

## Sheet 11

Topic: FastSLAM

Due date: 14.07.2017

### Exercise: FastSLAM Implementation

FastSLAM is a Rao-Blackwellized particle filter for simultaneous localization and mapping. The pose of the robot in the environment is represented by a particle filter. Furthermore, each particle carries a map of the environment, which it uses for localization. In the case of landmark-based FastSLAM, the map is represented by a Kalman Filter, estimating the mean position and covariance of landmarks.

Implement the landmark-based FastSLAM algorithm as presented in the lecture. Assume known feature correspondences.

To support this task, we provide a detailed listing of the algorithm as a PDF file and a small Python framework on the course website. The framework contains the following folders:

**data** contains the world definition and sensor readings used by the filter.

**code** contains the FastSLAM framework with stubs for you to complete.

You can run the fastSLAM framework in the terminal: `python fastslam.py`. It will only work properly once you filled the blanks in the code.

- (a) Complete the code blank in the `sample_motion_model` function by implementing the odometry motion model and sampling from it. The function updates the poses of the particles based on the old poses, the odometry measurements  $\delta_{rot1}$ ,  $\delta_{trans}$  and  $\delta_{rot2}$  and the motion noise. The motion noise parameters are:

$$[\alpha_1, \alpha_2, \alpha_3, \alpha_4] = [0.1, 0.1, 0.05, 0.05]$$

How is sampling from the motion model different from the standard particle filter for localization (Exercise sheet 7)?

- (b) Complete the code blanks in the `eval_sensor_model` function. The function implements the measurement update of the Rao-Blackwellized particle filter, using range and bearing measurements. It takes the particles and landmark observations and updates the map of each particle and calculates its weight  $w$ . The noise of the sensor readings is given by a diagonal matrix

$$Q_t = \begin{bmatrix} 0.1 & 0 \\ 0 & 0.1 \end{bmatrix}$$

How is the evaluation of the sensor model different from the standard particle filter for localization (Exercise sheet 7)?

- (c) Complete the function `resample_particles` by implementing stochastic universal sampling. The function takes as an input a set of particles which carry their weights, and returns a sampled set of particles.

How does the resampling procedure differ from resampling in the standard particle filter for localization (Exercise sheet 7)?

Some implementation tips:

- To read in the sensor and landmark data, we have used dictionaries. Dictionaries provide an easier way to access data structs based on single or multiple keys. The functions `read_sensor_data` and `read_world_data` in the `read_data.py` file read in the data from the files and build a dictionary for each of them with time stamps as the primary keys.

To access the sensor data from the `sensor_readings` dictionary, you can use

```
sensor_readings[timestamp, 'sensor']['id']  
sensor_readings[timestamp, 'sensor']['range']  
sensor_readings[timestamp, 'sensor']['bearing']
```

and for odometry you can access the dictionary as

```
sensor_readings[timestamp, 'odometry']['r1']  
sensor_readings[timestamp, 'odometry']['t']  
sensor_readings[timestamp, 'odometry']['r2']
```