Lab 8

School of Architecture, Civil and Environmental Engineering

EPFL, WS 2020-2021

https://disal.epfl.ch/teaching/signals_instruments_systems/

Outline

- Contents
  - Odometry with non-deterministic uncertainties
  - Feature based navigation
  - Sensor Fusion

- Tools
  - Webots
  - C compiler
  - MATLAB

Getting Started

- Installation
  - Go to moodle and download:

    Lab08 (.zip) and the assignment
- Starting with Webots
  - Launch Webots
  - Open World file for lab8
  - Clean + Build robot controller

Lab might be a bit long, try to solve the (B) questions later (part of the project)

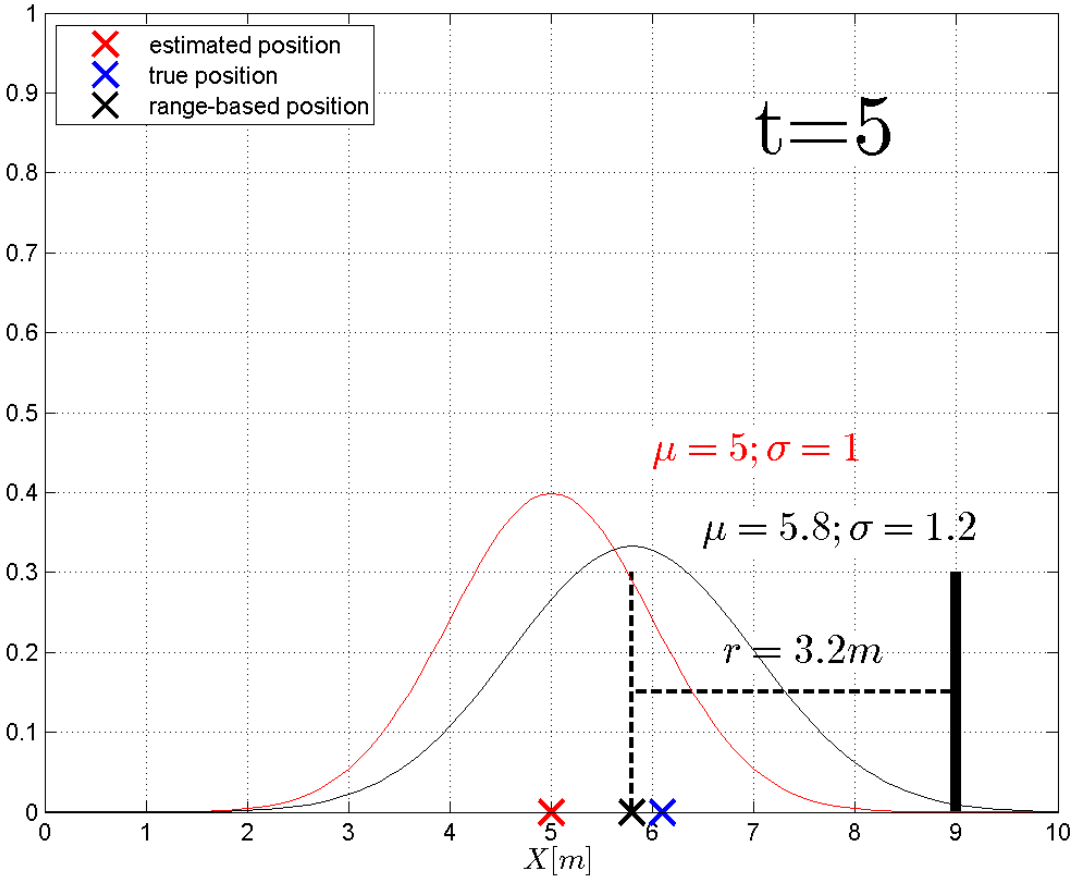
Robot Pose

- In 2D : Ground Robot
  - Needs 3 variables

  (e.g. 2 positions + heading)

  $p_{2D} = [x, y, \theta]^T$

Feature based navigation



Kalman Filter

Algorithm **Kalman_filter**($\mu_{t-1}, \Sigma_{t-1}, u_t, z_t$)

1. Prediction:
2. $\bar{\mu}_t = A_t \mu_{t-1} + B_t u_t$
3. $\bar{\Sigma}_t = A_t \Sigma_{t-1} A_t^T + R_t$

4. Correction or update:
5. $K_t = \bar{\Sigma}_t C_t^T (C_t \bar{\Sigma}_t C_t^T + Q_t)^{-1}$
6. $\mu_t = \bar{\mu}_t + K_t (z_t - C_t \bar{\mu}_t)$
7. $\Sigma_t = (I - K_t C_t) \bar{\Sigma}_t$

8. Return μ_t, Σ_t

[Adapted from Thrun et al., 2005]

Feedback for Lab 8

Please help us improve the labs by giving us feedback.

Lab 8 is new, we need feedback !

Thank you and enjoy the lab!