Virtual Autonomous Navigation Environment

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Mr. Christopher Cummins

Geotechnical and Structures Laboratory

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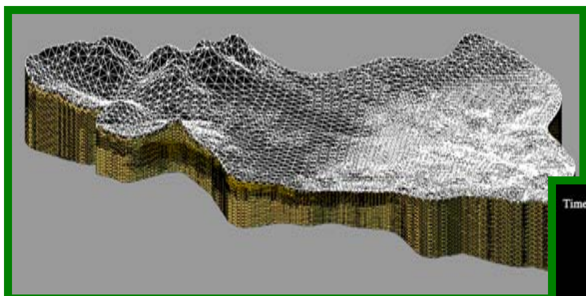
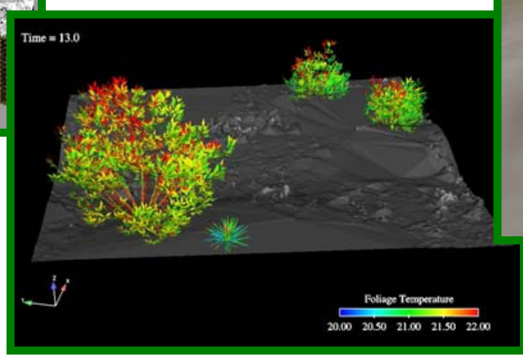
VANE Research Focus

- **Integrate vehicle mobility, ground physics, terrain physics and sensor response models into a High Performance Computing computational testbed to facilitate virtual testing of UMS for autonomous navigation performance**





VANE Simulation Testbed

Purpose:
- **Represent mechanical system interactions with the CTB**
- **Realistic movement**
- **Provide an interface for mechanical systems and sensor models**
- **Allow easy configuration of mission scenario**

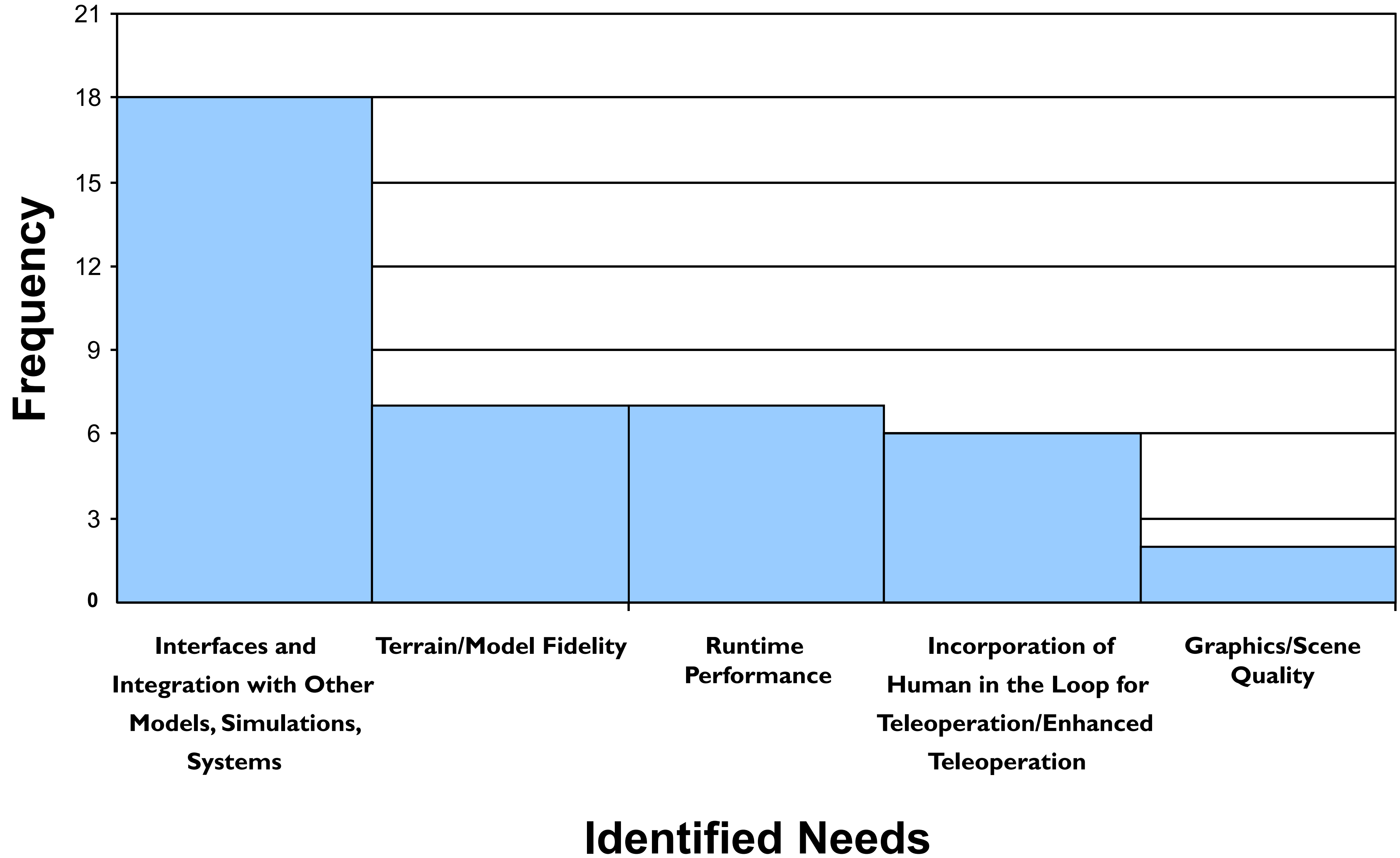
Results:
- **JAUS Compliance**
- **Dynamics engine for VANE simulation**
- **Simultaneous viewing of sensor output, vehicle mobility, and ANS**
- **Mission rehearsal and playback**

Payoff:
- **Interaction with guest JAUS compliant subsystems.**
- **Faster debugging of components**
- **Viewing options for output data**

Schedule

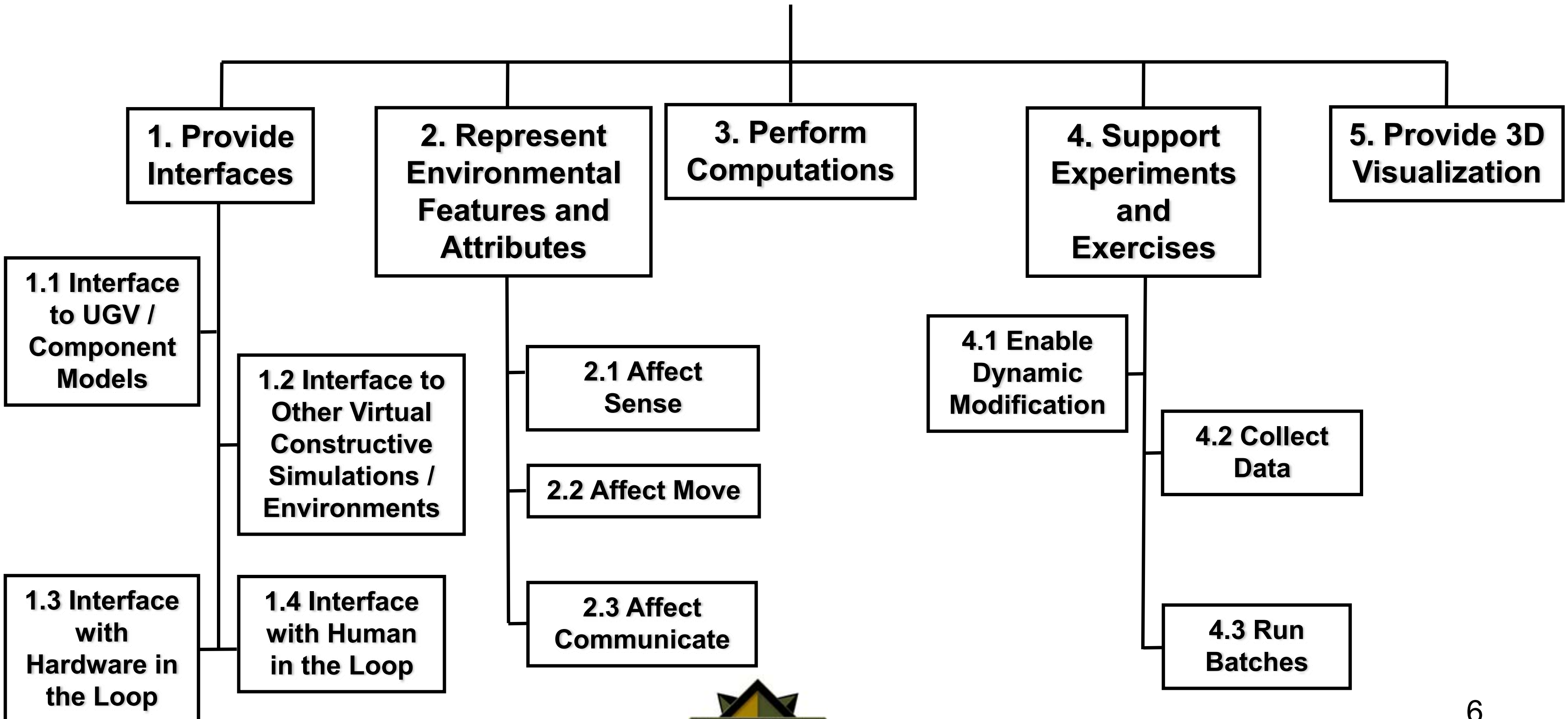
Milestones	**FY08**	**FY09**	**FY10**	**FY11**
Mechanical systems				
UI design and construction				
CTB Environment Interface				
JAUS Applications				

Major Needs Identified by Stakeholders



Functional Analysis

Objective: Provide a high-fidelity, high-resolution environment for assessment of UGV systems and subsystems across concepts, designs, and operations to achieve implementation of the best systems.

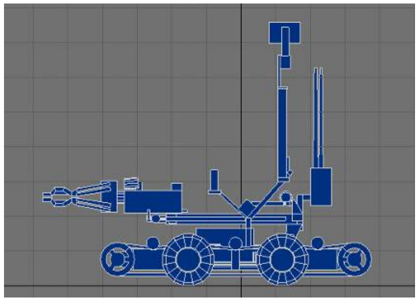


Common Open Architecture

- **Open Architecture Characteristics:**
  - Based on Open, Publicly Available Specifications — Preferably Maintained as Standards by a Consensus Process, e.g. By an Internationally Recognized Governing Group
  - Well-defined, Widely Used Non-Proprietary (Standard) Interfaces, Services and Formats
  - Durable (Stable or Slowly Evolving) Component Interfaces That Facilitate Component Replacement and Addition of New Capabilities
  - Upgradeable Through Incorporation of Additional or More Capable Components With Minimal Impact on the System

Vehicle/Object Modeling

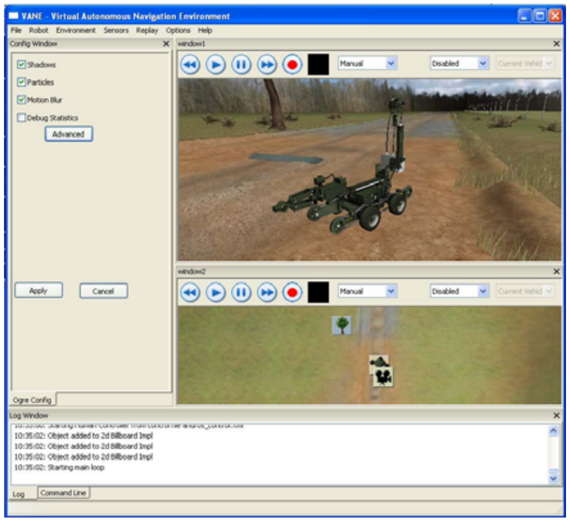
- **Objects exist in several contexts**
  - Collision geometries
  - Joint constraints
  - GUI visualization
  - Sensor detection



- **Every object needs to make sense in each of these contexts.**
- **The testbed manages the objects so that the contexts can be resolved to one entity**
- **Some object data can be manipulated graphically though the testbed.**

GUI Design

- OGRE rendering engine
  - Object Oriented Graphics Rendering Engine
  - Open source
  - Object Oriented for manageability
  - Includes shadow, shaders, object and scene loading, and other functions to reduce programming time.
  - Portable
  - DirectX/OpenGL
- WXWidgets interface
  - Free software license
  - Powerful
  - Easy to program
  - Multiple windows
  - Portable
  - Uses the native GUI to reduce the learning curve



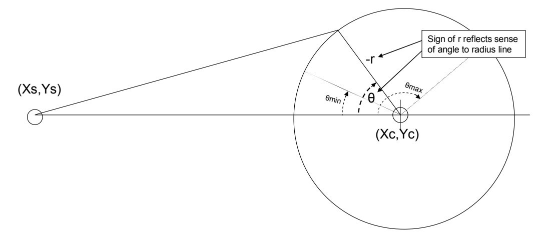
Ridged Body Dynamics Simulation

- ODE (Open Dynamics Engine)
  - Open Source
  - Mature
  - Widely used
  - Fast or Accurate
  - Portable
- Different levels of accuracy are possible
  - Allows for different uses for the VANE test bed depending on the mission.
- The option exists if replacement of ODE with other physics solutions such as PhysX is desired.
- ODE has an active user base to help in solving programming issues and to ensure continuing updates.

Robot picking an object

Actuator Modeling

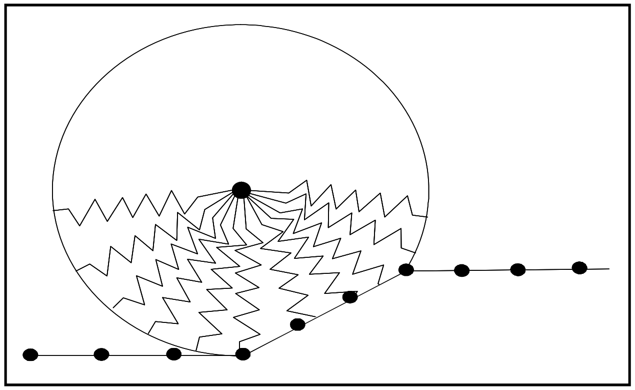
- **Actuator joints and motors**
  - **Linear Actuators**
  - **Rotational Servos**
  - **Lever Arms**
  - **Motors/Engines**



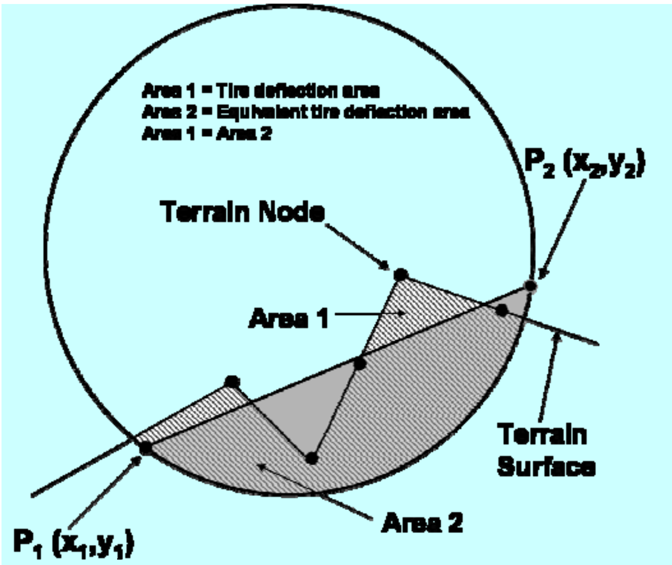
- **The joints use either a force or a speed solver.**
  - **The speed solution is used on joints that are not torque limited. This allows for easy and accurate modeling of speed limited joints.**
- **Lever arm linkages are modeled internally to the actuator to decrease degrees of freedom in the physics solver.**

Ground Contact Interface

- The terrain is represented by a series of nodes
- The forces on the wheel are computed using the continuous spring tire model
- The traction element sinkage is determined and used to calculate the sinkage at the current time step that applies to each terrain node in contact with the traction element



Continuous spring tire model and terrain nodes



$$S_c = (V \times T)/C \times S$$

S = Predicted total sinkage (in) for entire wheel
C = Chord Length (in) from P1 to P2
T = Time step (sec)
V = Vehicle's instantaneous velocity (in/sec)
S_c = Sinkage (in) this time step

Terrain Generation

- **Conversion to formats appropriate to dynamics and visualization**
  - **High resolution for dynamics modeling**
  - **Low resolution for GUI display**
- **The Terrain formats allow for paging of large data sets.**
- **The formats also allow for easy deformation of the terrain by the soil sinkage models.**

Simulated and Real Environments

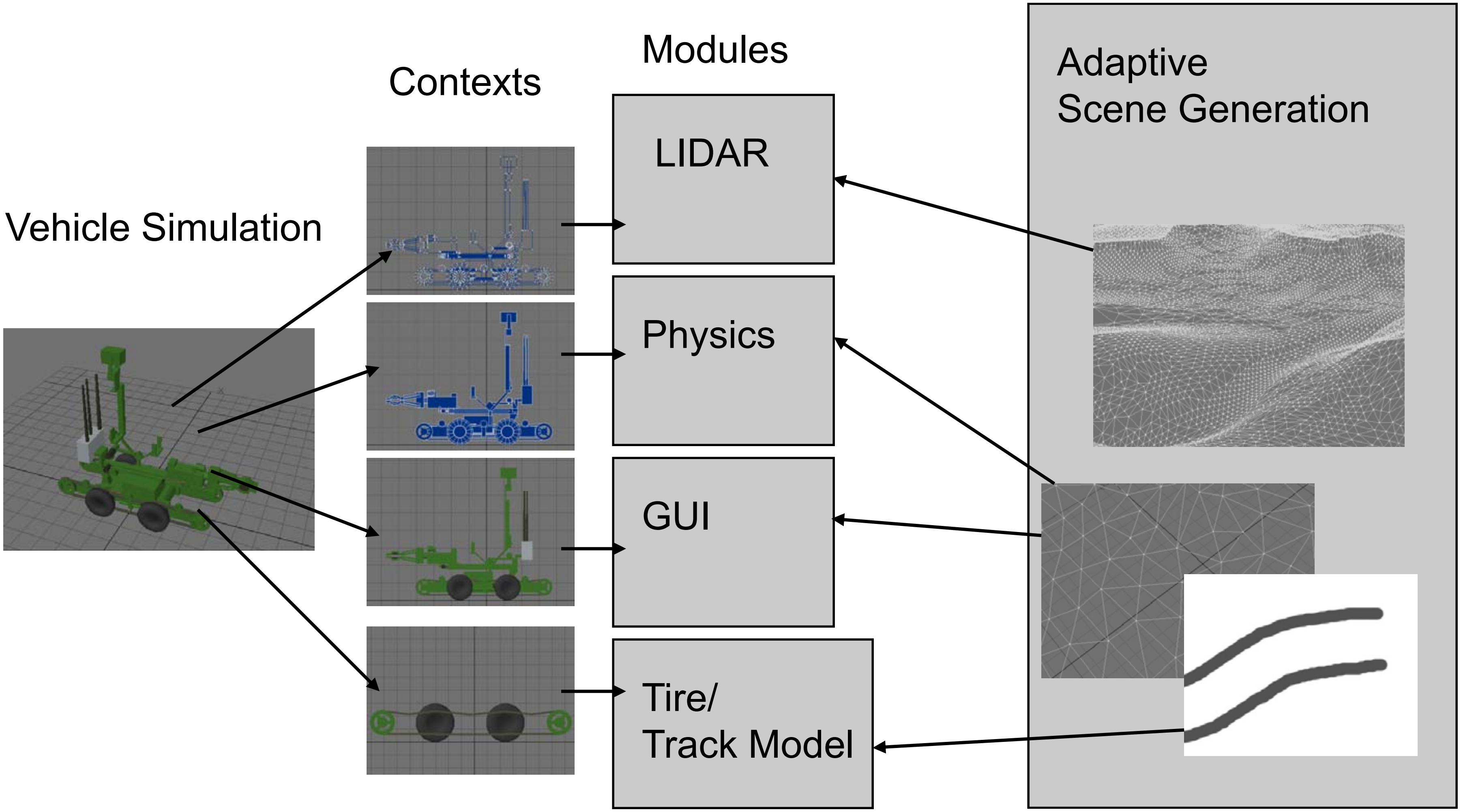
Operating over scanned terrain

Path Forward

- Operator Control Unit (OCU) construction
- Interaction between sensor models and vehicle simulation
- Easier integration of terrain into dynamics engine
- Importing of larger data sets

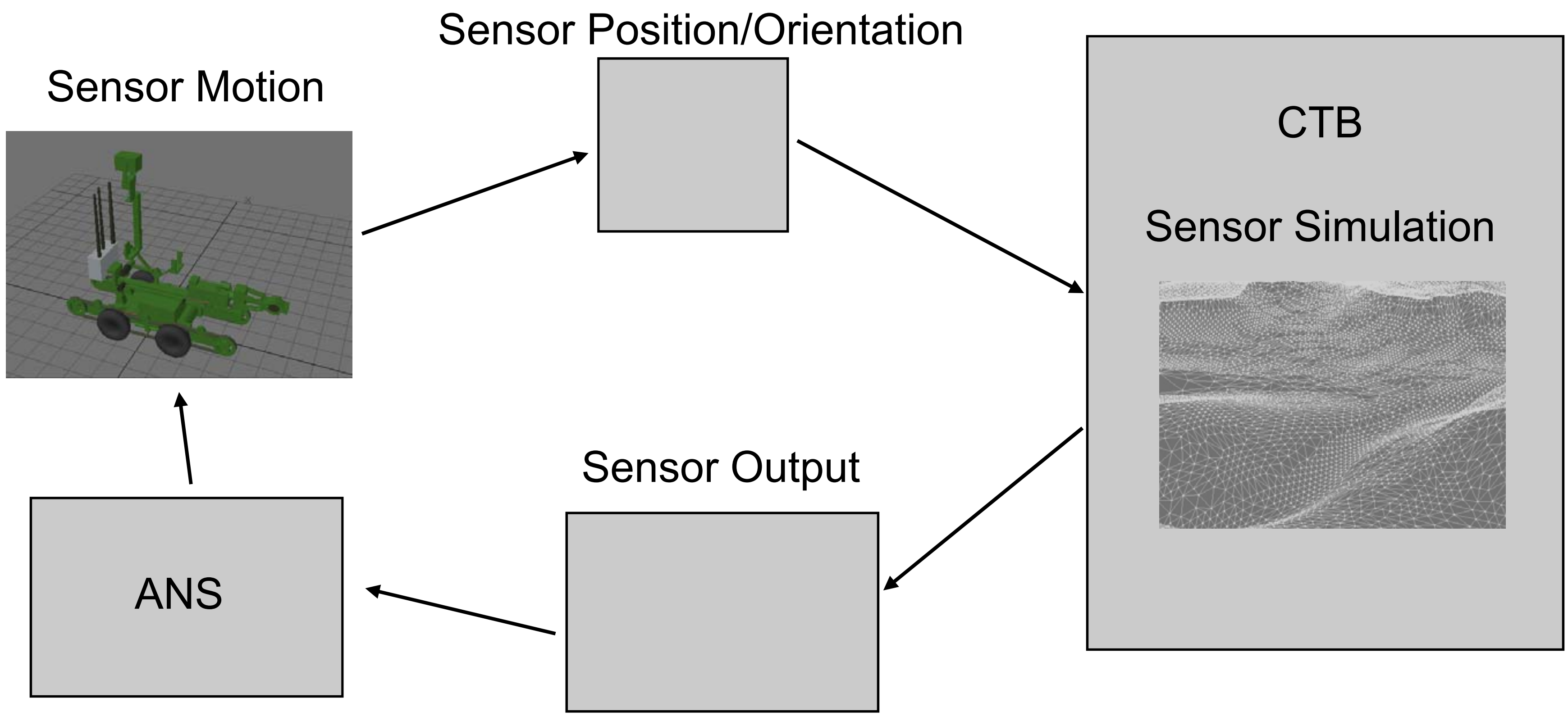
Path Forward

Testbed / CTB interaction



Path Forward

Testbed / CTB interaction



VANE Simulation Testbed

- **Demonstration of the VANE Dynamics**