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Autonomous Robotic Stone Stacking with Online next Best Object Target Pose Planning

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Abstract—Predominately, robotic construction is applied as prefabrication in structured indoor environments with standard building materials. Our work, on the other hand, focuses on utilizing irregular materials found on-site, such as rubble and rocks, for autonomous construction. We present a pipeline that detects randomly placed objects in a scene that are used by our next best stacking pose searching method employing gradient descent with a random initial orientation, exploiting a physics engine. This approach is validated in an experimental setup using a robotic manipulator by constructing balancing vertical stacks without mortars and adhesives. We show the results of eleven consecutive trials to form such towers autonomously using four arbitrarily in front of the robot placed rocks.

I. INTRODUCTION

Over the last decade, robotics has been introduced to architectural construction not only for safer and more efficient construction, but also for exploring diverse forms [1]. However, there are still intensive manual labor works involved for on-site assembly of these components [2].

Digital fabrication has explored applications of autonomous robots in on-site operation scenarios [3], but are restricted to build with regular materials. Building structures with irregular shaped objects was presented in [4], however they apply glue to increase stability. To reduce the environmental impact we aim to use such material without additional adhesives, to build dry-stack compositions. Therefore, our work focuses on developing an automated fabrication process using irregular objects, which are not processed but found on-site.

As a case study, discrete rigid elements, such as stones or concrete rubble, are targeted as a building material. Our goal is to construct a balancing vertical tower with found objects, while maintaining the structure in static equilibrium using a robotic manipulator. To achieve this, we developed a holistic work-flow including precise object detection, motion control, and planning the next target pose (see Figure 1). As part of this work-flow, we describe an algorithm suggesting stable poses for stacking, validated by an implementation of this autonomous stacking work-flow in a real-world experiment. Due to the instability of vertical tower, it is natural to observe errors between a desired target pose and an actual stacked pose. Thus, the work-flow puts emphasis on the resultant pose evaluation and a dynamic re-planning of the target pose.

This paper makes the following contributions regarding handling irregularly shaped objects:

– a pose searching algorithm considering structural stability using a physics engine
– an object detection pipeline
– an autonomous system for constructing balancing vertical towers using a manipulator

II. RELATED WORK

Research in architecture and digital fabrication investigates novel production techniques in which material behavior is linked to fabrication and assembly tasks [5]. Recently, it has...
been shown that robots bring new capabilities to construction sites, an uncontrolled environment full of uncertainties [3]. Whereas some works, like [6], show how to localize a mobile robot in such an environment, our work focuses on handling building materials of arbitrary shape, such as found irregularly shaped stones. The use of such objects reveals the following challenges. Firstly, individual object instances need to be identified. Secondly, grasping and stacking poses are not obvious, requiring a novel algorithm to pick a ‘good’ next pose among infinitely many. Thirdly, the stacking task may be performed in unstable situations; for example vertical tower stacking in our case, requiring recurring structural evaluation and target re-planning after each object placement.

Computational structural analysis methods have been explored with rigid discrete elements, such as simple brick-like geometries. Livesley [7, 8] set a basis of a numerical method for limit analysis of discrete rigid block structures. Block and colleagues employed graphical statics in interactive design tools with structural analysis feedback [9], and Whiting et al. [10] extended the limit analysis by Livesley to design a guidance system by adding infeasibility metrics. While these works analyzed a static equilibrium of given geometric configuration with obvious geometric contact surfaces (or support polygons), in our case with irregularly shaped elements, we need to start from contact detection, which is a core function of physics engines, and then acquire a contact surface.

From an architectural design motivation, simulation with physics engine has been explored by Nielsen et al. [11] but their construction input was to place the next stone at the lowest possible location. As for design with irregularly shaped objects, Lambert and Kennedy developed an application for guiding masonry construction with a geometric packing algorithm in two dimensional convex shapes, but it is limited to two dimensional tiling [12].

Humans synthesize the Center of Mass (CoM) position and the support polygon to infer the stability of objects [13]. On the other hand, physics engines, such as Open Dynamics Engine (ODE), have been used for evaluating structural stability of object compositions [14]. Similarly, our algorithm employs a physics engine to extract the CoM position and dynamic characteristics, as well as the contact points between the irregularly shaped objects.

Integrated autonomous systems dealing with object detection and picking these objects with robotic arms have been proposed for industrial applications [15], [16]. These works have successfully detected irregularly shaped stone-like objects for geometric packing, but are limited to place these objects in containers, and hence, did not need to consider structural stability.

III. OBJECT DETECTION

Before starting with the stacking algorithm, we need to find the objects in the scene. Additionally, during the course of the object stacking, we want to be able to track the locations of the objects. In the scope of this work, we are only considering pre-scanned (the scanning method is described in Section V) models of the objects to be detected in the scene. Therefore, we present an object detection pipeline that consists of the following steps. We start by extracting 3D keypoints from raw point clouds of an RGB-D sensor. These keypoints are then described using keypoint descriptors and matched to keypoints from a pre-scanned object in a descriptor matching step. Using these matches and a clustering step, we find an initial alignment of the scene and the pre-scanned object, which is then refined by applying an Iterative Closest Point (ICP) algorithm. As a final step of the object detection pipeline, we verify that we have enough inlier points by applying the identified pose transform of the object to the scene.

Keypoint Extraction and Description

From an RGB-D sensor we get a scene point cloud $P_C$, in camera frame $C$. To get keypoints, we used two methods, a simple voxel based subsampling, as well as the Point Cloud Library (PCL) implementation of Intrinsic Shape Signatures (ISS) [17], which can not only describe the keypoints, but also used as a keypoint detector. Besides the ISS descriptor we tested two additional descriptors, namely the Fast Point Feature Histogram (FPFH) descriptor [18] and the Rotational Projection Statistics (RoPS) descriptors [19]. Here, the RoPS descriptors were giving us the best results in the matching step, at a slightly higher computational cost.

Descriptor Matching and Clustering

We compare a keypoint $k_{C,scene}$ of a scene point cloud with a keypoint of a point cloud of a pre-scanned object $k_{O,object}$ in object frame $O$. To find a pair of corresponding keypoints $k_{C,scene}$ and $k_{O,object}$, we set up a kd-tree in descriptor space to find the nearest neighbors. Then we use an approach, presented in [20], to verify that the matched keypoints are geometrical consistent. We select the $b$ best transforms $T_{O,j,matching}$, $j \in \{1, \ldots, b\}$ that give the most geometrical consistent matches. The transforms $T_{O,j,matching}$ project the object point cloud $P_{O,object}$ into the camera frame $C$.

Transform Refinement and Verification

Using an ICP step we refine these transforms $T_{O,j,matching}$ to get better alignments of the two complete filtered point clouds $P_{C,scene}$ and $P_{O,object}$. We denote these refined transforms by $T_{O,j,refined}$. In a last step, we check for the inlier ratios of the transformed point clouds and we then select the one which has the highest ICP score, given that we have an inlier ratio of the model points larger than a threshold value; in our application we set this threshold value to 20% resulting in the final transform $T_{O}$.

Object in Robot Arm Frame

To transform the point cloud of the localized object $P_{O,object}$ into the robot arm frame $R$, we apply the previously detected best transform $T_{O}$, a fixed pre-calibrated transform $T_{TC}$ from the camera frame $C$ to the robot arm tooltip frame.
The best pose for object \( o \). The valid pose search subroutine is described in Algorithm 2 and the cost calculation in Algorithm 3. The gradient descent sub-routine is further depicted on the right.

\[ T_i \] and the transform given by the robot state \( T_{RT} \) between the robot arm frame \( R \) and the tooltip frame \( T \):

\[
P_{R,\text{object}} = T_{RT} \cdot T_{TC} \cdot T_{CO} \cdot P_{O,\text{object}}.
\] (1)

**IV. Pose Searching**

The global goal is to construct a vertical tower consisting of irregularly shaped objects from a subset \( S \) of available objects \( o_i \in S \subseteq O \), where \( O \) denotes the complete set of given objects. Within the set \( S \), we want to find the best object and its target pose. The search space is twofold: discrete object space and continuous pose space. To find a stable pose on a vertical stack, our pose searching method places each object \( o_i \) on the top object of the existing stack in a dynamic simulation using a physics engine. For evaluating each object’s ‘goodness’ with a certain pose \( p_i \), we introduce a cost function that maximizes the support polygon \( S_j \)’s area \( A_j \) of the newly placed object \( o_j \) and minimizes other considerable parameters, such as kinetic energy. Throughout this process, several initial poses are tested with fixed initial positions but randomized orientations. We are sampling our initial orientations randomly, to keep the problem viable in large problem sets, where a holistic pose sampling would become intractable. The returned cost value is interchangeable among available objects in \( S \), thus we find the best object \( o^* \) with the best pose \( p^* \).

**Overview of the algorithm**

The pose searching algorithm iteratively evaluates poses with valid contacts (support polygon) between a newly placed object \( o_i \) and the existing stack. Once a pose with valid contacts is found, the algorithm refines the pose with gradient descent. To find a valid contact pose, we set the object to an initial pose in simulation that is close to the existing stack, but not yet touching it. The initial pose \( p_{init,i} \) of a new object \( o_i \in O \) consists of its initial position \( r_{init,i} \) and its initial orientation \( \mathbf{q}_{init,i} \). The initial position is set with an offset from the centroid \( C_j \) of the last placed object’s support polygon \( S_j \) along the normal direction \( n_j \) of \( S_j \) (see Figure 3). To obtain the initial orientation, the detected object orientation is rotated around a randomized axis with the random angle \( \theta \in [-\theta_{init}, \theta_{init}] \).

Based on the initial pose \( p_{init,i} \), the valid contact pose \( p_{contact,i} \) is found by a sub-routine named valid pose search by applying an attraction force \( F \) parallel to a thrust line input (in our case along the gravitational axis). We then run gradient descent (see the right in Figure 2) to iteratively improve the contact pose \( p_{contact,i} \) using the cost function presented below. After the local optimum pose \( p_{local,i}^* \) is found, the orientation of the initial pose \( p_{init,i} \) is randomized again to find the next valid contact pose \( p_{contact,i}^* \). After computing certain number \( x \) of local minima, we find the pose \( p_i^* \) with the lowest cost as the solution pose of \( o_i \). We iterate the process over the available subset \( S \) to find the best object \( o^* \).

To avoid jittering effect in physics simulation, the whole algorithm performs physics engine update steps only when it is necessary. Objects in an existing stack are set to be immobile in the whole process, except when the cost is calculated.

**Valid pose search**

For evaluating physical stability of object \( o_i \), it is a valid approach to analyze whether \( P_i^* \), the projection of the CoM position \( P_i \) onto the support polygon \( S_i \), is inside the support polygon or not (see Figure 4). In order to find a valid support
The valid pose search algorithm.

Algorithm 1 Valid pose search algorithm

1: function VALIDPOSESEARCH(o_i, p_{init,i})
2:   set o_i's pose to p_{init,i}
3:   do
4:     apply force F to o_i
5:     step physics simulation once
6:     if P'_i \not\in S_j then return false
7:     while N_{contact}(p_i) < 3
8:       pause physics simulation
9:       p_{contact,i} ← current pose
10:      if E_{kin}(p_{contact,i}) < E_{kin,stable} then return true
11:   else return false

For an irregularly shaped object o_i, we consider the contact points of the object to other objects. The assumed contact situations are simple: either on a flat surface for the first stack, or collision between two rigid body objects with parallel contact normals.

The valid pose search method is detailed in Algorithm [1]. To assure that p_{init,i} results in a valid contact pose p_{contact,i}, we apply an attraction force F along the thrust line direction vector v_i to the object o_i (see Figure 3). During this process, we continuously check whether the projection P'_i of the CoM position lies within the support polygon (see Figure 4).

As soon as the number of contacts N_{contact}(p_i) between o_i and the existing stack is at least three (see Figure 4), the resulting pose p_{contact,i} is evaluated by o_i’s kinetic energy E_{kin}(p_{contact,i}) with a threshold value E_{kin,stable}. By evaluating the kinetic energy, we limit the viable set of poses to the ones that cause minimal motion of the existing stack. This approach for finding a valid contact pose p_{contact,i} guarantees to satisfy the following constraints:

\[ E_{kin}(p_{contact,i}) \leq E_{kin,stable} \]
\[ P'_i \in S_j \]
\[ N_{contact}(p_{contact,i}) \geq 3. \]  

Cost calculation

We assign a cost to each valid contact pose p_{contact,i} to compare its ‘goodness’ in terms of a robust object poses, which allows further stacking. Therefore, we maximize the area of the support polygon S_i as well as minimize other considerable parameters, such as kinetic energy E_{kin}, and surface normal deviation from the thrust line n_i for reducing sheer forces.

To robustly find the support polygon S_i from the sparse contacts between o_i and the existing stack, contacts over several simulation update steps, in our case 10 steps, are collected and simplified [21]. After acquiring 3D point sets, Principal Component Analysis (PCA) is performed for dimension reduction from 3D to 2D point set. Processing the 2D point set with Delaunay triangulation [22], the polygon mesh S_i is created for calculating its area A_i and surface normal n_{c,i} (see Figure 3).

Given the area A_i of the support polygon S_i, the kinetic energy E_{kin}(p_{contact,i}), the dot product \|n_i \cdot v_i\|, where v_i is the thrust line direction vector, the length \|r_{p_j,p_i}\| between P_i and the CoM of the previously stacked object P_j, we define the cost function as

\[
f(p_{contact,i}) = w_1A_i^{-1} + w_2E_{kin}(p_{contact,i}) + w_3\|r_{p_j,p_i}\| + w_4\|n_i \cdot v_i\| ,
\]

s.t. \( w_j \geq 0 \) \( \forall j \in 1, \ldots, 4 \)

where \( w_j \) are manually selected weights of the individual energy function components. An overview of the cost calculation algorithm can be seen in Algorithm 2.

Algorithm 2 Cost calculation

1: function CALCULATECOST(o_i, p_{contact,i})
2:   set all objects in stack mobile
3:   contactsArray[] ← 0
4:   for k ← 0, k < 10 do
5:     step physics simulation once
6:     contactsArray[] ← current contacts set
7:   contacts ← simplify(contactsArray[])
8:   contactPlane ← PCA(contacts)
9:   contacts ← projection(contacts, contactPlane)
10:  S_i ← 2D DelaunayTriangulation(contacts)
11:  get A_i(S_i), E_{kin}(p_{contact,i}), \|r_{p_j,p_i}\|, \|n_i \cdot v_i\|
12:  reset poses of all objects in stack
13:  set all objects in stack immobile
14:  cost ← f(p_{contact,i})
15:  return cost

After assigning the cost to the valid contact pose p_{contact,i}, gradient descent is performed for searching the local optimum pose p_{local,i}, as depicted in the right of Figure 2. In this process, we iteratively calculate a small pose step \( \Delta p \) consisting of \( \delta \hat{r} \) and \( \delta \hat{q} \) as given in Eq. (5) and Eq. (6), to obtain an updated initial pose for valid contact pose searching:

\[
p_{local,i}[n + 1] = p_{local,i}[n] + \Delta p
\]

s.t. \( \Delta p = (\delta \hat{r}, \delta \hat{q}) \)

where \( p_{local,i}[0] = p_{contact,i} \). The translation \( \delta \hat{r} \) assigns a positive constant offset \( z_{const} \) in contact normal direction to avoid placing the object o_i at invalid poses overlapping.
with the existing stack. Given $\epsilon_r$ as a small value, $T_1$ as a homogeneous transformation matrix from world frame to the thrust line aligned frame at $C_j$ (see Figure 3), and $z_{\text{const}}$, we obtain $\delta \mathbf{r}$ as:

$$\delta \mathbf{r} = T_1(\frac{\partial f}{\partial r_x}, \frac{\partial f}{\partial r_y}, z_{\text{const}}),$$

and $\delta \hat{\mathbf{r}} = \epsilon_r \parallel \delta \mathbf{r} \parallel^2 $, s.t. $z_{\text{const}} \geq 0$.

For rotation, we describe the orientation with a quaternion $\mathbf{q}$ in axis-angle representation as $(\text{axis}, \text{angle})$. Given $\epsilon_q$ as small rotation angle, and $T_1$, we obtain $\delta \hat{\mathbf{q}}$ as:

$$\mathbf{v}_{\text{axis}} = T_1(\frac{\partial f}{\partial \theta_x}, \frac{\partial f}{\partial \theta_y}, \frac{\partial f}{\partial \theta_z})$$

and $\delta \hat{\mathbf{q}} = (\mathbf{v}_{\text{axis}}, \epsilon_q)$

For minimization of the cost, we iterate the process described in Eq. (4) until the difference of returned cost becomes smaller than the threshold $\gamma$ as $f(p_{\text{local contact}},i[\min]) - f(p_{\text{local contact}},i[\text{next}]) < \gamma$. We write the optimization process as,

$$p_{\text{local contact},i}^* = \min_{p_{\text{local contact},i}} f(p_{\text{local contact},i})$$

s.t. $A_i(S_i) \geq A_{\text{min}},$

where $A_{\text{min}}$ is the minimal support polygon area.

After finding a local optimum pose $p_{\text{local},i}^*$, a new randomized rotation is assigned to the initial pose $p_{\text{init},i}$ and the process is repeated until $x$ local solutions are found, as shown in the left of Figure 2. The pose with minimum cost is selected as a solution $p_i^*$ for object $o_i$. We iterate the entire process over all objects of the available subset $S$, returning the best object $o_i^*$ with the best pose $p_i^*$.

V. EXPERIMENTAL SETUP

To show the applicability and repeatability of the presented pose searching and object detection methods, we implemented the algorithms, using Robotic Operating System [ROS] [23], on a robotic platform to perform autonomous dry-stacking as in Figure 1. The goal is to create a vertical tower out of randomly placed irregularly shaped objects whose mechanical and geometric properties are known.

A. Experimental Setup

We use a set of six natural lime stones (Figure 5) as objects because they show challenging properties for the stacking task like irregular shape and low friction coefficient. The point cloud and mesh model of the object’s geometric shape were previously acquired with an ATOS Core high precision scanner. These models are used for detecting the objects in the scene, as well as for simulating in a physics engine used in the pose searching algorithm. To lower the computation cost, we reduced the mesh model for the pose searching algorithm to a homogeneously triangulated mesh with 500 faces. This showed to be a reasonable trade-off between reducing the computation cost and being able to generate a contact situation that correlates with the real world. The weight, CoM position, and moment of inertia of each stone were measured and added to the geometric model description. The friction coefficient was estimated with a low value of $\mu_{\text{stone}} = 0.1$. For manipulating the objects, we use a robotic arm equipped with a three-finger gripper as depicted in Figure 3. The object detection is performed with an RGB-D depth camera mounted on the robot arm. The size of the objects are selected to fit in the finger stroke of the gripper. We are using Moveit! [24] to generate collision free motions of the robot. A force-torque sensor mounted at the attaching point of the gripper is used to detect impact during the placing of the object.

The work-flow of autonomously creating a vertical stack of arbitrarily placed stones is shown in Figure 4. This task is performed by continuously executing a loop consisting of object detection, pose searching and object manipulation.

<table>
<thead>
<tr>
<th>Parameter</th>
<th>Value</th>
<th>Parameter</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>$w_1$</td>
<td>0.179</td>
<td>$A_{\text{min}}$</td>
<td>$1 \times 10^{-5}$ m$^2$</td>
</tr>
<tr>
<td>$w_2$</td>
<td>0.472</td>
<td>$F$</td>
<td>100 N</td>
</tr>
<tr>
<td>$w_3$</td>
<td>0.094</td>
<td>$E_{\text{kin,stable}}$</td>
<td>20 J</td>
</tr>
<tr>
<td>$w_4$</td>
<td>0.255</td>
<td>$\theta_{\text{init}}$</td>
<td>$\frac{\pi}{2}$ rad</td>
</tr>
<tr>
<td>$x$</td>
<td>5</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Fig. 5: Lime stones with irregular shape are used to create vertical stacks.

Fig. 6: An overview of the used hardware setup: a ROBOTIQ 3-finger gripper, a FT150 force torque sensor, and an Intel® RealSense™ SR300 RGB-D camera are attached to a UR10 arm.

TABLE I: Parameters
In this paper, we introduced an autonomous robotic system that constructs a balancing vertical tower out of irregularly shaped stones without using mortars or extra materials. Its work-flow consists of a continuous loop with object detection, target pose search, physical manipulation, and evaluation. We presented an object detection pipeline suited to localize irregularly shaped objects in a scene and a target pose searching algorithm to generate stable stacks. The proposed algorithms were implemented on a robotic system and tested in an experimental setup (a fixed platform in a controlled environment with a flat terrain, and pre-scanned objects). The system showed to be able to perform stacking tasks autonomously, contributing to a preliminary setup for detecting irregularly shaped objects and also validating the proposed pose searching algorithm.

As a next step to improve the stability of the planned stack in this setup, the pose searching could consider the future cost by simulating several steps ahead. Aiming at more practical situations, we want to focus on construction with unseen objects. This involves the segmentation of unknown objects in a scene and their handling with incomplete information.

Furthermore, we aim at creating more complex target shapes, such as arches or walls. These shapes can create structures where each object is in contact with more than two objects. In such a situations, not just a vertical or single thrust line, but a more complex thrust line network needs to be analyzed.

**VI. Conclusion**

Table II shows the mean execution times of the different parts of the presented approach, although computational and execution speed was not a focus of this paper. On average, a trial to construct a vertical stack lasted 271.0 s. The main fraction of this time is spent for the manipulation task that includes path planning, arm and gripper motion. This is mainly due to the fact that the robot, for safety reasons, is operated with reduced speed. The remaining time is spent for the pose searching algorithm itself, object detection and other tasks, such as visualization and stopping the motion before capturing depth images. The stacking work-flow is not yet optimized in terms of construction time and could be greatly improved by parallelizing manipulation with pose searching and object detection, and by increasing the operation speed.

**VII. Acknowledgement**

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