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**ALGORITHMS OF AUTONOMOUS
MOBILE ROBOTS**

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Content

Introduction.....	7
1 Hardware of the mobile robots.....	8
1.1 Chassis of the mobile robots	8
1.2 Chassis structures of mobile robots	10
1.2.1 Wheeled chassis	10
1.2.2 Tracked chassis	12
1.2.3 Walking chassis	12
1.2.4 Combination of previous types	12
1.2.5 Other types of motion	12
1.3 Kinematic analysis of the wheeled chassis of mobile robots.....	13
1.3.1 Differential drive.....	13
1.3.2 Ackerman chassis	14
1.3.3 Tracked or multi-wheeled chassis.....	16
1.4 Drive systems.....	16
1.5 Sensors of mobile robots	17
1.5.1 Ultrasonic sensors	17
1.5.2 Optical sensors	21
1.6 The active systems for the measurement of the distances.....	26
1.6.1 Diffuse laser distance meter - Time of Flight Method.....	26
1.6.2 Laser distance meter - triangulation method.....	27
1.6.3 Active stereovision	28
1.6.4 Interferometry	30
1.7 The fusion of information from various sensors.....	31
2. Basic algorithms and methods of mobile robots localization and navigation ..	32
2.1 Algorithms of the autonomous mobile robots.....	32
2.2 Localization of mobile robots	35
2.2.1 Location based on extraction of environment properties.....	36
2.2.2 Location by visual system.....	36
2.3 Navigation of mobile robots.....	38
2.3.1 Local navigation methods.....	38
2.3.2 The global navigation methods.....	43

2.4	Digitalization of image information	44
2.4.1	Image	44
2.4.2	Image digitalization	44
2.4.3	Sampling	45
2.4.4	Quantization.....	45
2.4.5	Coding – the formats.....	46
2.5	Colour and the colour models.....	46
2.5.1	Colour	46
2.5.2	Colour model RGB and RGBA	48
2.5.3	HSV colour model	49
2.5.4	HSL colour model.....	50
2.5.5	Conversion RGB to HSV and HSL	51
2.6	Image information processing	52
2.6.1	Image pre-processing techniques.....	53
2.6.2	Edge detection in an image	54
2.7	Image processing library.....	60
2.7.1	AForge.NET	60
2.7.2	EmguCV	61
3	Technical and program solution for autonomous mobile robots controlling in the pre-crash collision situations	62
3.1	Design and realization of autonomous mobile robot.....	62
3.1.1	Mobile robot chassis	62
3.1.2	Block diagram of the mobile robot.....	63
3.1.3	Power supply of mobile robot.....	64
3.1.4	Power module	64
3.1.5	Layout of the electronic modules and sensors on the chassis.....	65
3.1.6	Power supply module and communication protocol.....	78
3.1.7	The optical camera system MS Kinect – the sensor	80
3.1.8	Prototype of the autonomous mobile robot and CμPC	83
3.1.9	Experimental work - measurement and algorithm comparison procedures	84
4.	Implementation and evaluation of the resulting control and image processing algorithms of the autonomous mobile robot	86
4.1	Receiving information from the camera system	86

4.2	The RGB filter algorithm.....	87
4.3	The HSL filter algorithm	89
4.4	Image analysis algorithm - Region labelling algorithm of connected regions.....	91
4.5	Row boundary algorithm and handling insufficient states.....	105
4.6	Algorithms for calculating the sharp control values for drive units.....	112
4.7	Control panel of the autonomous mobile robot	121
5	Discussion	125
6	Conclusion	128
	Summary.....	130
	Súhrn.....	131
	References.....	132

INTRODUCTION

Mobile robots are increasingly used in agricultural production. Nowadays, there are many available solutions to identify obstacles with the subsequent stopping of vehicles (or mobile robots). Current solutions require the presence of a person in collision situations, which increases the cost of implementing the technological process. Proposals for autonomous mobile robots and inputs control algorithms are based on the conventional integrated sensors, and only a tiny sphere of research teams are working on a camera capturing and processing multidimensional images. So far, satisfactory navigation results and safe obstacle avoidance have not been achieved, where input information for the control algorithm is obtained from complex camera systems.

The onset of the era of computers and image digitalization, the development of the image processing and computer vision is moving fast. Research and development of algorithms aimed at understanding the image is mainly focused on technical, industrial and security applications, and only marginally agricultural work. Combining electronics, automation, image processing algorithms, and computer vision can practice as well as make equipment that will perform various agricultural work activities and tasks completely independently, without intervention, with feedback based on the image information. Such autonomous robotic systems can relieve and protect humans from monotonous and often mentally for human health, to claims of agricultural work.

At present, there are many elementary algorithms for obstructing obstacles, respectively to manage mobile robots in collision situations. However, these algorithms are only usable for a single typing operation and the ability to interact with algorithms and the common synthesis of different tasks is not currently solved. By combining image processing algorithms and algorithms for safe obstruction of obstacles (collision situations), it is possible to build a system that would be able to solve partial navigation problems, thus enabling the navigation of autonomous mobile robots between obstacles, thereby avoiding collision situations.

This publication brings new methods of image processing, navigation, localization, algorithmization and identification of specific objects that will be of importance in future practice and will contribute to the efficiency of the use of small autonomous robots in agricultural operations. This publication brings a new method proposed in image processing, navigation, localization, algorithms and identifying specific objects that will be important for future practice and will contribute to more efficient use of small autonomous robots in agricultural operations.

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