ViTa-SLAM: Biologically-Inspired Visuo-Tactile SLAM

Oliver Struckmeier, Kshitij Tiwari, Martin J. Pearson, and Ville Kyrki

***Abstract*— In this work, we propose a novel, bio-inspired multi-sensory SLAM approach called ViTa-SLAM. Compared to other multi-sensory SLAM variants, this approach allows for a seamless multi-sensory information fusion whilst naturally interacting with the environment. The algorithm is empirically evaluated in a simulated setting using a biomimetic robot platform called the WhiskEye. Our results show promising performance enhancements over existing bio-inspired SLAM approaches in terms of loop-closure detection.**

I. Introduction

Of late, there is growing interest in biologically inspired SLAM algorithms. For instance, the rat hippocampus inspired RatSLAM [1] provides a biologically-inspired 3 DOF SLAM architecture which has been shown to work for robots operating under a myriad of environmental conditions. While the vanilla RatSLAM was purely designed as a visual SLAM approach, there are additional works that now explain its usage with other sensory modalities like WiFi [2] and auditory signals [3].

In nature, most mammals like the rats use their whiskers to interact with their environment through contact (Fig. 1). In [4], it was shown that rats rely on whiskers to maintain a cognitive understanding of their surroundings. To this end, this work describes our preliminary findings of extending the RatSLAM algorithm to account for both visual and tactile sensory modalities. The new algorithm will be hereby referred to as ViTa-SLAM. The novel aspect of this algorithm is that it utilizes multiple sensory modalities to estimate the state of the robot which are implicitly fused as opposed to other methods that require explicit weighted fusion like [5].

Fig. 1: Rat interacting with its surroundings while foraging.

II. ViTa-SLAM

ViTa-SLAM comprises of two sensory inputs: *visual* and *tactile*. Below, we elucidate how each of these sensory modalities are processed to obtain the best pose estimate.

A. Visual Data Processing

Each visual frame is converted to greyscale (B/W img) and processed to obtain a local view template (V) similar to the vanilla RatSLAM [1].

B. Tactile Data Processing

The tactile data contains two kinds of information: *contact points* and *deflection*. *Contact points* $(Cts.)$ refers to the point on the object surface where the contact is made while *deflection* $(Defl.)$ refers to the amount of bending of the whiskers. The former is used to obtain a Point Feature Histogram (PFH) [6] while the latter is used to obtain the Slope Distribution Array (SDA) [7]. Together, they are referred to as tactile features (F). Previous attempts at pure whisker sensor based SLAM can be found in works like the WhiskerRatSLAM [8].

C. Overall System Architecture

The overall system architecture is shown in Fig. 2 wherein the pose cell network (PC) combines the information F, V from both modalities to obtain the best pose estimate. A semi-metric experience map (Exp. Map) [9] is generated to evaluate the model performance.

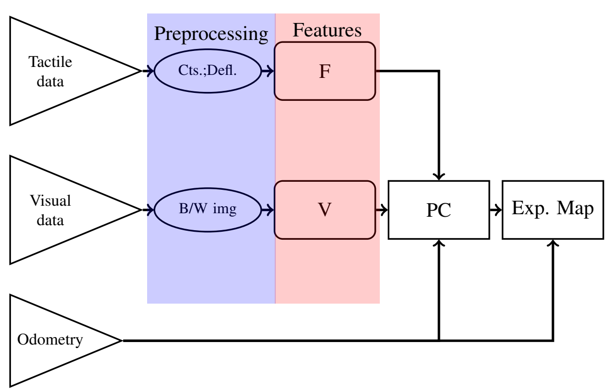

Fig. 2: Overview of Vita-SLAM architecture.

III. Evaluation

In this section, we describe the robot platform and the experimental scenario under which the model performance of ViTa-SLAM was evaluated. Following suit, the results obtained are described.

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A. Robot Platform

The (simulated) robot platform used for empirical evaluation is called the WhiskEye. This robot is equipped with 24 whiskers which can be individually controlled and comes with a mobile base. The whiskers are mounted at the end of a neck which was kept fixed at a desired pose for this work. Aside from these, the platform is also equipped with a static RGB camera.

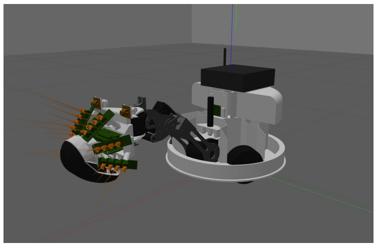

Fig. 3: Simulated robot platform, WhiskEye.

B. Environment

The robot is deployed in a visually sparse scene meaning there are not many diverse visual cues to be processed. Additionally, to break the 1-fold rotational symmetry of the rectangular environment being used, two static landmarks (cylinder and cube) are also placed in the scene.

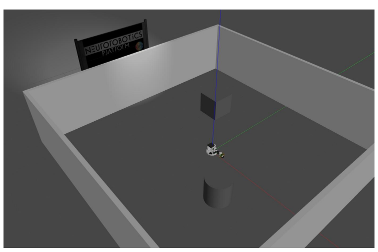

Fig. 4: Environmental setup. 2 landmarks in a visually sparse arena.

C. Behavior

The robot was given a pre-meditated trajectory to perform: It was required to reach landmark 1 (cylinder), revolve around it, then approach landmark 2 (cube), revolve around it and terminate exploration. At all times, the whiskers were being controlled using the Rapid Cessation of Protraction (RCP) protocol [10].

D. Results

In order to evaluate ViTa-SLAM performance, it was directly pitted against vanilla RatSLAM while keeping the platform and environment identical for both settings. As can be seen from Fig. 5, vanilla RatSLAM generated too many novel visual templates which eventually lead to failure of loop-closure detection. The frequent generation of novel templates can be attributed to visual sparsity of the scene. However, with ViTa-SLAM, additional tactile information helps detect loop closures[1] as shown in Fig. 6. There are however challenges with using the passive whisking behavior which leads the whisker array of the robot to collide with landmarks. This induces noise into the tactile data which adversly affects loop-closure detection.

[1]Video demonstration available here: https://youtu.be/ygX340vA3rM

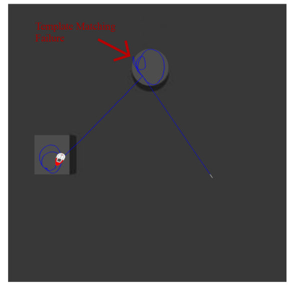

Fig. 5: RatSLAM failure.

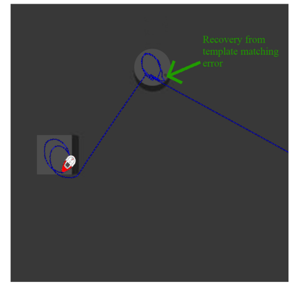

Fig. 6: ViTa-SLAM success.

IV. Conclusion and Future Works

In this work, we presented preliminary variant of our novel ViTa-SLAM algorithm which allows for multi-sensory SLAM whilst interacting with the environment through contact. Whilst the state-of-the-art bio-inspired SLAM model called RatSLAM was inspired by the rat hippocampal formations, it was designed purely for non-contact sensing scenarios. Similarly, WhiskerRatSLAM was designed purely for contact-sensing based SLAM. With this work, we have extended the outreach of these bio-inspired SLAM approaches to biomimetic robots bringing us one step closer to transitioning from biologically-inspired to biologically plausible methodologies.

In the future works, we plan on extending our algorithm to higher dimensions to account for the full 6 DOF pose while the algorithm currently can handle upto 3 DOF pose. While this poses significant computational challenges, it is essential to generalizing the applicability of this method. Additionally, we will investigate active sensory switch mechanism to minimize rudimentary sensory data acquisition.

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