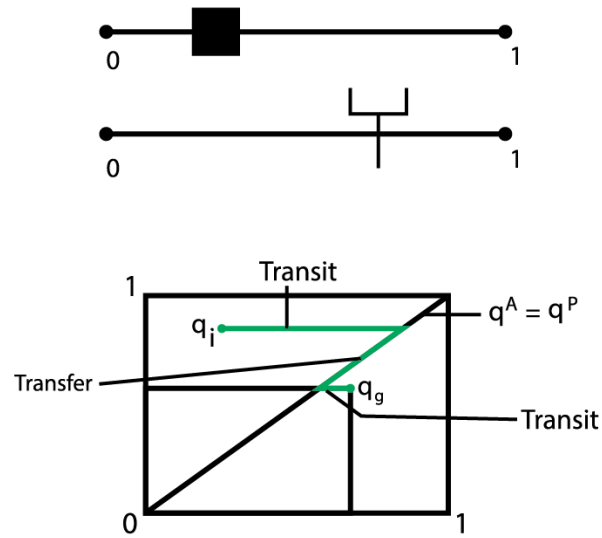


2 Bead on Wire

Case 1:

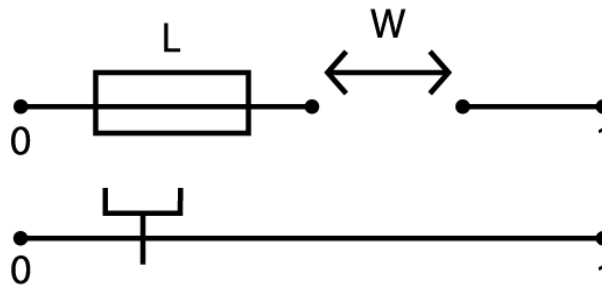
Actions: {grasp, ungrasp}
 modes: {Transfer, Transit}

Transfer → Robot moving bead
 Transit → Robot moving on its own

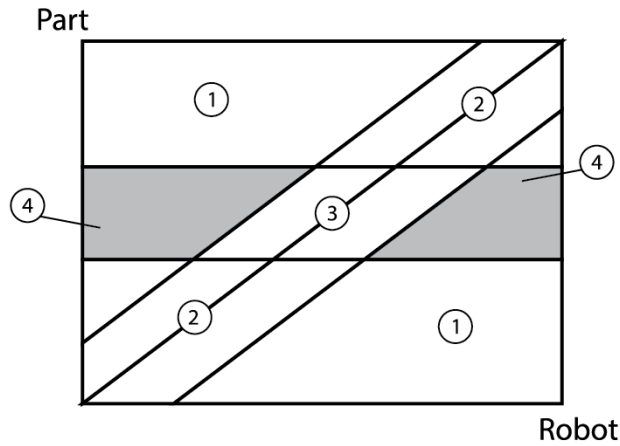


Transfer Space: $q^A = q^P$
 Transit Space: Copies of R^1 stacked on each other to form R^2 (Foliation)

Case 2:



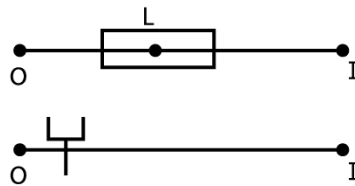
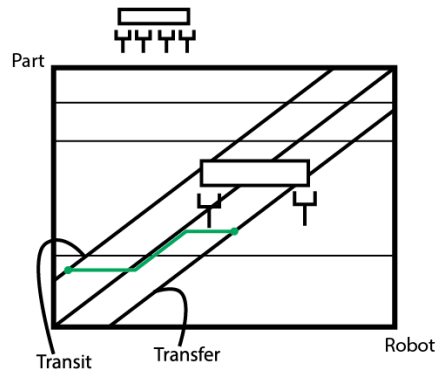
Both Transfer and Transit *Cspace* are foliated



- 1. Transit only
- 2. Transit + Transfer
- 3. Transfer only
- 4. Forbidden

Case 3:

Rod L can cross gap W if being held by the robot while crossing



Consider if the rod had an encasing tub instead of the gap → TRANSFER OBSTACLE

3 Manipulation Cspace

1. World $W = R^2$ or R^3
2. Obstacle $O \subset W$
3. Robot A , $q^A \in C^A$
4. Part p , $q^p \in SE(2)$ or $SE(3)$

$$C = C^A \times C^p$$

$$C_{obs}^A = \{(q^A, q^p) \in C | A(q^A) \cap O \neq \phi\} \text{ Robot-Obstacle}$$

$$C_{obs}^p = \{(q^A, q^p) \in C | p(q^p) \cap O \neq \phi\} \text{ Part-Obstacle}$$

$$C_{adm} = C \setminus C_{obs}^A \setminus C_{obs}^p \setminus C_{obs}^{Ap}$$

$$C_{obs}^{Ap} \rightarrow \text{Robot penetrate object}$$

C^{stable} : set of all stable configuration.

C^{grasp} : set of all configuration where robot is grasping the part

$C^{transition} = C^{grasp} \cap C^{stable}$ (only places the robot can pick up and put down the part)