

K. Iagnemma • S. Dubowsky

Mobile Robots in Rough Terrain

**Estimation, Motion Planning,
and Control with Application
to Planetary Rovers**

With 58 Figures

Table of Contents

Chapter 1 Introduction	1
1.1 Problem Statement and Motivation	1
1.2 Purpose of This Monograph	3
1.3 Background and Literature Review	4
1.3.1 Rough Terrain Modeling and Estimation	4
1.3.2 Rough Terrain Motion Planning	7
1.3.3 Rough Terrain Control	11
1.4 Outline of This Monograph	13
1.5 Assumptions	13
Chapter 2 Rough Terrain Mobile Robot Modeling and Estimation ...	17
2.1 Introduction	17
2.2 Robot Kinematic and Force Analysis	18
2.2.1 Robot Kinematic Analysis	18
2.2.2 Robot Force Analysis	21
2.3 Terrain Characterization and Identification	24
2.3.1 Equation Simplification	27
2.3.2 Sensing and Implementation Issues	31
2.4 Results: Terrain Identification	33
2.4.1 Simulation Results	33
2.4.2 Experimental Results	35
2.5 Wheel-Terrain Contact Angle Estimation	39
2.5.1 Extended Kalman Filter Implementation	42
2.6 Results: Wheel-Terrain Contact Angle Identification	44
2.6.1 Simulation Results	44
2.6.2 Experimental Results	45
2.7 Summary and Conclusions	50
Chapter 3 Rough Terrain Motion Planning	51
3.1 Introduction	51
3.2 Rough Terrain Motion Planning	52
3.2.1 Step One: Rapid Path Search	52
3.2.2 Step Two: Model-Based Evaluation	57
3.2.3 Uncertainty in Rough Terrain Motion Planning	59

3.2.4. Incorporating Uncertainty in the Rapid Path Search	61
3.2.5. Incorporating Uncertainty in the Model-Based Evaluation	62
3.3 Simulation Results—Rough Terrain Planning	65
3.4 Rough Terrain Articulated Suspension Configuration Planning	70
3.4.1 Articulated Suspension Configuration Planning Problem Description	70
3.4.2 Mobility Analysis	71
3.4.3 Articulated Suspension Configuration Planning for Enhanced Tipover Stability	72
3.5 Results—Rough Terrain Articulated Suspension Configuration Planning	75
3.5.1 Simulation Results	75
3.5.2 Experimental Results	76
3.6 Summary and Conclusions	79
Chapter 4 Rough Terrain Control	81
4.1 Introduction	81
4.2 Mobile Robot Rough Terrain Control (RTC)	82
4.3 Wheel-Terrain Contact Force Optimization	84
4.3.1 Optimization Criteria	84
4.3.2 Problem Constraints	86
4.4 Results—Rough Terrain Control	87
4.4.1 Simulation Results	87
4.4.2 Experimental Results	92
4.5 Summary and Conclusions	96
Chapter 5 Conclusions and Suggestions for Future Work	97
5.1 Contributions of This Monograph	97
5.2 Suggestions for Further Work	98
References	101
Index	109