

Manipulator control by calibration-free stereo vision

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ABSTRACT

Based on the concept of object- and behavior-oriented stereo vision a method is introduced which enables a robot manipulator to handle two distinct types of objects. It uses an uncalibrated stereo vision system and allows a direct transition from image coordinates to motion control commands of a robot. An object can be placed anywhere in the robot's 3-D work space which is in the field of view of both cameras. The objects to be manipulated can either be of flat cylindrical or elongate shape. Results gained from real-world experiments are discussed.

Keywords: object grasping, calibration-free stereo vision, object- and behavior-oriented robot vision, manipulator control

1. INTRODUCTION

Grasping an object is a task which can easily be performed by human beings. During the grasping process the eyes are used to continuously obtain feedback information. Humans do not have exact knowledge of the "optical parameters" of their eyes or the "geometric dimensions" of their arms. Still they are able to coordinate arm movements fast and efficiently.

A classical approach for accomplishing a grasping process with a "seeing" robot manipulator would require a carefully calibrated mechanical and optical system. In recent years, however, different methods have been developed to control a manipulator arm, using visual information, without the need of calibration. Such systems can adapt to changes in the work conditions of the system (e.g. camera parameters, mechanical wear of parts).

[Yoshimi, Allen 1994] perform a peg-in-hole alignment. The position of the peg is controlled by an uncalibrated camera mounted at the wrist of the robot's end effector. [Hollinghurst, Cipolla 1994] move the gripper to four known positions. Using the information gained from two free-standing cameras (no mechanical connection with the robot arm) a self-calibration of the system is performed to eventually grasp an object.

A different approach to robust, adaptive and calibration-free manipulator control has been proposed by [Graefe, Ta 1995]. The key characteristic of their concept is the method of object- and behavior-oriented stereo vision. The system performs a continuous implicit calibration as a side effect of normal operation. Motion control commands are

generated directly from image coordinates. Flat cylindrical objects were grasped, regardless of their initial location in the robot's work space. Those objects have a vertical axis of symmetry and can be grasped without knowledge of the gripper orientation with respect to the object.

The method of object- and behavior-oriented stereo vision has been improved and now elongate objects in addition to flat cylindrical objects can be grasped. The following points were addressed in realizing the new algorithm:

- The same reference point of the object must be localized in the images of both cameras despite the different appearance of the object in the two images.
- The orientation of the object relative to the gripper has to be determined by the vision system.
- An additional degree of freedom of the robot, the rotation of the gripper, must be controlled to accommodate the object orientation.

2. OBJECT-AND BEHAVIOR-ORIENTED STEREO VISION

The method of object- and behavior-oriented monocular vision has been successfully applied in various applications, e.g. navigation of a mobile robot operating in a laboratory environment [Wershofen 1996]. This mobile robot has a repertoire of three basic behaviors patterns, i.e. following a wall, turning and moving towards goal points. Goal points can serve as a target when traversing open areas or may identify a docking station. The object-oriented vision system provides information about all relevant objects to complete a certain task. Important "objects" for indoor navigation include walls, junctions, goal points and obstacles in general. The task of navigating a mobile robot requires information of **different** objects to perform **different** behaviors.

In order to apply the concept of object- and behavior-oriented vision to a manipulator arm we first have to determine behavior patterns for the manipulator. As its name imposes, the main purpose of a robot manipulator is to manipulate, to handle something. When thinking about possible tasks for a robot arm we can distinguish between a manipulator mounted on a mobile basis and a stationary robot arm. The number of possible tasks for a mobile manipulator arm exceeds those for a fixed one. It may be one of the following:

- opening and closing doors
- removing obstacles/items in the pathway of the mobile base (e.g. a cleaning robot)
- interacting with the environment (e.g. calling an elevator by pressing the request button)
- grasping an item at point A and bring it to point B (e.g. distributing mail in an office)
- assembling of goods (with or without tools)

For a stationary robot manipulator the tasks to be executed are mainly pick-and-place operations (e.g. removing items

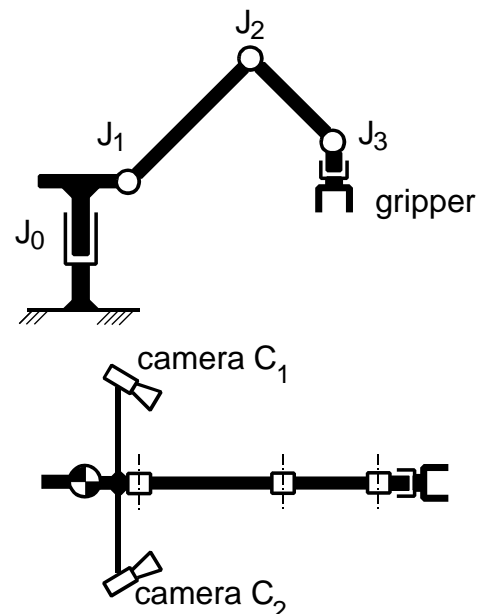


Figure 1

The robot arm joints and the camera arrangements

from a production line) or tasks where high accuracy is needed to produce high quality output (e.g. welding seams for a car). In those cases the manipulator follows a predefined sequence of commands.

Using visual feedback during operation can eliminate the need of calibration. The system, moreover, can adapt to changing parameters in the working environment, still allowing a high degree of accuracy.

To perform all tasks mentioned above, only a single behavior pattern is necessary. It is common to all tasks that the end effector has to be positioned at a certain position in 3-D space, either opened or closed. For the assembly task, multiple calls of this behavior pattern might be necessary. The vision system has to provide information about **different** objects to perform the **same** behavior. A typical pick-and-place operation has been used to validate the method of object- and behavior-based stereo vision. The aim is, to grasp different types of objects regardless of their position and orientation. In Figure 1, the position and viewing direction of the cameras can be seen. The cameras are mounted on a metal bar and participate in the rotation of joint J_0 . The manipulator arm used in our experimental setup has five degrees of freedom (J_0 - J_4). To grasp an object, the vision system has to provide information about the end effector and objects within the work space of the manipulator.

3. GRASPING OBJECTS

3.1 Approaching the object position in 3-D space

The position of both the end effector and the object are modeled as a single point in 3-D space. Objects are grasped from above to avoid collisions with other objects that might be in the work space of the robot. Therefore, joint J_3 is always controlled in such a way that the gripper is in a vertical orientation (see Figure 1). The remaining four independent degrees of freedom are controlled as follows:

To reach an object O , first the control words for joints J_1 and J_2 are modified by a small amount. The resulting displacements in the images are measured and used for subsequent generation of motion control commands for the manipulator. Controlling the joints J_1 and J_2 based on the image displacements of camera C_1 would result in a motion of the gripper towards O_1 , the projection of O onto the work plane as seen by C_1 . Similarly, motion control based on

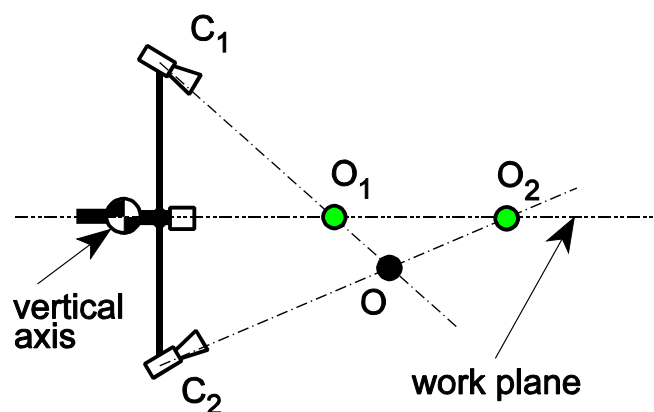


Figure 2

Disparity of apparent object locations O_1 and O_2 , corresponding to an object O outside of the robot's work plane (object modeled as a single point)

the camera C_2 will cause a motion of the gripper towards O_2 (see Figure 2). The two sets of motion control words will only be identical if O is located in the work plane. The control word for joint J_0 is modified until the object is in the work plane, then either one of the cameras may be used to compute subsequent control words for the joints J_1 and J_2 in order to reach the object. This results in an iterative movement of the end effector towards the object position.

Conventional stereo vision measures the disparity between corresponding features in two images in order to determine the coordinates of these features in Euclidian space. In contrast to this, in our realization of stereo vision the disparity between corresponding objects in two images is measured in order to determine the coordinates of the objects in the control word space of a manipulator arm. Therefore, computationally expensive coordinate transformations are avoided.

3.2 Objects with a vertical axis of symmetry

Flat cylindrical objects require knowledge only about the object position relative to the gripper expressed in image coordinates. The appearance of the object is due to its vertical axis of symmetry, almost identical in the images captured from both cameras. The projection of the object onto both image planes is of elliptical shape. To grasp such objects, it is sufficient to control the end effector in such a way as to make the position of the open gripper coincide with the center of the object in both images and then close the gripper.

If the height of a cylindrical object exceeds the height of the end effector it is likely that the gripper collides with the object when the object is grasped from above. A different strategy is necessary to grasp it from another direction. This problem is subject of ongoing research and will not be addressed in this paper.

3.3 Elongate objects

Grasping elongate objects needs information about the spatial position and orientation of the gripper with respect to the object. The image of an elongate object differs substantially in the two images. To apply the control concept as described above, a reference point must be assigned to the physical object, not to the images of the object. Extraction of the object position in the images of both cameras must refer to this reference point of the real object. The following criteria can be used to define such a reference point:

- the reference point must be visible in both images
- low-level image processing routines must be able to extract the reference point, although the images of objects without a vertical axis of symmetry can be totally different

the reference point should be assigned to that part of an object which is most suitable for grasping with the

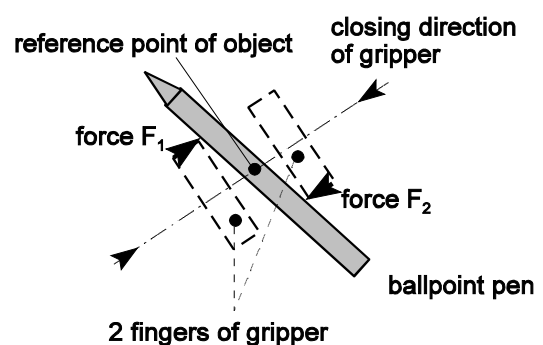


Figure 3

Misaligned gripper; forces F_1 and F_2 cause a non-compensable torque

available end effector

- the end effector of the manipulator arm should be able to grasp the object at the reference point without changing the position or orientation of the object

The gripper approaches the reference point of the object as described in section 3.1 (make gripper position coincide with reference point of the object). The position of the physical end effector is described by its tool center point (TCP). It is an imaginary point that lies along the last wrist axis at a user specified distance from the wrist [Koren 1985]. Here the TCP is the spatial center between the gripper jaws. A ballpoint pen serves as the object to be grasped. The reference point of the ballpoint pen lies on its rotational axis at a distance of half the object length from where the rotational axis intersects the object. The image processing algorithms, however, cannot extract spatial information from a two dimensional image. Therefore, tool center point and reference point of the object are approximated in the images by the centroids of their projections onto the image plane of the left and right camera image, respectively.

In order to align gripper and object, information about the current orientation of the gripper and the object has to be extracted from the images. Ideally, the closing direction of the gripper is perpendicular to the object surface. Our gripper is a two fingered parallel jaw type. The robot fingers consist of small flat plates. An optimal grasping of an elongate object requires an exact alignment of the gripper with respect to the object. Figure 3 shows an example of a misaligned gripper. The position of the end effector has been controlled in such a way that the tool center point of the end effector coincides with the reference point of the object. When the gripper closes, the object is first touched at two points. The two forces F_1 and F_2 result from the movement of both fingers of the gripper. These forces cause a non-compensable torque and make the object rotating around its reference point. When the object rotates the contact points finally become contact areas. If

$$\sum F = 0 \quad \wedge \quad \sum M = 0$$

the rotation stops and the ballpoint pen has been grasped. Other forces, such as friction, have intentionally been omitted here to simplify the description of misalignment. To align the end effector with the object, joint J_4 has to be controlled appropriately. Joint J_4 refers to the rotation of the gripper around its vertical axis. From its zero position the gripper can be rotated in the range of -180° to $+180^\circ$. Thus, two possible control words exist which make the gripper aligned with the object. For efficiency reasons, the desired solution requires the smaller change of this joint angle.

Figure 4 and 5 show a typical scene from the left and right camera, respectively. The object to be grasped is a ballpoint pen which is placed on a support of unknown height with the object's main axis approximately parallel to the table. Its position in the images is marked by a white point.

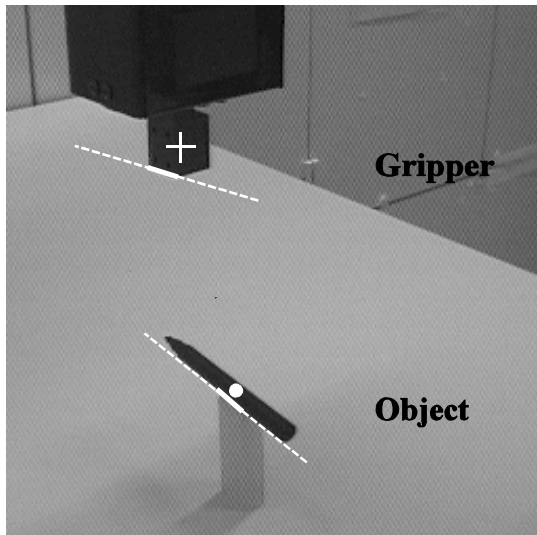


Figure 4
Snapshot from the left camera

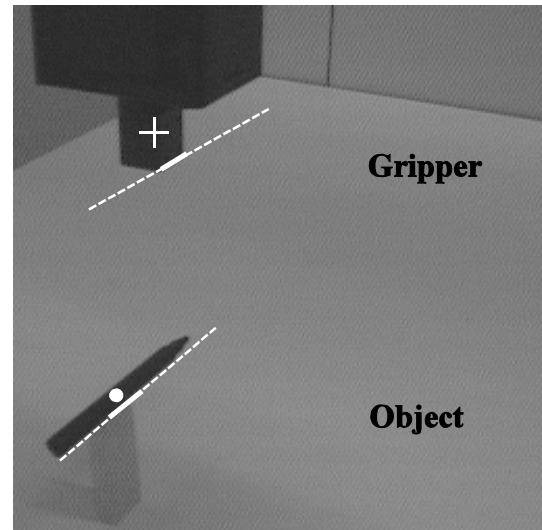


Figure 5
Snapshot from the right camera

The positions of the closed gripper in the images are marked by a white cross. The ballpoint pen is placed in such a way that no gripper rotation is necessary when the object has to be grasped. In 3-D space object and gripper are exactly aligned. The orientation of gripper and object in the images are shown by dashed lines in Figure 4 and Figure 5. The highlighted solid line sections correspond to the surface boundaries which are used to determine the relative orientation of gripper and object. In order to measure the orientation of the object in the images the slope of the outline is extracted close to the reference point. Having a vision system without distortion, the slope of the line sections in the images would be identical if the orientation of gripper and object are the same in 3-D space. It can be seen that the slope of the object boundaries in the images, indicated by the dashed lines, are not the same, despite of correct alignment. This is mainly because of the distortion of the cameras (e.g. pincushion distortion). Line sections of contours will have an identical slope when they are compared in the same area of an image. When the end effector is moved towards the object, their projections in the camera images will get closer, too. Before gripper and object projection merge in either image, movement towards the reference point is stopped. A final control word is computed which makes the tool center point and the reference point of the object coincide. The information from either image suffices to assure parallel alignment. The orientation of the relevant parts of gripper and object contour is measured in different sections of an image, causing an error in the alignment process.

4. IMPLEMENTATION

4.1 System overview

A five degree of freedom (DOF) articulated robot arm (Mitsubishi Movemaster 2) is used for picking up objects (Figure 6). Two cameras are mounted on opposite sides of the robot arm. The video cameras participate in the rotation of the arm around its vertical axis. A flat cylindrical object can be seen in front of the robot arm.

The images from the two cameras are processed by an object-oriented vision system [Graefe 1989] based on two frame grabbers, each containing a TMS320C40 Digital Signal Processor. The robot control program receives the information about the position and orientation of gripper and object. According to the approach of object- and behavior-oriented stereo vision, it computes appropriate motion control commands for the manipulator. Both gripper and object are dark and the background is uncluttered. Uncontrolled ambient light is used to illuminate the scene.

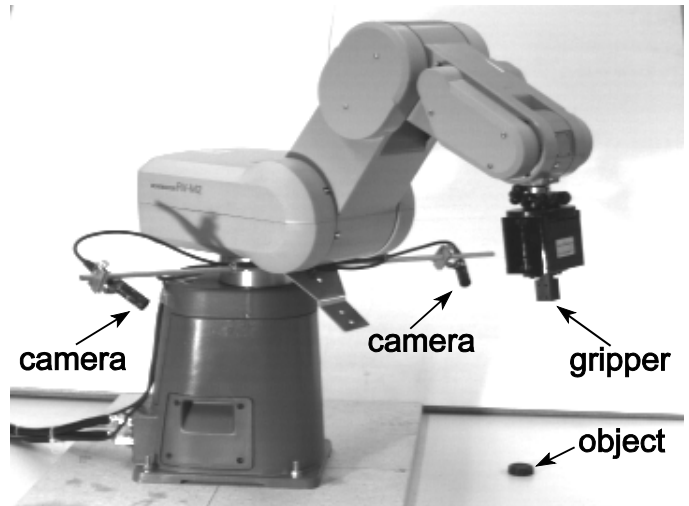


Figure 6
The Mitsubishi Movemaster RV-M2 with mounted cameras

4.2 Rotation of the end effector

Two different types of objects can be grasped; elongate objects and flat cylindrical objects. The objects are distinguished by their height and width in the images. The reference point of the ballpoint pen and the TCP of the end effector are approximated by the centroids of their projections onto the image plane of the left and right camera image, respectively. Gradient-based edge detectors are used for feature extraction. To determine the orientation of the end effector relative to the ballpoint pen in the images, two contour points from each line section would theoretically suffice. To make the system more robust, at least five contour points are extracted from the relevant outlines. The extracted points are fitted to straight lines by linear regression. We measure the orientation of the object near its reference point. This is the position where the parallel jaw gripper will grasp the object. Depending on the difference of the actual orientations of end effector and object in the images, joint J_4 is controlled as follows:

$$\Delta \alpha_4 = \begin{cases} 5^\circ & \text{if } \varphi \geq 15^\circ \\ 1^\circ & \text{if } 5^\circ \leq \varphi < 15^\circ \\ 0,5^\circ & \text{if } \varphi < 5^\circ \end{cases}$$

α_4 is the joint angle of joint J_4 and φ denotes the difference of the contour slopes in an image expressed in degrees. Information from either camera is sufficient to align the gripper with the object. If the relevant data has been

extracted from both images we determine ϕ by calculating the mean value.

5. EXPERIMENTS AND RESULTS

A ballpoint pen has been used for the experiments. It was about 9.5 cm in length and approximately 0.8 cm in diameter. The object was placed on supports of unknown height. Its main axis was approximately parallel to the surface where it was placed. A series of grasping experiments has been performed. The ballpoint pen was successfully located and grasped by the manipulator regardless of its initial position and orientation. To show the adaptability of the system, the viewing directions of the cameras were changed in a way unknown to the system. As expected, the system continued without degradation.

A complete grasping process can take up to 45 seconds, depending on the initial position and orientation of the object. Aligning gripper and object contributes with up to 10 seconds. This long grasping time is mainly due to the sequential execution of motions: (1) make reference point of object coincide with work plane, (2) approach object within work plane, and (3) rotate end effector. Moreover, the system waits until each motion of the robot has stopped before the next command is issued.

In the grasping experiments, the gripper was measured to be parallel with the object in the image, but actually closing the gripper caused non-compensable torques. The object's orientation is changed when the gripper is closed. This misalignment of the end effector was expected, as we do not measure the slope of the relevant object boundaries in the same area of the image.

Another potential error source is the lighting. As we are interested in robots operating in real world, we use uncontrolled ambient light. When carrying out the experiments, the slope of the contour of gripper and object was sometimes measured at the shadow of the boundaries, rather than at the boundaries itself.

The manipulator has been instructed to place a ballpoint pen at a certain position on the table. The orientation was

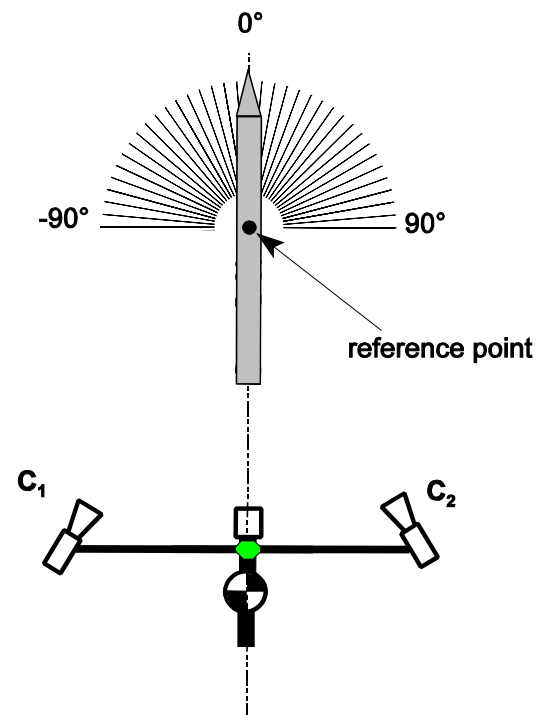


Figure 7
Sketched experimental setup with enlarged object; (top view)

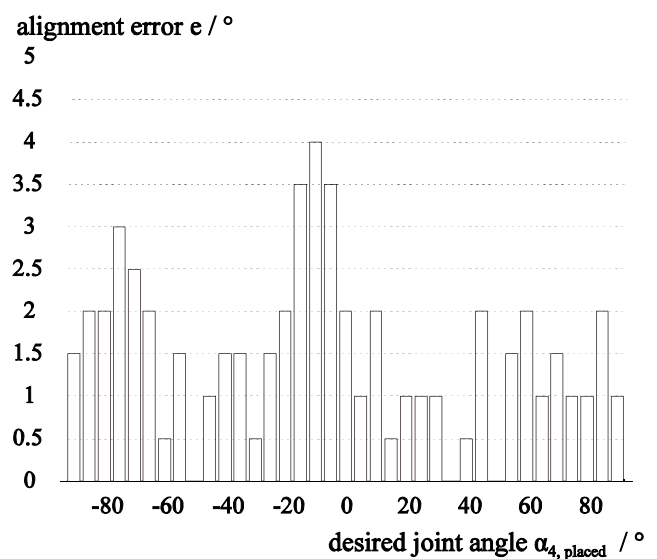


Figure 8
Misalignment of end effector

commanded from -90° to $+90^\circ$ in steps of 5° as shown in Figure 7. Each time the object was placed with a different orientation, the manipulator moved to a predefined position above the object and the grasping process was initiated. When the end effector was measured to be in parallel with the object, the current joint angle of J_4 was read from the robot control box, and finally the object has been grasped. The resulting error e is determined by

$$e = | \alpha_{4,placed} - \alpha_{4,controlled} |$$

where $\alpha_{4,placed}$ denotes the joint angle of J_4 when the object was positioned, and $\alpha_{4,controlled}$ the corresponding joint angle after gripper and object were measured as parallel in the images. Figure 8 shows the results for this experiment. A typical error in the range of 2° has been obtained. This misalignment is acceptable, because of the inherent camera distortions and the problems with shadows when extracting relevant features from the images. Improvements could be achieved by using dedicated light sources, and a camera model with correction factors. Our system, however, is developed to operate within a real-world environment.

6. SUMMARY AND FUTURE WORK

A method has been introduced which allows a robot manipulator to grasp two different types of objects. It automatically identifies the type of object detected within the work space and initiates all necessary operations to grasp it. As motion control commands are generated directly from image coordinates, neither the vision system nor the manipulator need to be calibrated. The system adapts during normal operation to all necessary parameters. One rotational degree of freedom of an object has been covered by including the rotation of the end effector around its vertical axis into the control concept of the system. Real world experiments have been performed to validate the concept of object- and behavior oriented stereo vision. The following results have been achieved with a manipulator arm which characteristics were completely unknown to the system and with uncalibrated cameras:

- Objects of elongate shape placed anywhere in that part of the robots work space that was observed by the camera were located and grasped.
- Operation of the robot continued without degradation even after the viewing direction of the cameras was arbitrarily changed in a way unknown to the system.

This implementation serves as the basic behavior pattern "Grasp Object" which is common to a variety of manipulator tasks. Further research will focus on grasping objects in an arbitrary position and orientation. As the position and orientation of any object can be described by three translational and three rotational parameters, at least a 6-DOF manipulator arm will be required.

To decrease the time needed for grasping an object, a long term memory is currently being implemented. Knowledge gained from previous grasping processes is accumulated and stored. Reuse of this knowledge then significantly improves the system performance.

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