Sheet 7
Topic: Grid Maps
Due: December 14, 2017

Exercise: Occupancy Mapping Algorithm Implementation

Implement the occupancy grid mapping algorithm as presented in the lecture. To support this task, we provide a small Octave framework on the course website. The framework contains the following folders:

- **data** contains the recorded laser scans and known robot poses at each time step.
- **octave** contains the grid maps framework with stubs to complete.
- **plots** stores the resulting images.

The below mentioned tasks should be implemented inside the framework in the directory **octave** by completing the stubs:

- Implement the functions in `prob_to_log_odds.m` and `log_odds_to_prob.m` for converting between probability and log odds values.
- Implement the function in `world_to_map_coordinates.m` for converting the \((x, y)\) world frame coordinates of a point to its corresponding coordinates in the grid map. You might find the Octave functions `ceil` and `floor` useful.
- Implement the function in `inv_sensor_model.m` to compute the update of the log odds value of each cell in the map for a particular laser scan measurement.

After implementing the missing parts, you can run the occupancy grid mapping framework. To do that, change into the directory **octave** and launch Octave. Type `gridmap` to start the main loop (this may take some time). The script will produce plots of the state of the resulting maps and save them in the **plots** directory. You can use the images for debugging and to generate an animation. For example, you can use ffmpeg from inside the plots directory as follows:

```
ffmpeg -r 10 -i gridmap_%03d.png -b 500000 gridmap.mp4
```

Figure 1 depicts the example images of the resulting maps using grid sizes of 0.5 m and 0.1 m.

Some implementation tips:
• Use an inverse sensor model corresponding to laser range finders (see lecture slides). The corresponding \( p_{\text{free}} \) and \( p_{\text{occ}} \) values are specified in the gridmap.m script. Use \( p_{\text{occ}} \) to update the occupancy value of cells that laser beam endpoints hit and \( p_{\text{free}} \) for all other cells along the beam. Use the function robotlaser_as_cartesian.m to compute the Cartesian coordinates of the endpoints of a laser scan. The provided bresenham.m function can be used for computing the cells that lie along a laser beam in map coordinates.

• Compute all occupancy value updates in log odds (not probabilities) so they can be added directly to the map.

• Test your implementation with a grid size of 0.5m. Once you are satisfied with your results, you can run the algorithm with an increased resolution (e.g. 0.1m), as this will take considerably more time.

• While debugging, run the algorithm only for a few steps by replacing the for-loop in gridmap.m by something like for \( t = 1:10 \).

• Many of the functions in Octave can handle matrices and compute values along the rows or columns of a matrix. Some useful functions that support this are \( \text{sum}, \text{log}, \text{sqrt}, \text{sin}, \text{cos} \), and many others.

Figure 1: Examples for the final result of the occupancy mapping algorithm.