CSCE 580: Artificial Intelligence

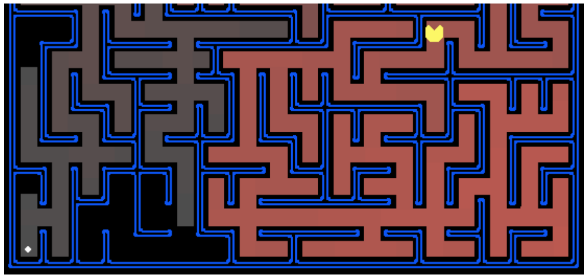
Advanced Applications: Robotics**

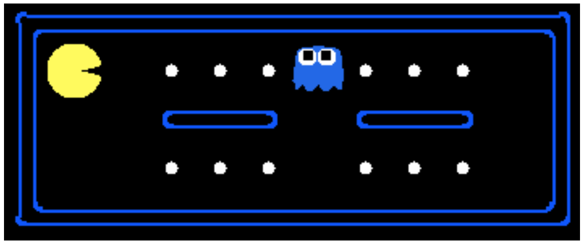
Instructor: Pooyan Jamshidi

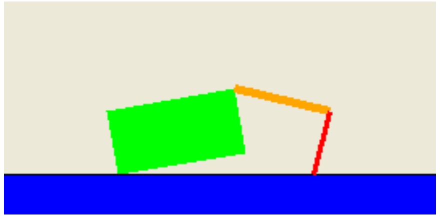
University of South Carolina

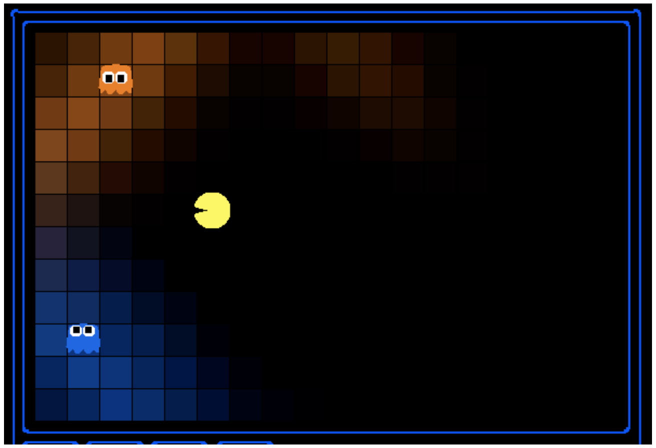
[These slides are mostly based on those of Dan Klein and Pieter Abbeel for CS188 Intro to AI at UC Berkeley, ai.berkeley.edu]

So Far: Foundational Methods

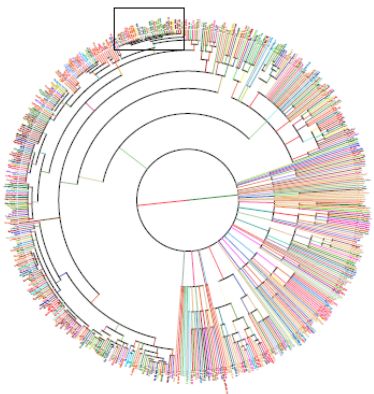


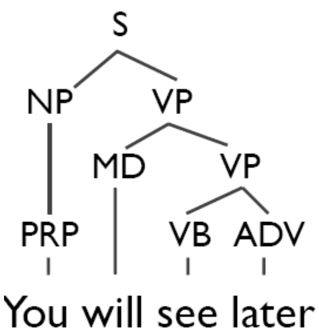






Now: Advanced Applications





Después lo veras

AlphaGo

AlphaGo

Google is trying to make artificial intelligence history — and it could happen this week

Drake Baer

Mar. 7, 2016, 3:49 PM 9,639

FACEBOOK LINKEDIN TWITTER EMAIL PRINT

CADE METZ BUSINESS 03.16.16 7:00 AM

IN TWO MOVES, ALPHAGO AND LEE SEDOL REDEFINED THE FUTURE

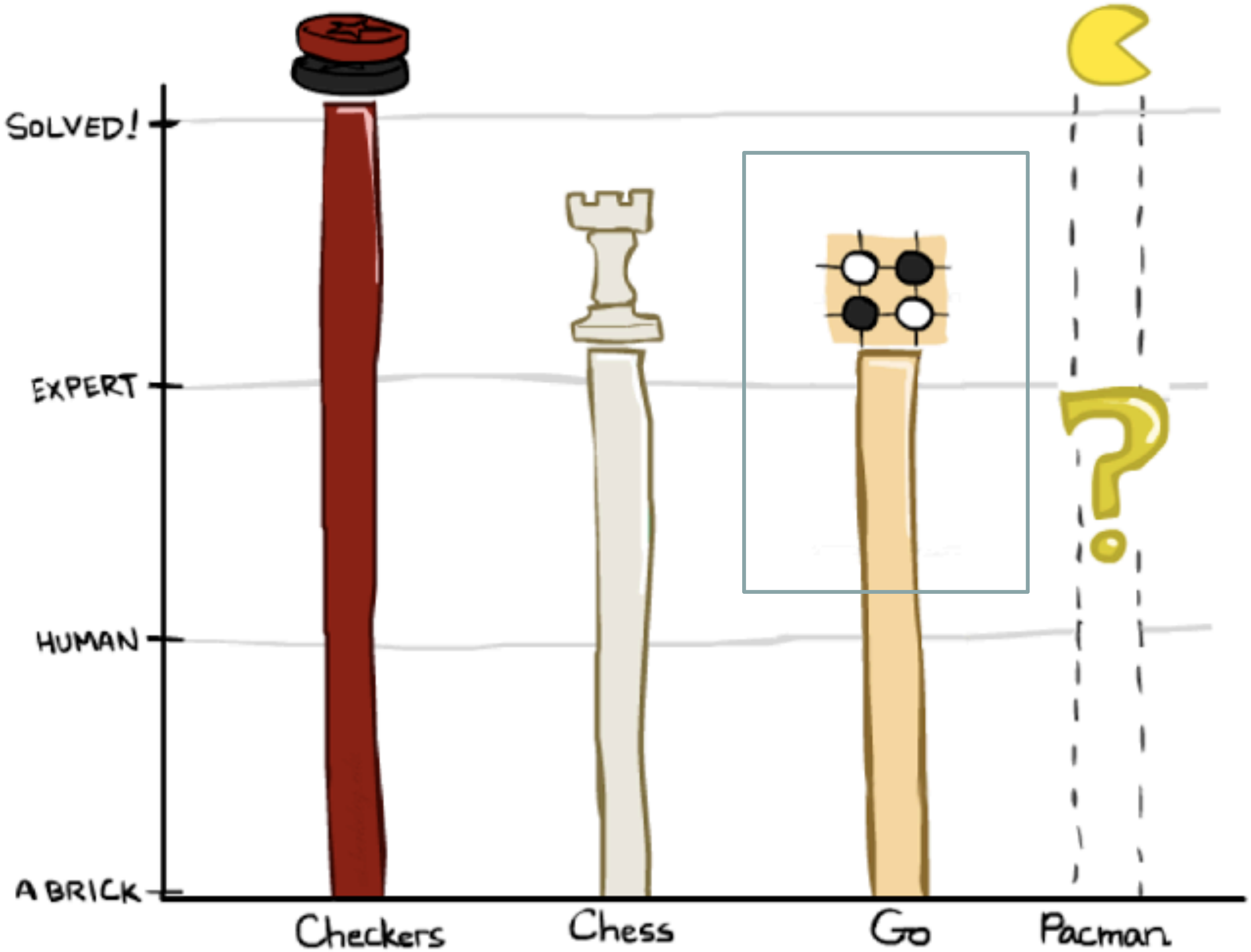
Lee Sedol. GEORDIE WOOD FOR WIRED

SEOUL, SOUTH KOREA — In Game Two, the Google machine made a move that no human ever would. And it was beautiful. As the world looked on, the move so perfectly

LATEST NEWS

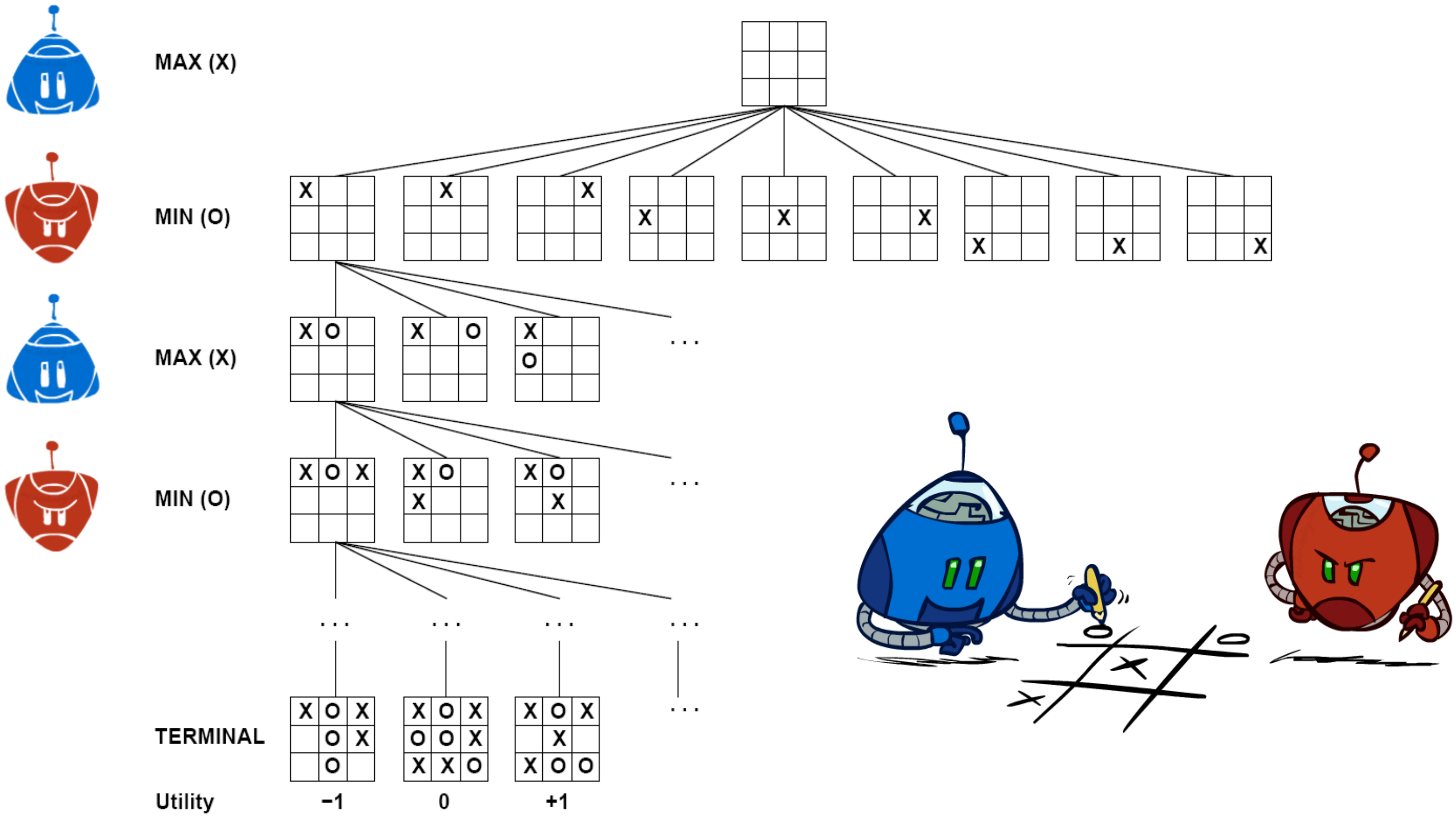
MOBILE
It's Official: The Smartphone Market Has Gone Flat
5 HOURS

DESIGN
Neural Nets Got You


SOLVED!
EXPERT
HUMAN
A BRICK
Checkers
Chess
Go
Pacman

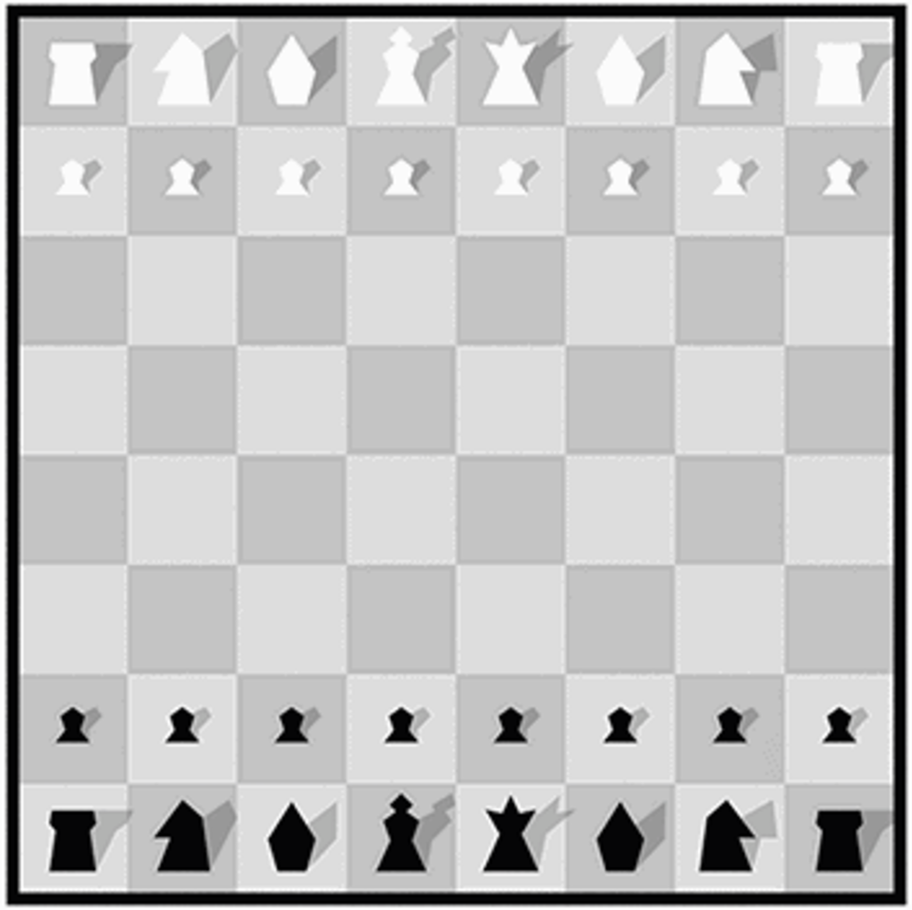
How would you
make an AI for Go?

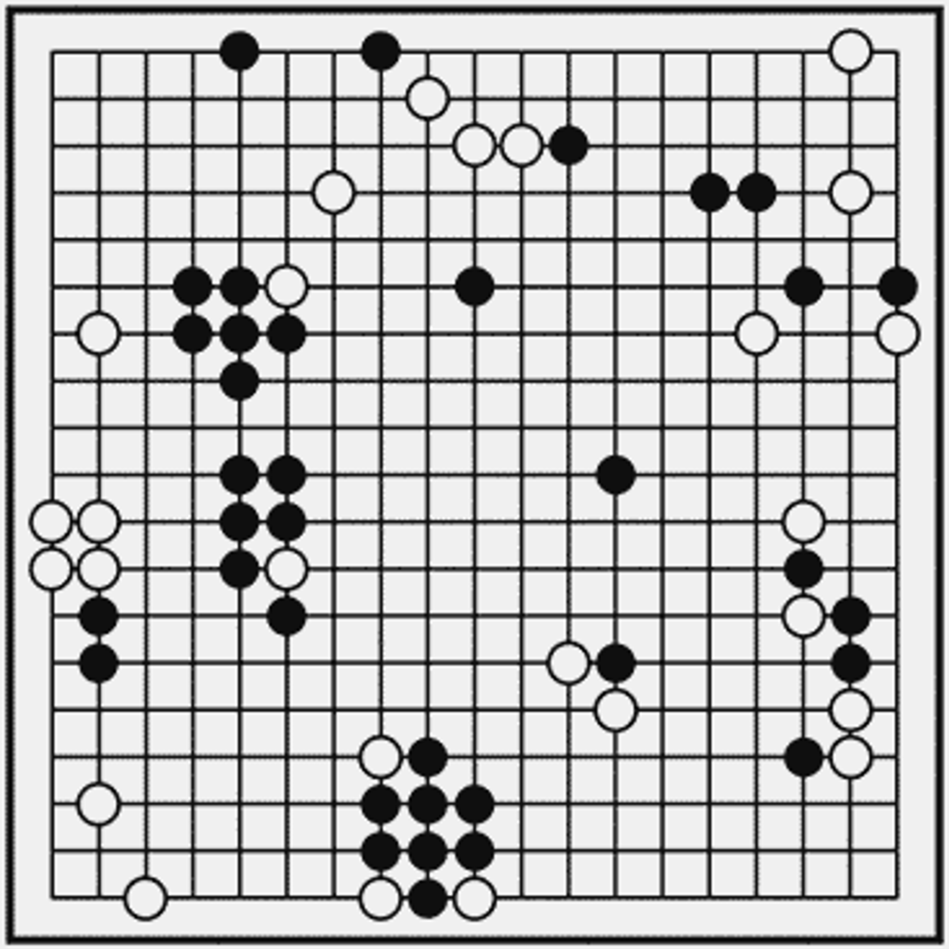
MiniMax!



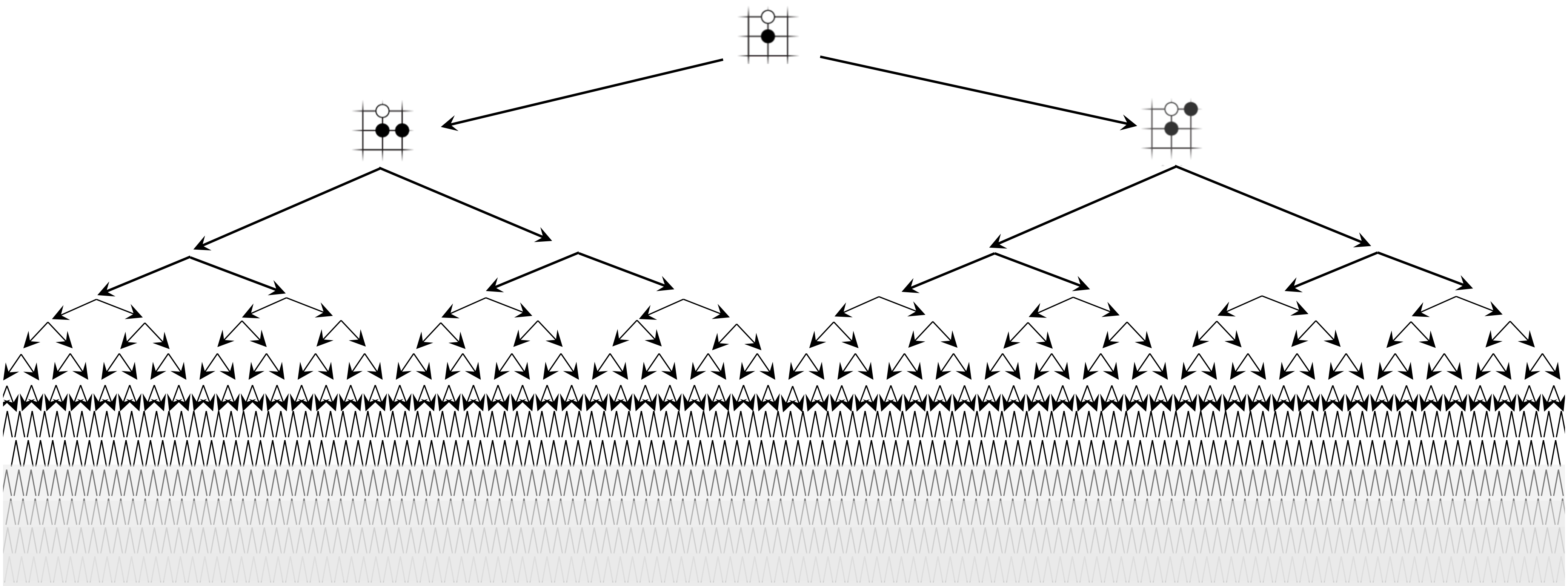
Why is it hard?

In particular, why is it harder than chess?

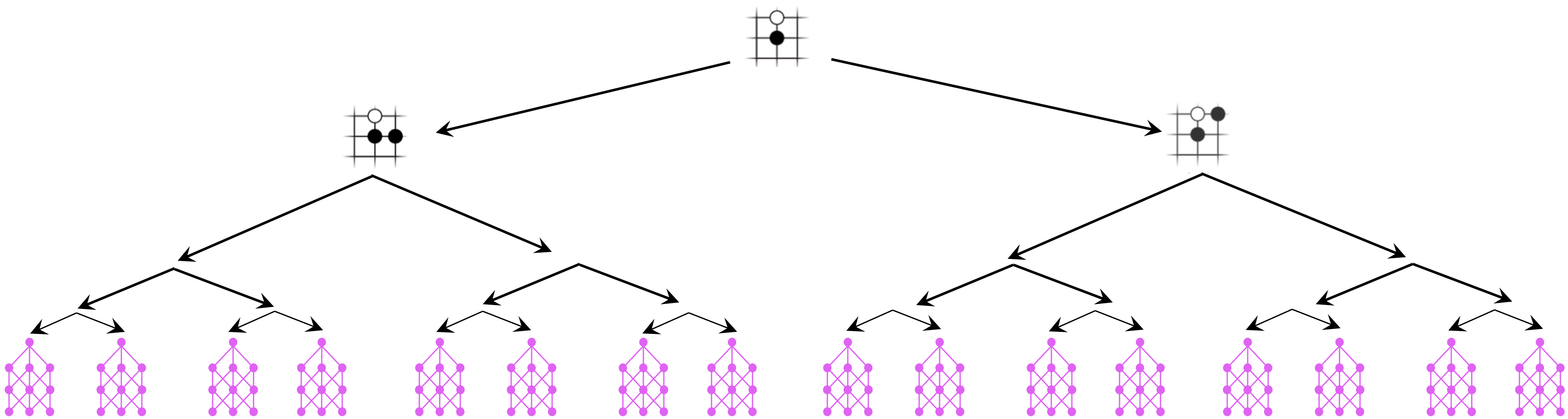




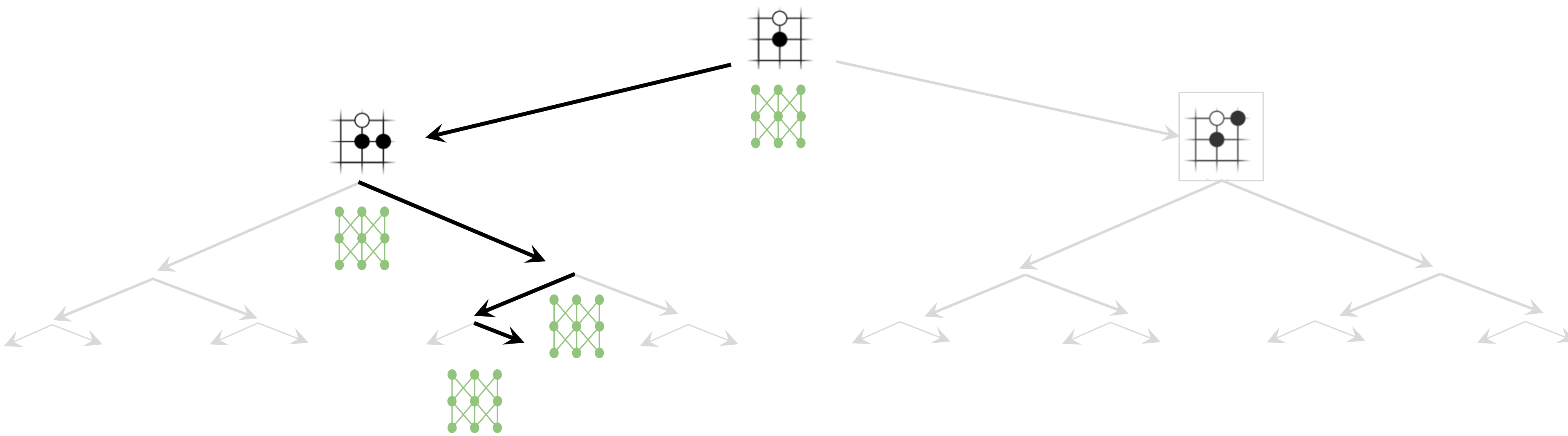
Exhaustive search



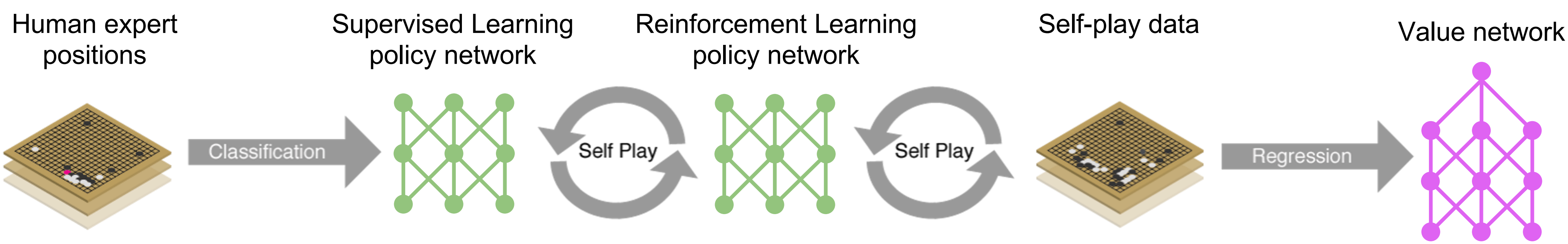
Reducing depth with value network

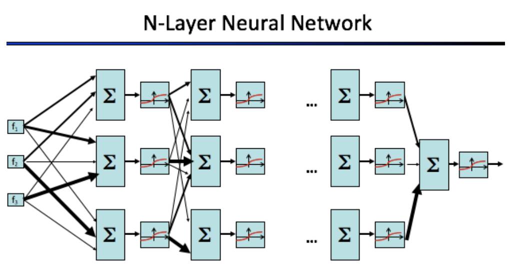


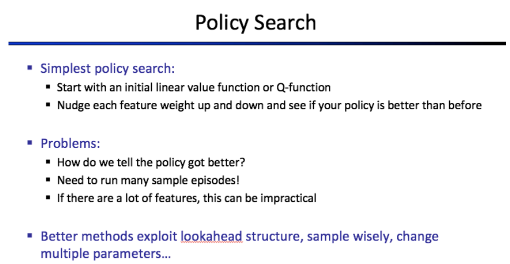
Reducing breadth with policy network



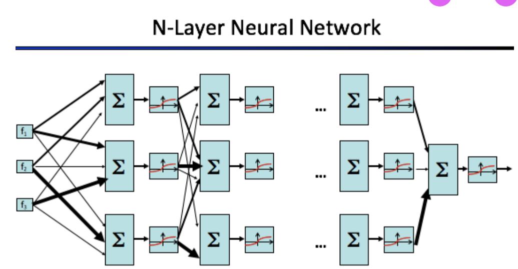
Neural network training pipeline



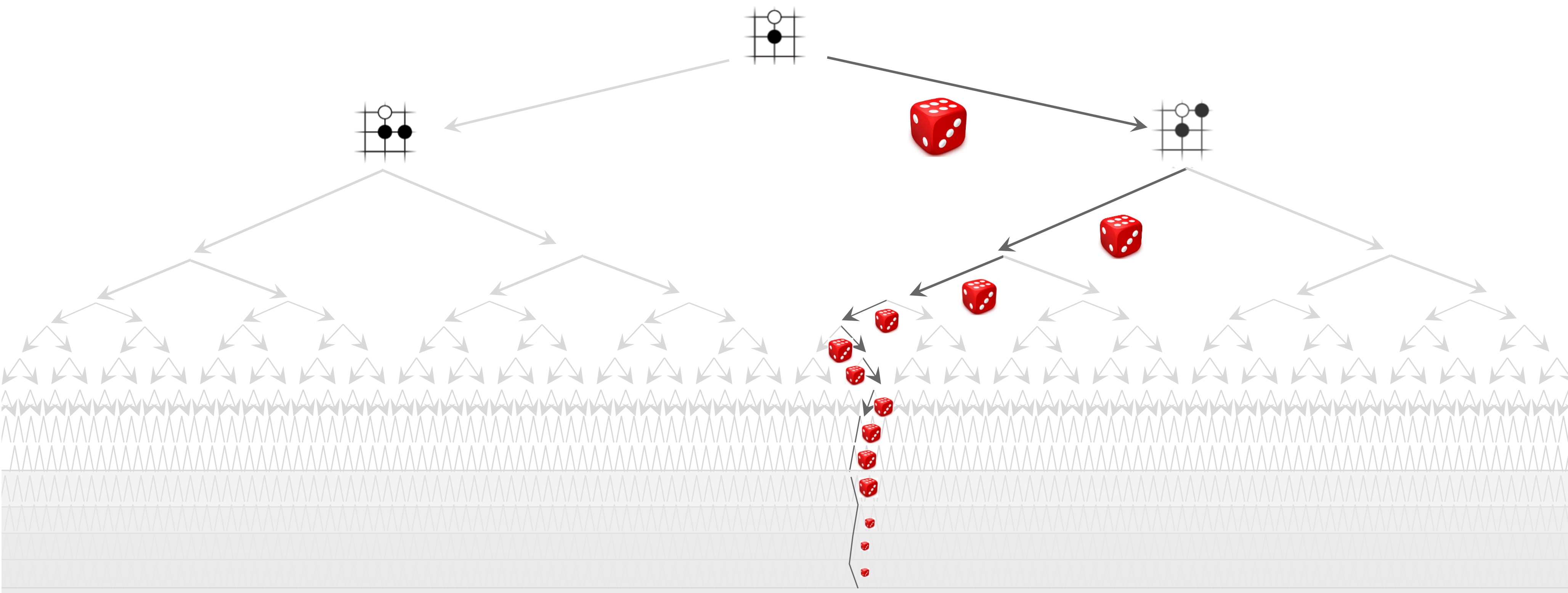



Policy Search

- Simplest policy search:
  - Start with an initial linear value function or Q-function
  - Nudge each feature weight up and down and see if your policy is better than before
- Problems:
  - How do we tell the policy got better?
  - Need to run many sample episodes!
  - If there are a lot of features, this can be impractical
- Better methods exploit lookahead structure, sample wisely, change multiple parameters…



One more thing: Monte-Carlo rollouts



nature International weekly journal of science

Search Go

▸ Advanced search

NATURE | ARTICLE

日本語要約

Mastering the game of Go with deep neural networks and tree search

David Silver, Aja Huang, Chris J. Maddison, Arthur Guez, Laurent Sifre, George van den Driessche, Julian Schrittwieser, Ioannis Antonoglou, Veda Panneershelvam, Marc Lanctot, Sander Dieleman, Dominik Grewe, John Nham, Nal Kalchbrenner, Ilya Sutskever, Timothy Lillicrap, Madeleine Leach, Koray Kavukcuoglu, Thore Graepel & Demis Hassabis

Affiliations | Contributions | Corresponding authors

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Editor's summary

العربية

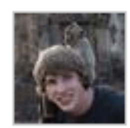
The victory in 1997 of the chess-playing computer Deep Blue in a six-game series against the then world champion Gary Kasparov was seen as a significant milestone in the development of artificial inte…

Related audio

Hear from the makers of the AI that mastered Go - and the professional player it beat.

00:00

Authors with **Loop profiles** beta



Julian Schrittwieser

Marc Lanctot

a natureresearch journal

nature
International journal of science

Article

Mastering the game of Go without human knowledge

David Silver, Julian Schrittwieser, Karen Simonyan, Ioannis Antonoglou, Aja Huang, Arthur Guez, Thomas Hubert, Lucas Baker, Matthew Lai, Adrian Bolton, Yutian Chen, Timothy Lillicrap, Fan Hui, Laurent Sifre, George van den Driessche, Thore Graepel & Demis Hassabis

Nature **550**, 354–359 (19 October 2017)
doi:10.1038/nature24270
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Computational science Computer science Reward

Received: 07 April 2017
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Editorial Summary

AlphaGo Zero goes solo

To beat world champions at the game of Go, the computer program AlphaGo has relied largely on supervised learning from millions of human expert moves. David Silver and colleagues have now produced a system called

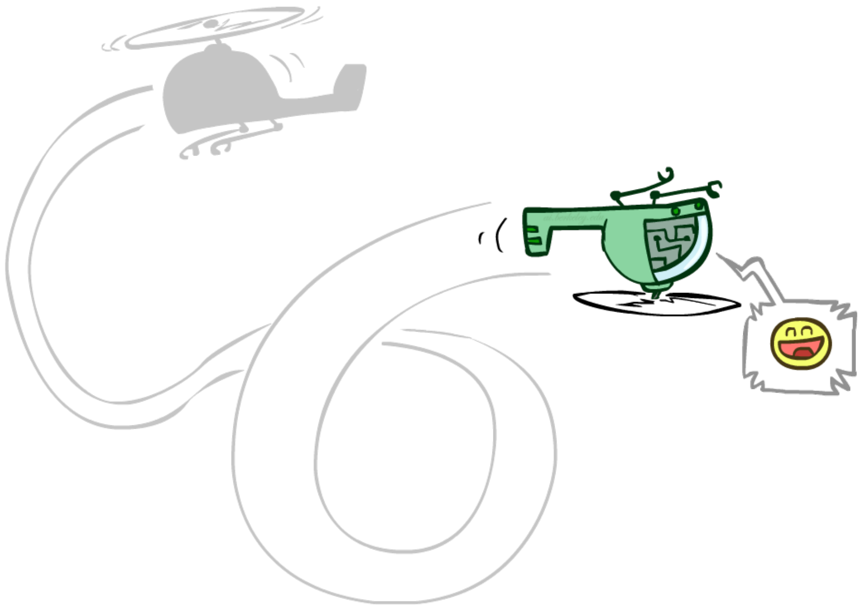
Associated Content

Nature | News & Views

Artificial intelligence: Learning to play Go from scratch

Satinder Singh, Andy Okun & Andrew Jackson

Robotic Helicopters



Motivating Example

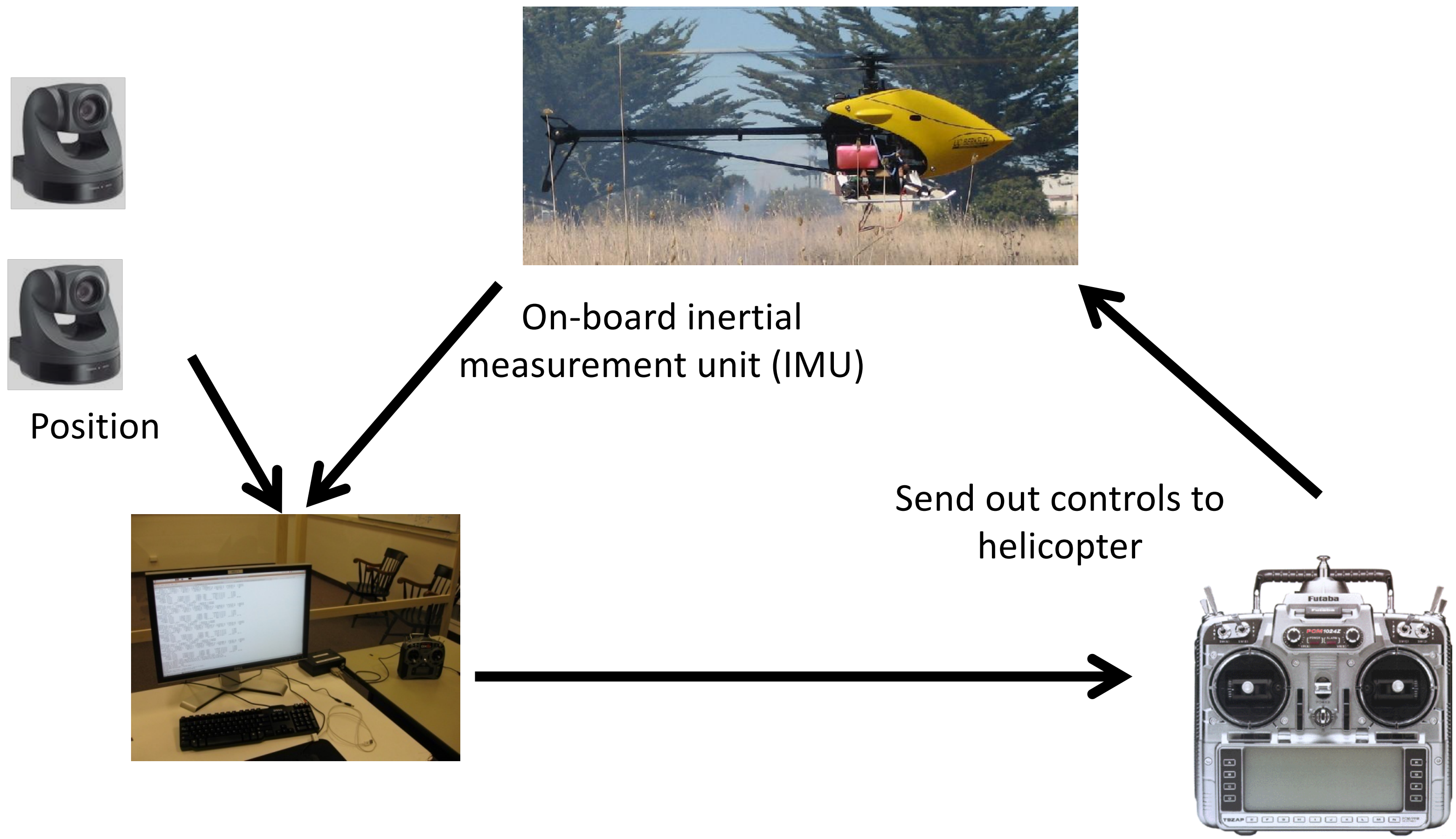
- How do we execute a task like this?

[VIDEO: tictoc_results.wmv]

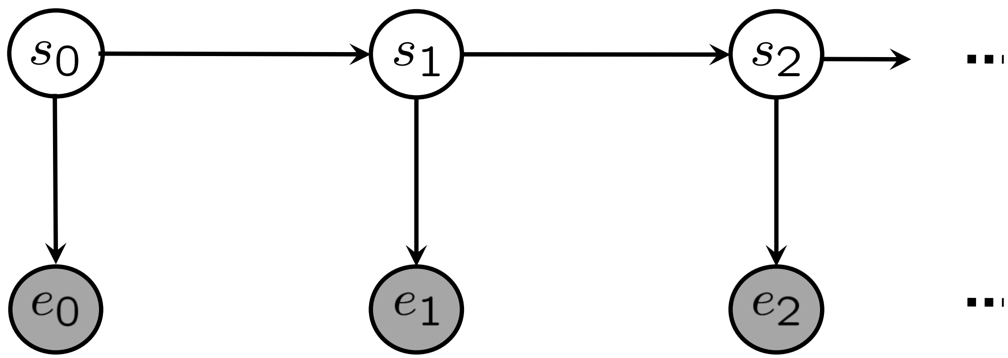
Autonomous Helicopter Flight

- Key challenges:
  - Track helicopter position and orientation during flight
  - Decide on control inputs to send to helicopter

Autonomous Helicopter Setup



HMM for Tracking the Helicopter



- State: $s = (x, y, z, \phi, \theta, \psi, \dot{x}, \dot{y}, \dot{z}, \dot{\phi}, \dot{\theta}, \dot{\psi})$
- Measurements: [observation update]
  - 3-D coordinates from vision, 3-axis magnetometer, 3-axis gyro, 3-axis accelerometer
- Transitions (dynamics): [time elapse update]
  - $s_{t+1} = f(s_t, a_t) + w_t$ f: encodes helicopter dynamics, w: noise

Helicopter MDP

- State: $s = (x, y, z, \phi, \theta, \psi, \dot{x}, \dot{y}, \dot{z}, \dot{\phi}, \dot{\theta}, \dot{\psi})$
- Actions (control inputs):
  - a_{lon} : Main rotor longitudinal cyclic pitch control (affects pitch rate)
  - a_{lat} : Main rotor latitudinal cyclic pitch control (affects roll rate)
  - a_{coll} : Main rotor collective pitch (affects main rotor thrust)
  - a_{rud} : Tail rotor collective pitch (affects tail rotor thrust)

- Transitions (dynamics):
  - $s_{t+1} = f(s_t, a_t) + w_t$

  [f encodes helicopter dynamics]

  [w is a probabilistic noise model]

- Can we solve the MDP yet?

Problem: What's the Reward?

- Reward for hovering:

$$
\begin{aligned}
R(s) \quad = \quad & -\alpha_x (x - x^*)^2 \\
& -\alpha_y (y - y^*)^2 \\
& -\alpha_z (z - z^*)^2 \\
& -\alpha_{\dot{x}} \dot{x}^2 \\
& -\alpha_{\dot{y}} \dot{y}^2 \\
& -\alpha_{\dot{z}} \dot{z}^2
\end{aligned}
$$

RL: Helicopter Flight

[Andrew Ng]

[Video: HELICOPTER]

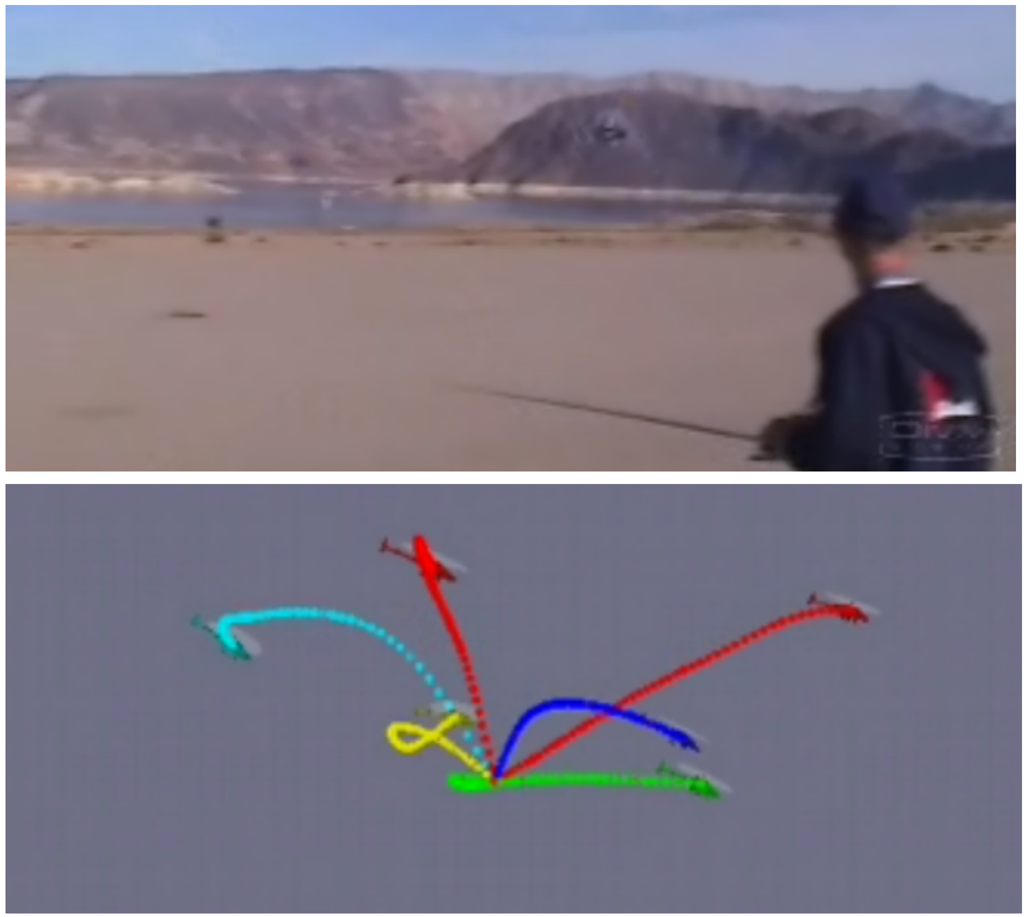
Problem for More General Case: What’s the Reward?

- Rewards for “Flip”?
  - Problem: what’s the target trajectory?
  - Just write it down by hand?

Flips (?)

[VIDEO: 20061204---bad.wmv]

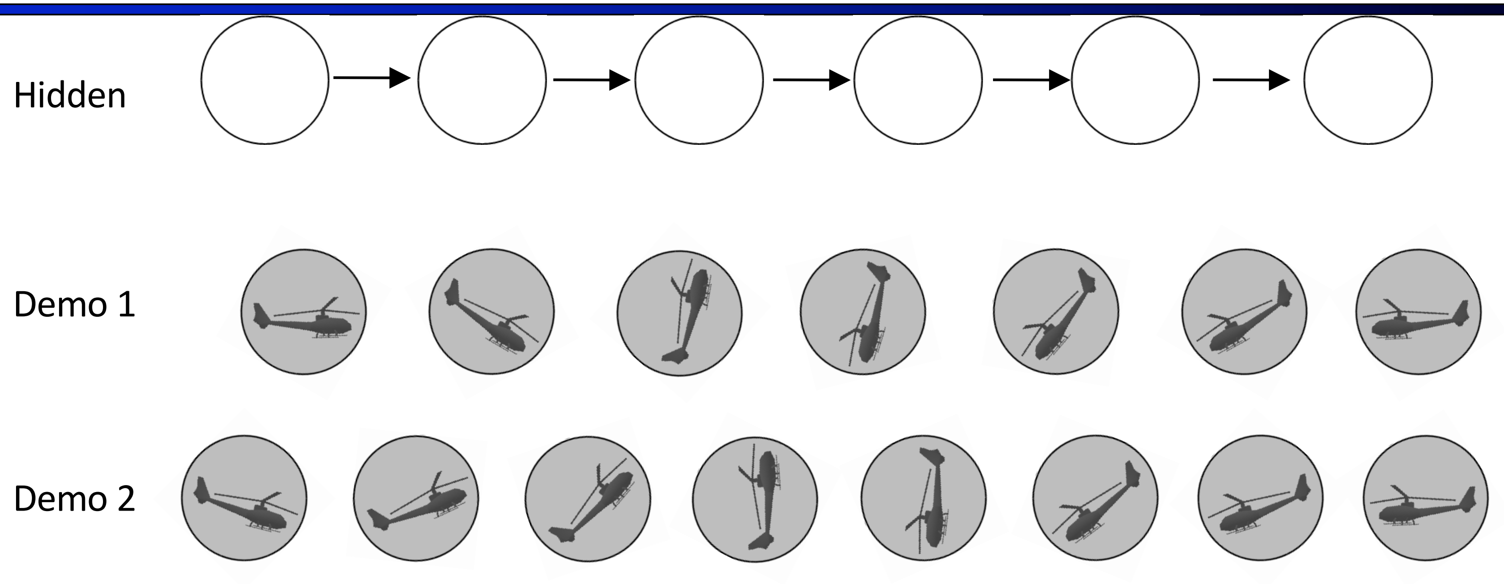
Helicopter Apprenticeship?



[VIDEO: airshow_unaligned.wmv]

Demonstrations

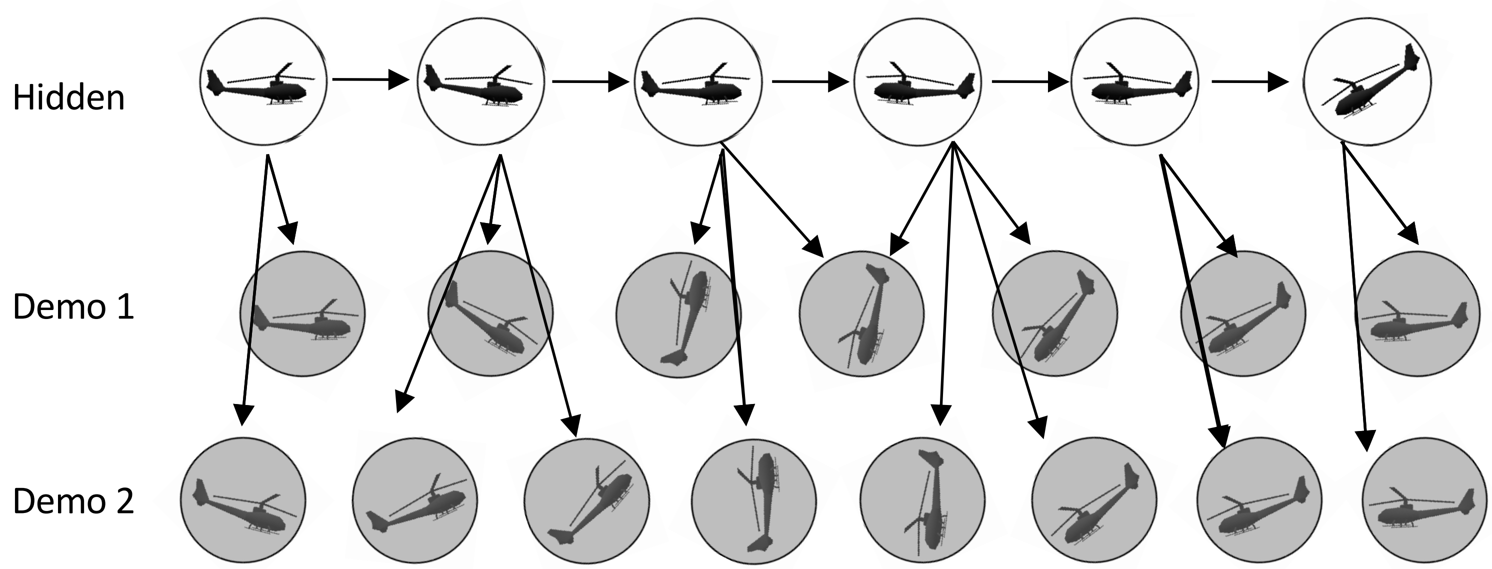
Learning a Trajectory



- HMM-like generative model
  - Dynamics model used as HMM transition model
  - Demos are observations of hidden trajectory
- Problem: how do we align observations to hidden trajectory?

Abbeel, Coates, Ng, IJRR 2010

Probabilistic Alignment using a Bayes' Net



- Dynamic Time Warping

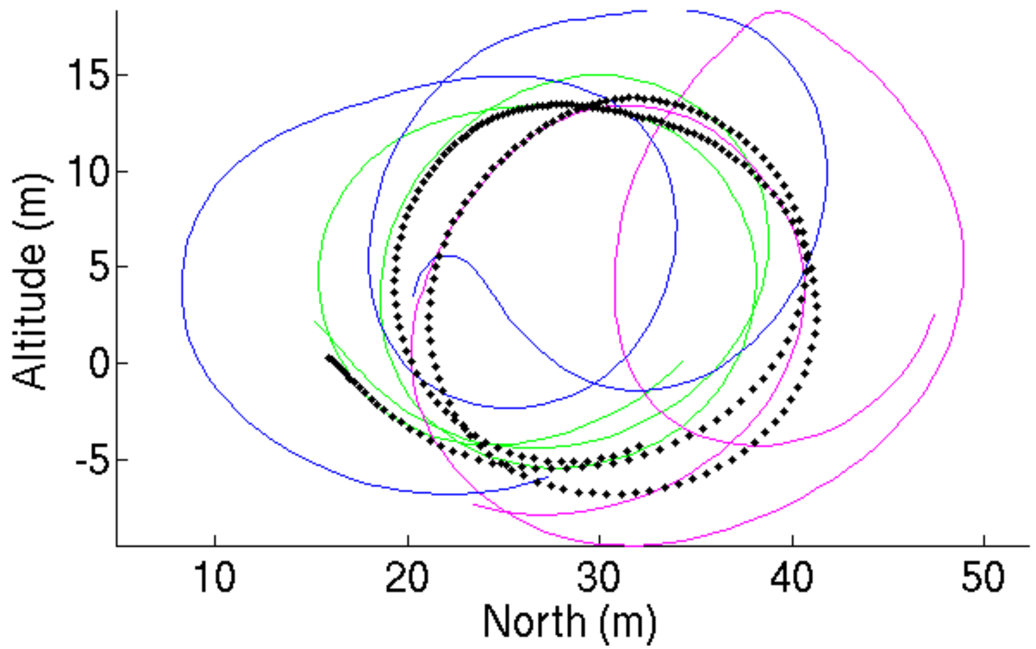
  (Needleman&Wunsch 1970, Sakoe&Chiba, 1978)
- Extended Kalman filter / smoother

Abbeel, Coates, Ng, IJRR 2010

[VIDEO: airshow_unaligned.wmv]

Aligned Demonstrations

Alignment of Samples



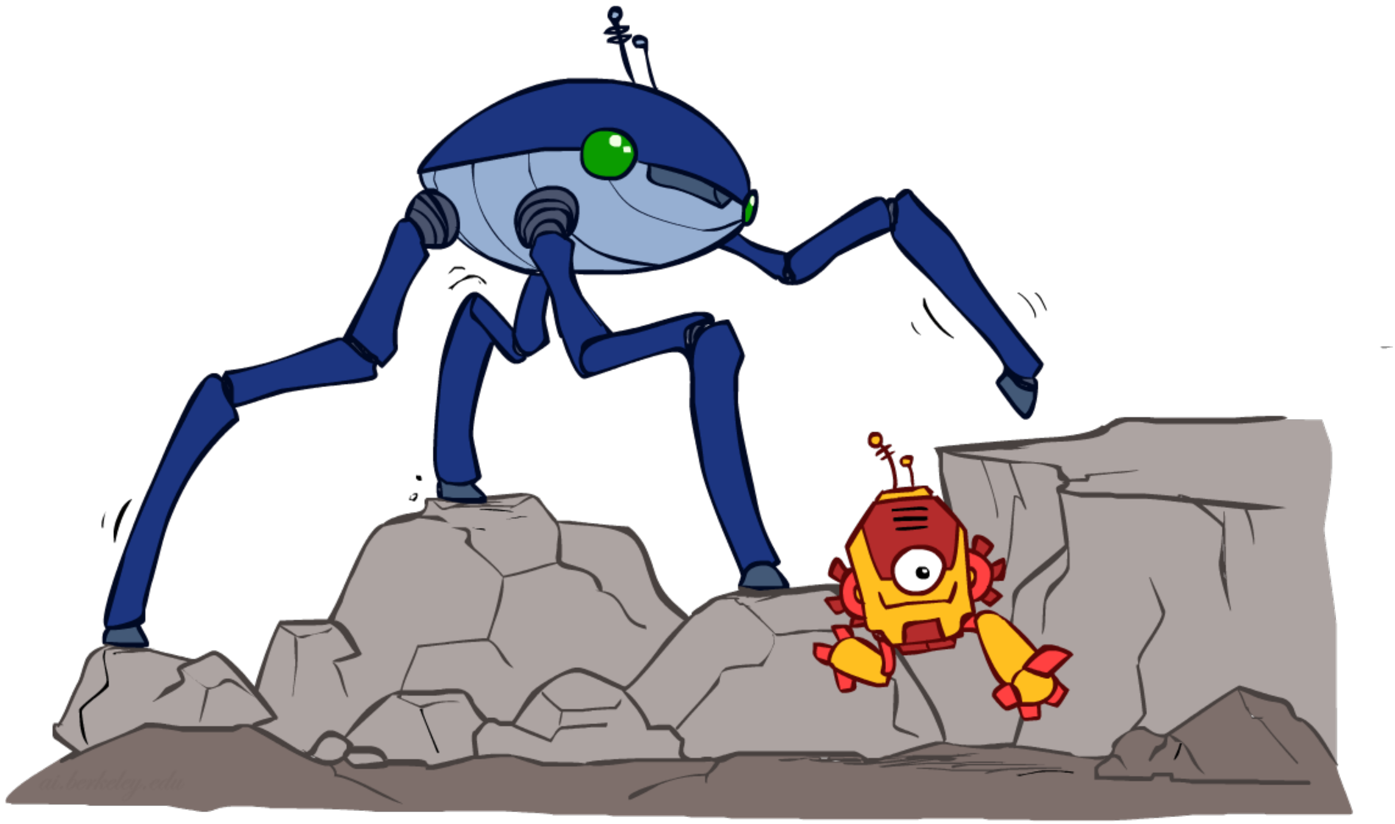
- Result: inferred sequence is much cleaner!

Learned Behavior

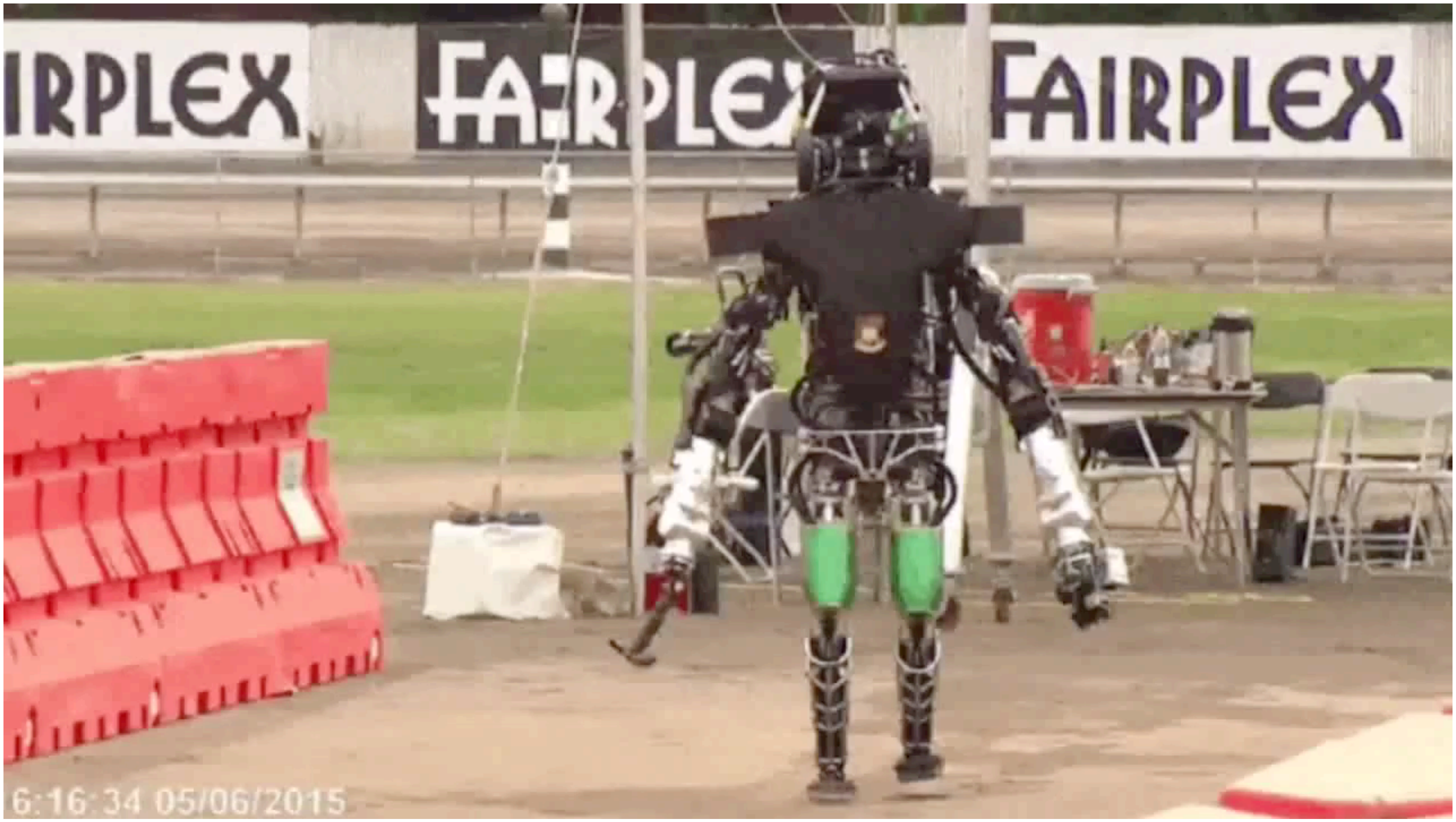
[VIDEO: airshow_trimmed.wmv]

[Abbeel, Coates, Quigley, Ng, 2010]

Legged Locomotion

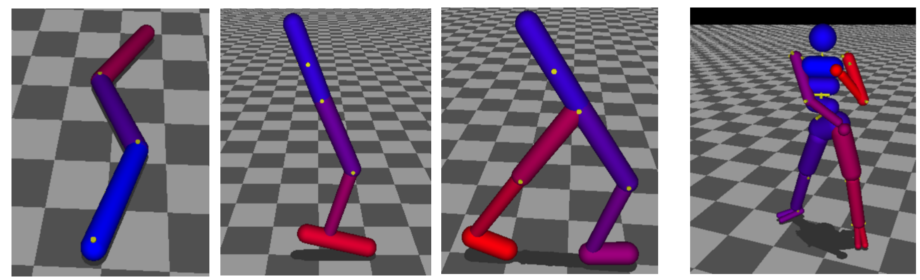


For Perspective: Darpa Robotics Challenge (2015)



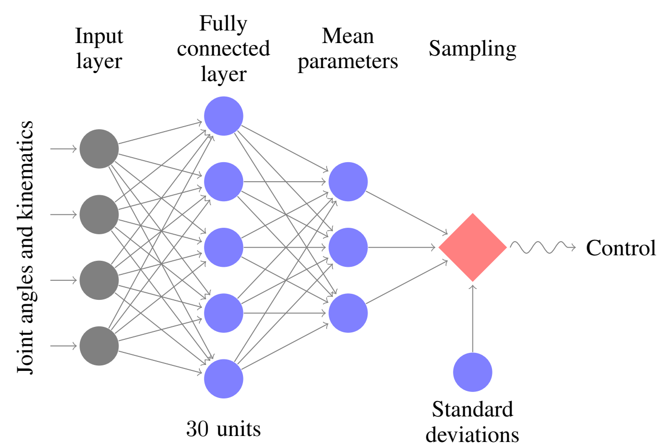
How About Continuous Control, e.g., Locomotion?

Robot models in physics simulator
(MuJoCo, from Emo Todorov)



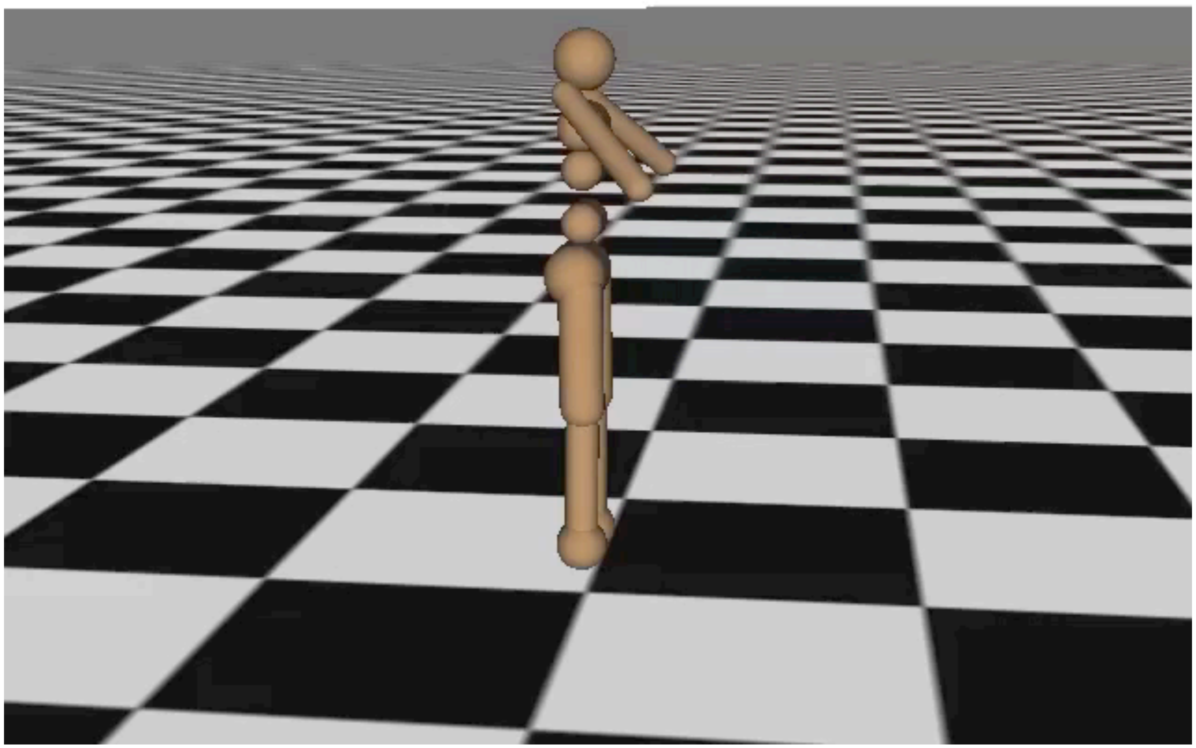
Input: joint angles and velocities
Output: joint torques

Neural network architecture:



Learning Locomotion

Iteration 0



[Schulman, Moritz, Levine, Jordan, Abbeel, 2015]

Deep RL: Virtual Stuntman

[Peng, Abbeel, Levine, van de Panne, 2018]

Quadruped

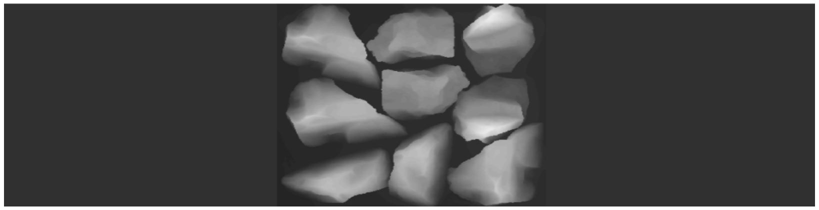
- Low-level control problem: moving a foot into a new location
  → search with successor function ~ moving the motors
- High-level control problem: where should we place the feet?
  - Reward function R(x) = w . f(s)   [25 features]

[Kolter, Abbeel & Ng, 2008]

Reward Learning + Reinforcement Learning

- Demonstrate path across the "training terrain"

- Learn the reward function
- Receive "testing terrain"---height map.



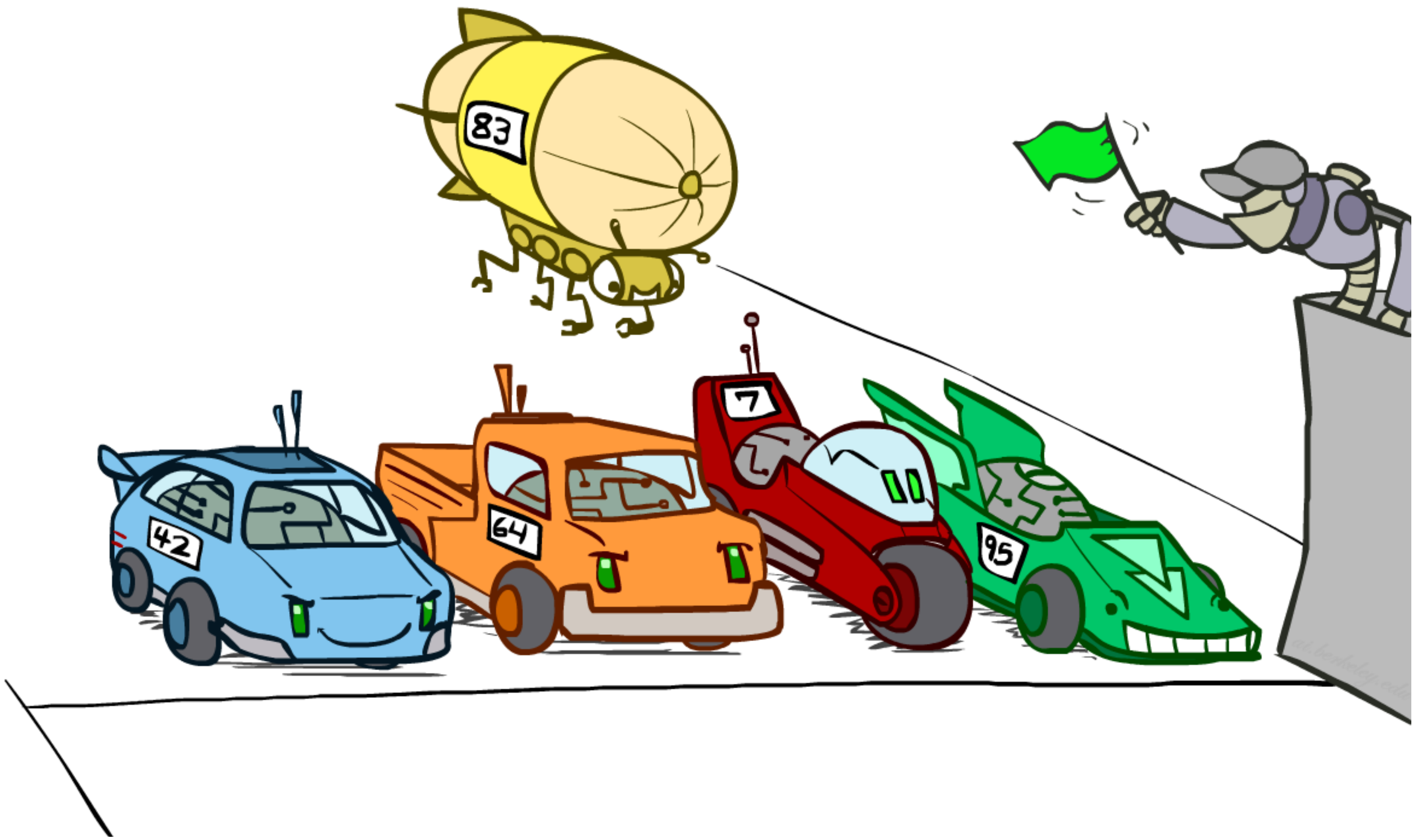
- Find the optimal policy with respect to the *learned reward function* for crossing the testing terrain.

[Kolter, Abbeel & Ng, 2008]

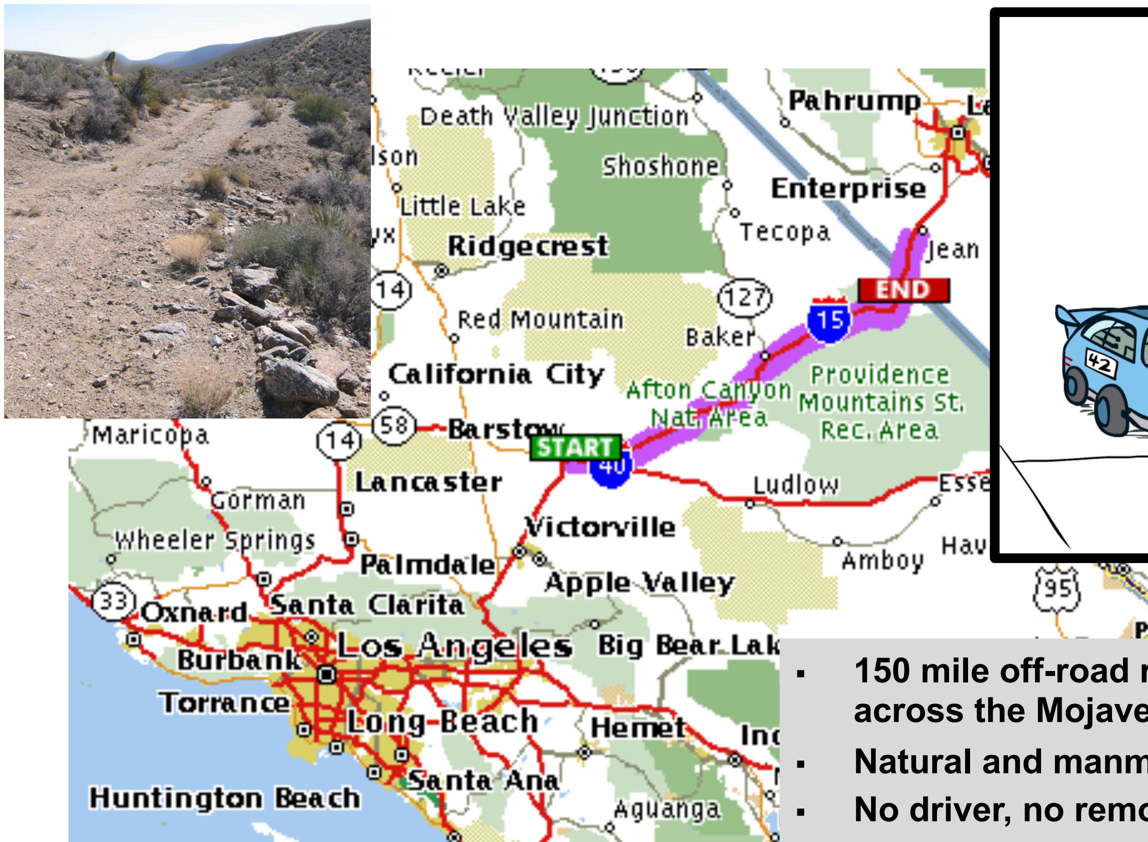
Without reward learning

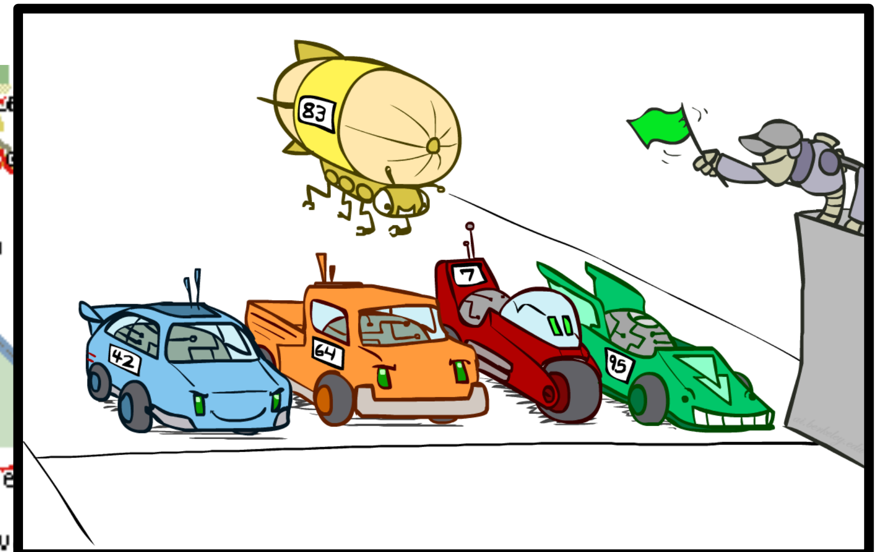
With reward learning

Autonomous Driving



Grand Challenge 2005: Barstow, CA, to Primm, NV





- 150 mile off-road robot race across the Mojave desert
- Natural and manmade hazards
- No driver, no remote control
- No dynamic passing

Autonomous Vehicles

Autonomous vehicle slides adapted from Sebastian Thrun

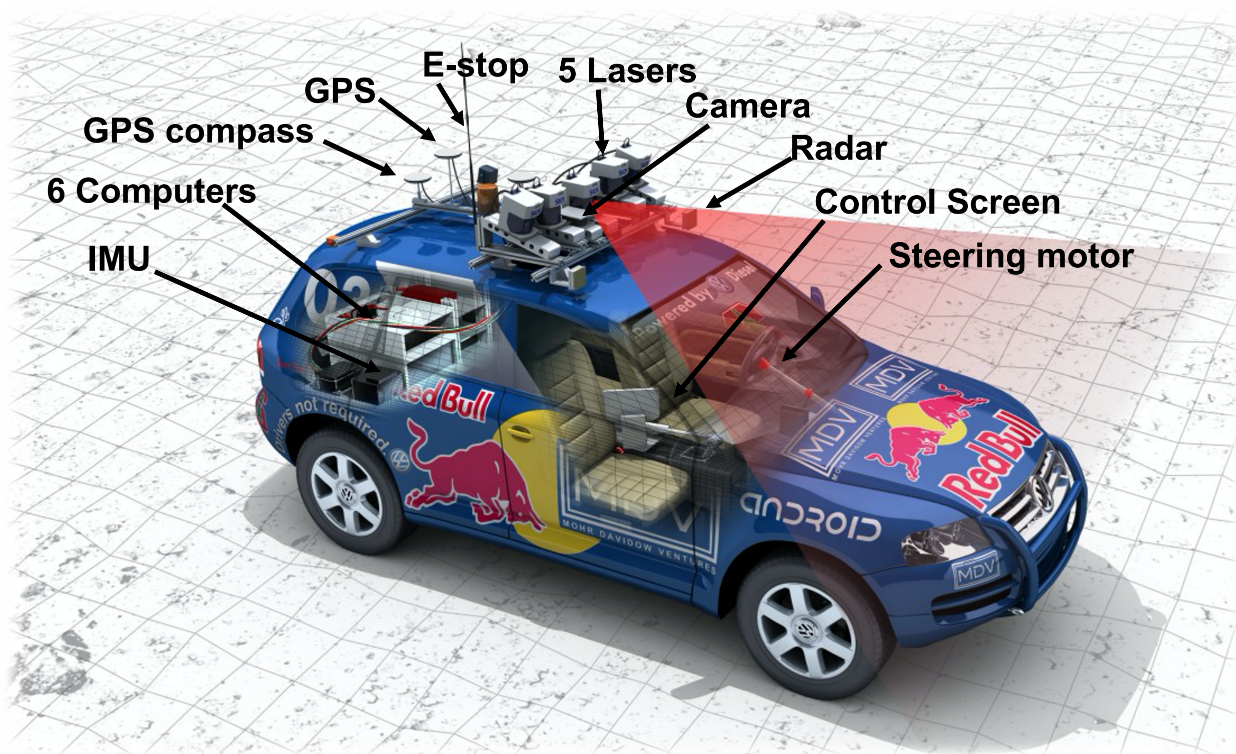
Grand Challenge 2005 Nova Video

[VIDEO: nova-race-supershort.mp4]

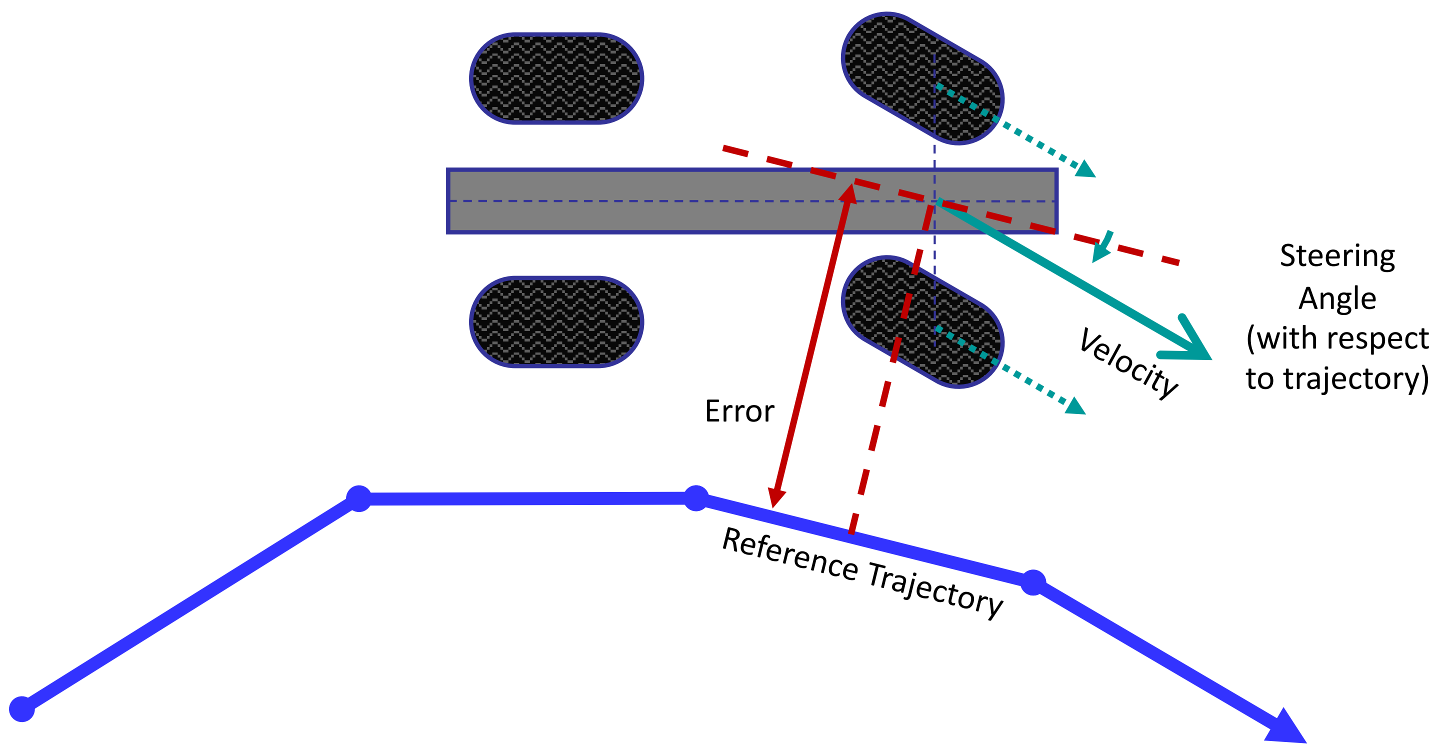
Grand Challenge 2005 – Bad

[VIDEO: grand challenge – bad.wmv]

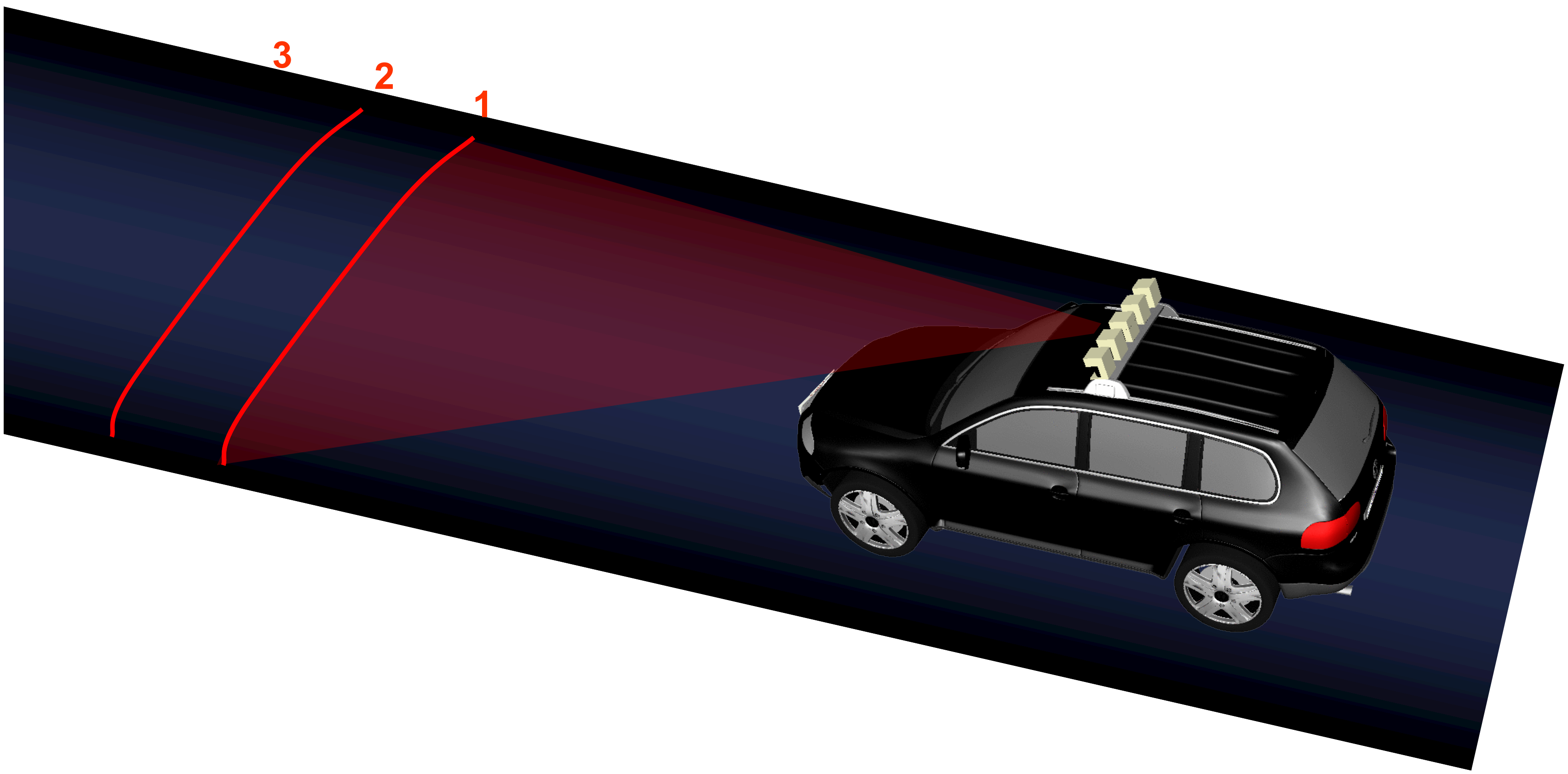
An Autonomous Car



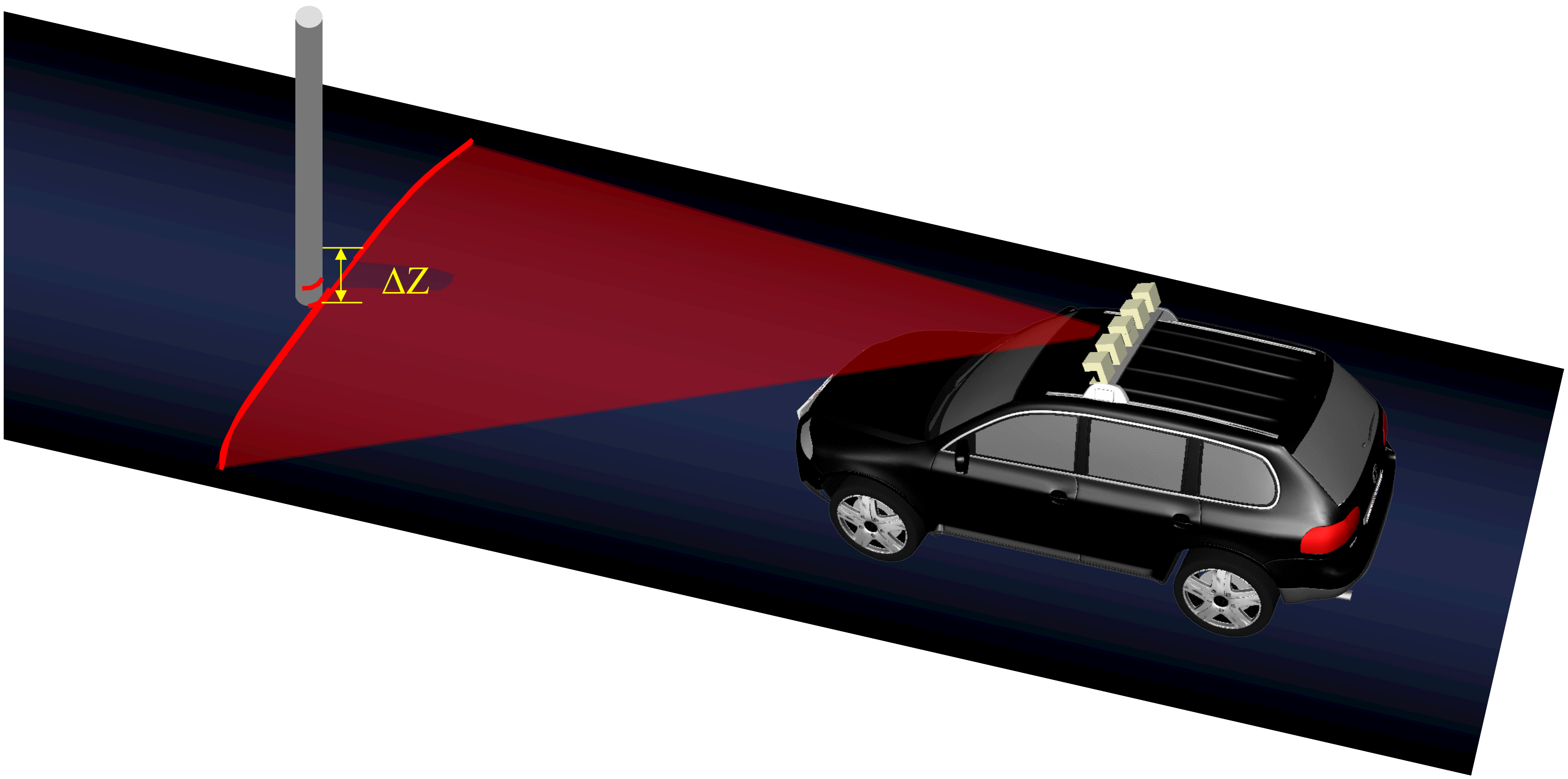
Actions: Steering Control



Laser Readings for Flat / Empty Road

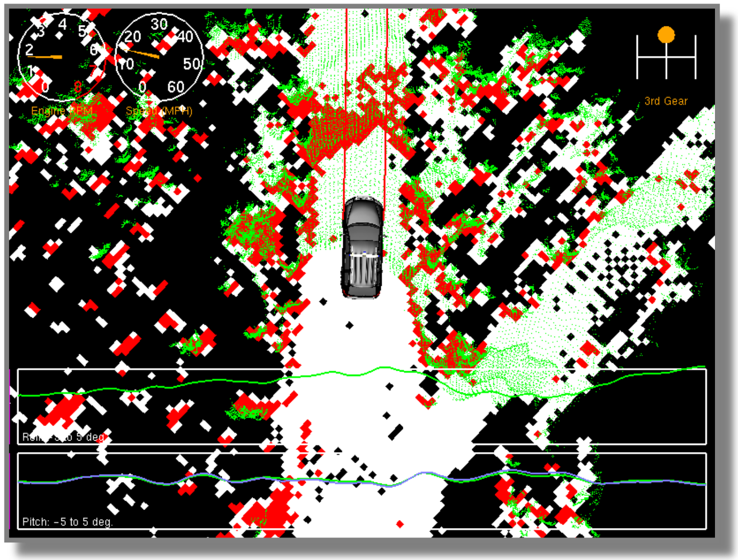


Laser Readings for Road with Obstacle



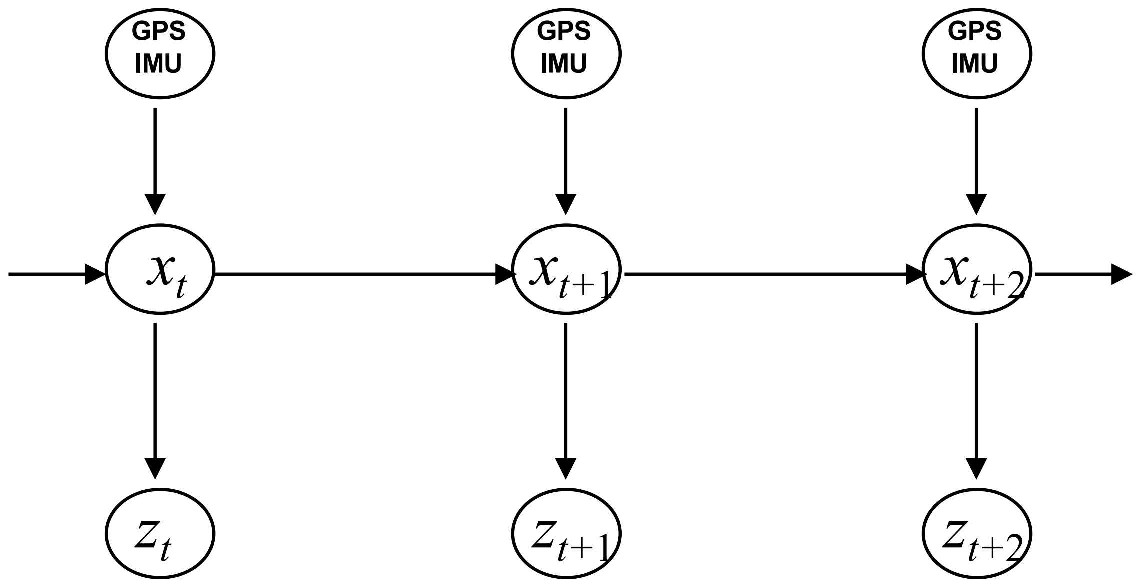
Obstacle Detection

Trigger if $|Z^i - Z^j| > 15\text{cm}$ for nearby z^i, z^j

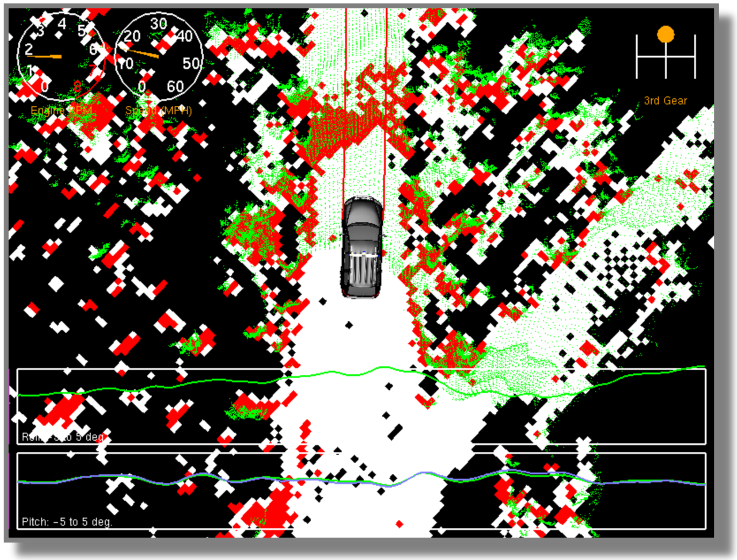


Raw Measurements: 12.6% false positives

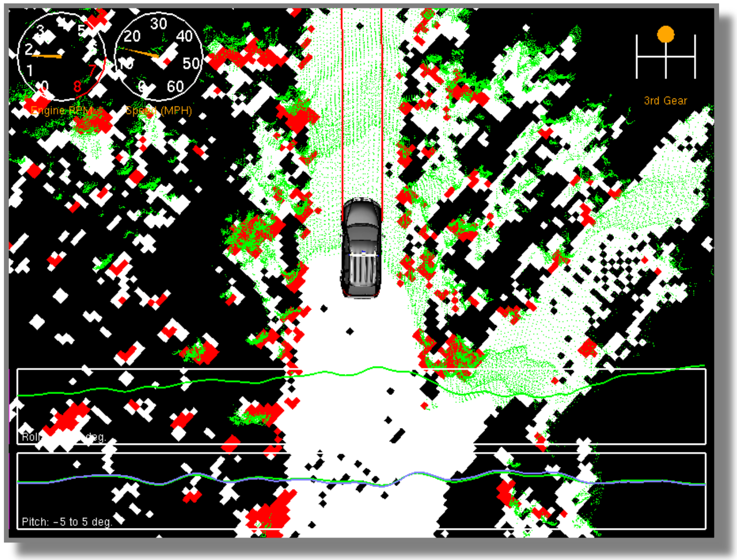
Probabilistic Error Model



HMMs for Detection

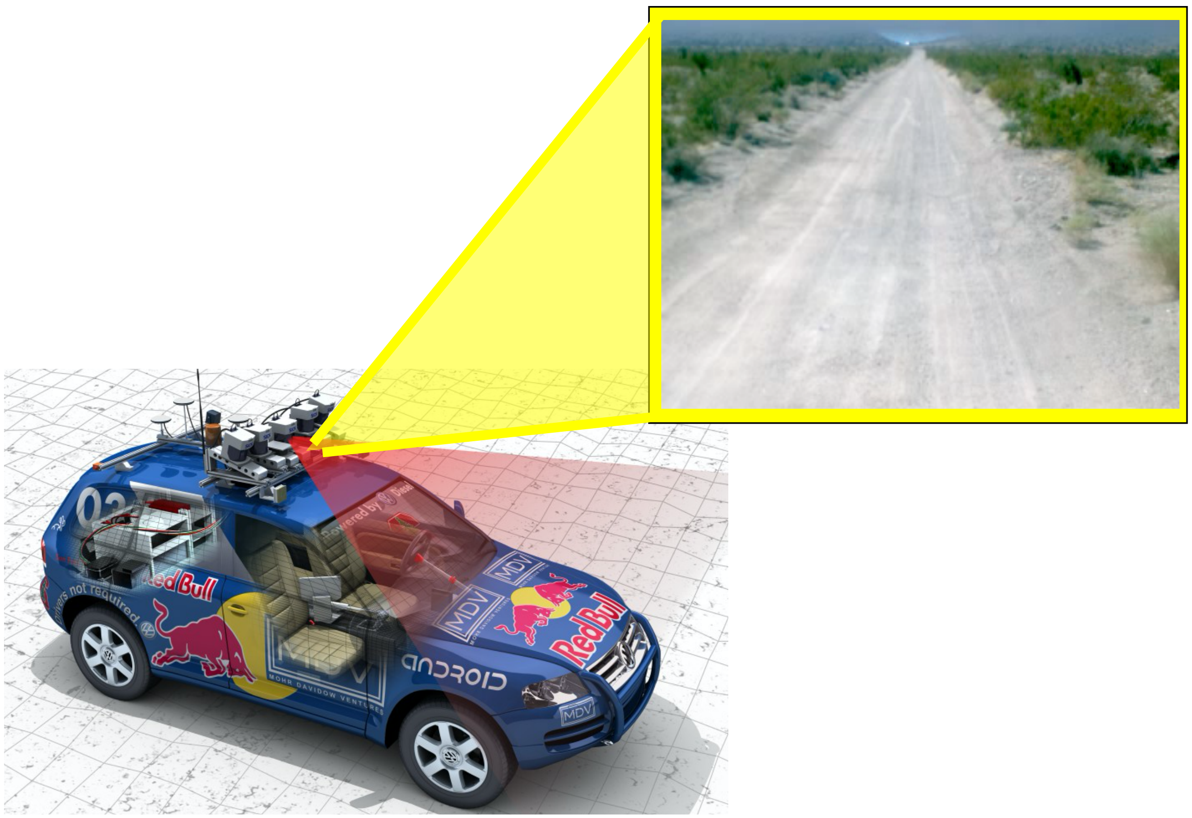


Raw Measurements: 12.6% false positives



HMM Inference: 0.02% false positives

Sensors: Camera



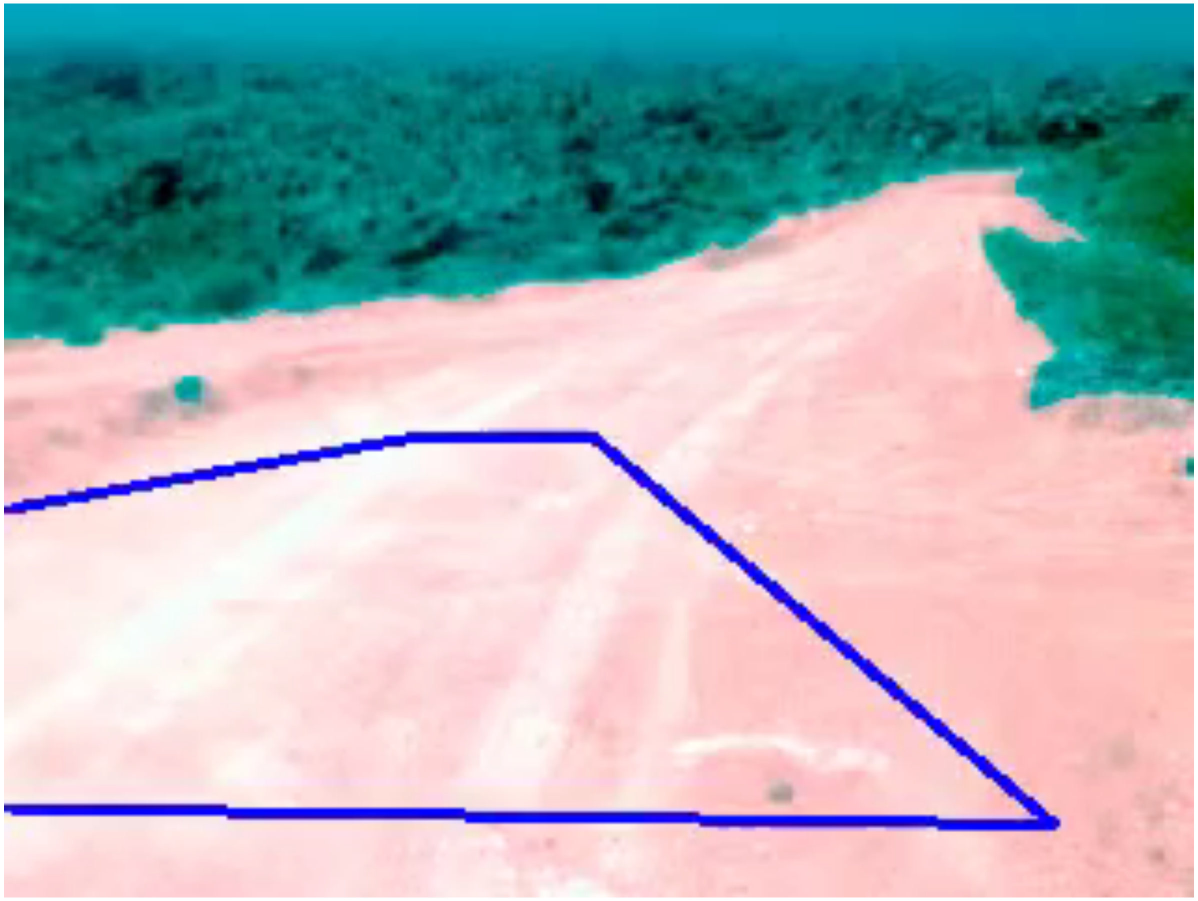
Vision for a Car

[VIDEO: lidar vision for a car]

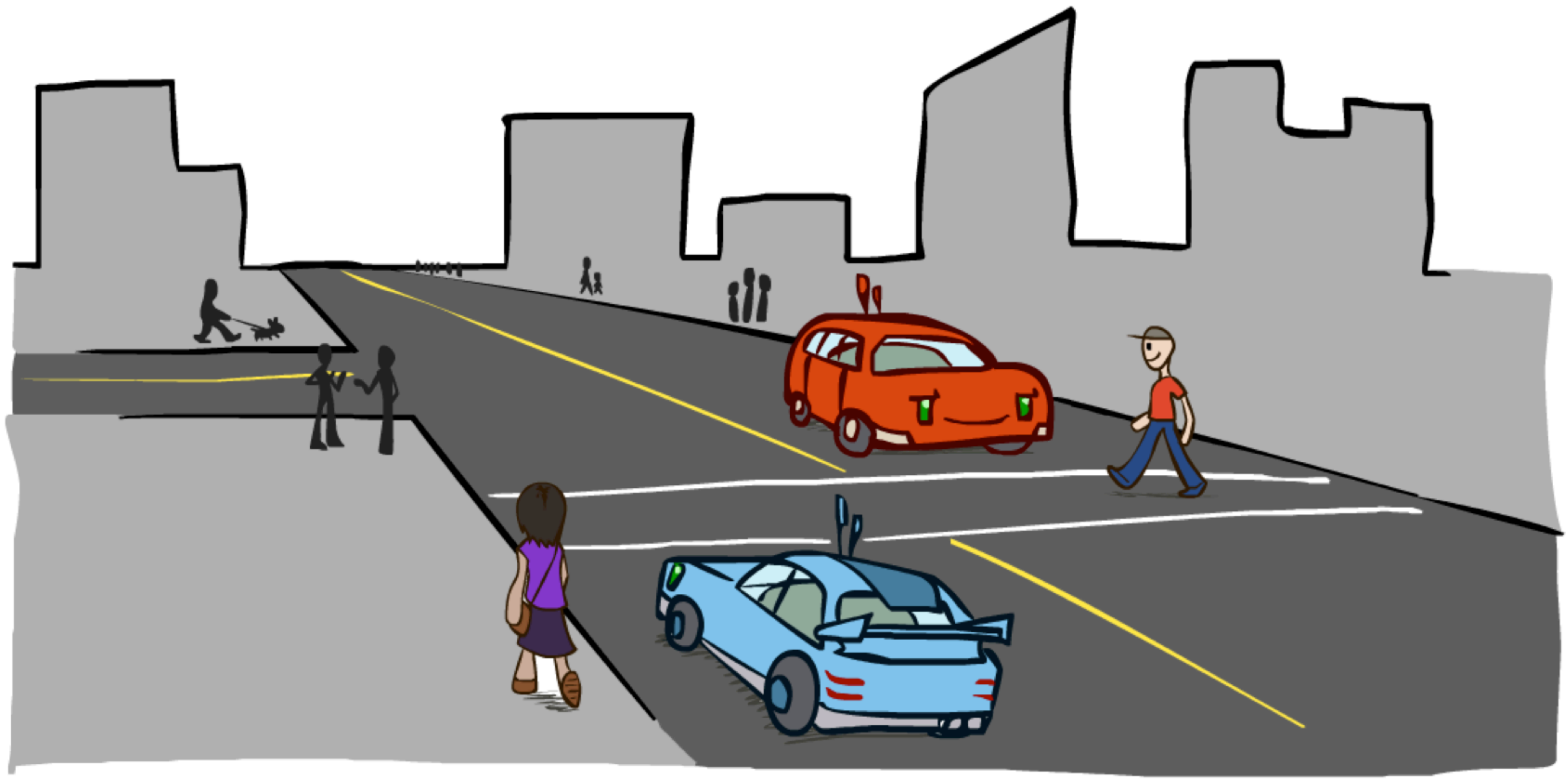
Vision for a Car

[VIDEO: self-supervised vision]

Self-Supervised Vision



Urban Environments

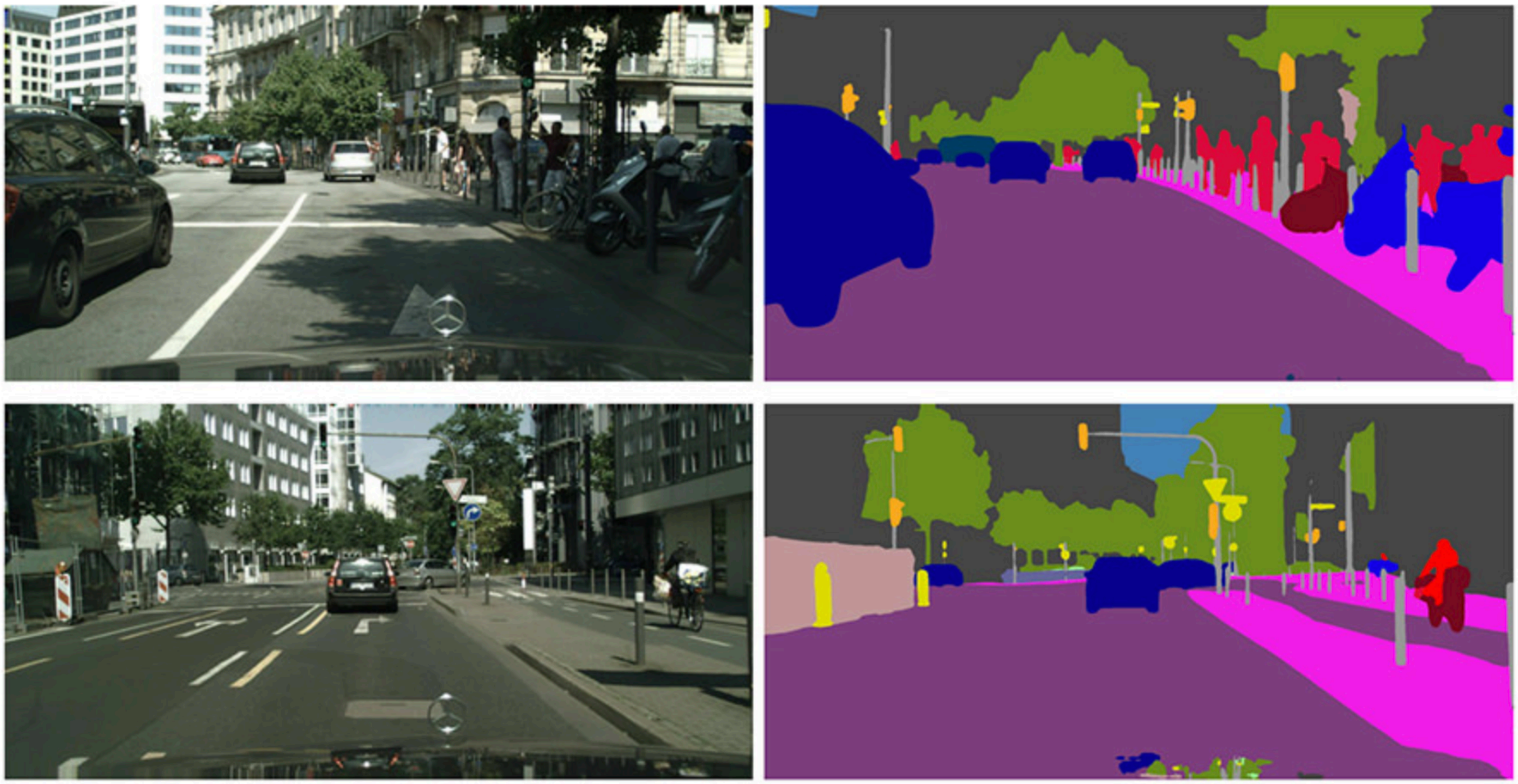


[VIDEO: ROBOTICS – gcar.m4v]

Google Self-Driving Car (2013)

(mostly lidar)

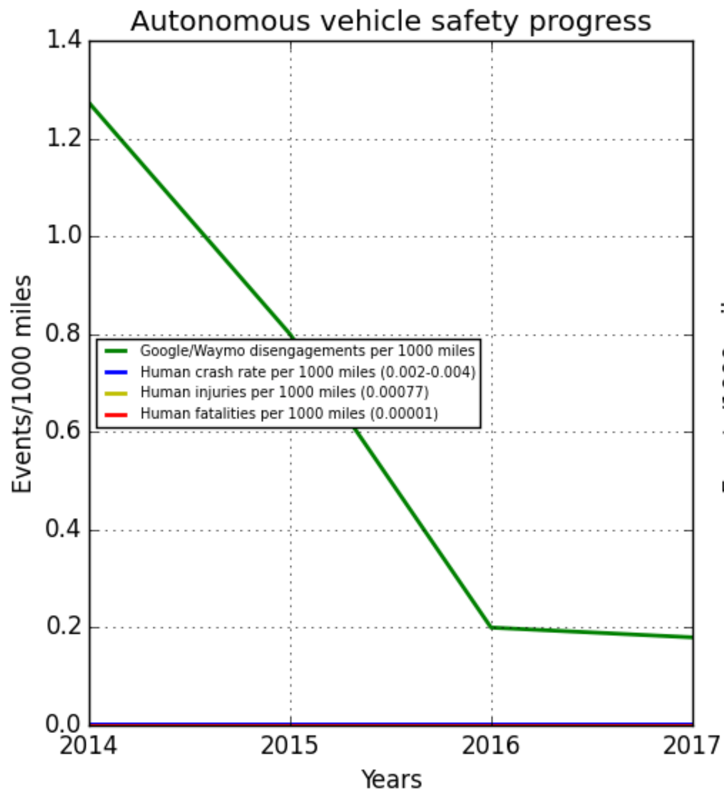
Recent Progress: NN Semantic Scene Segmentation

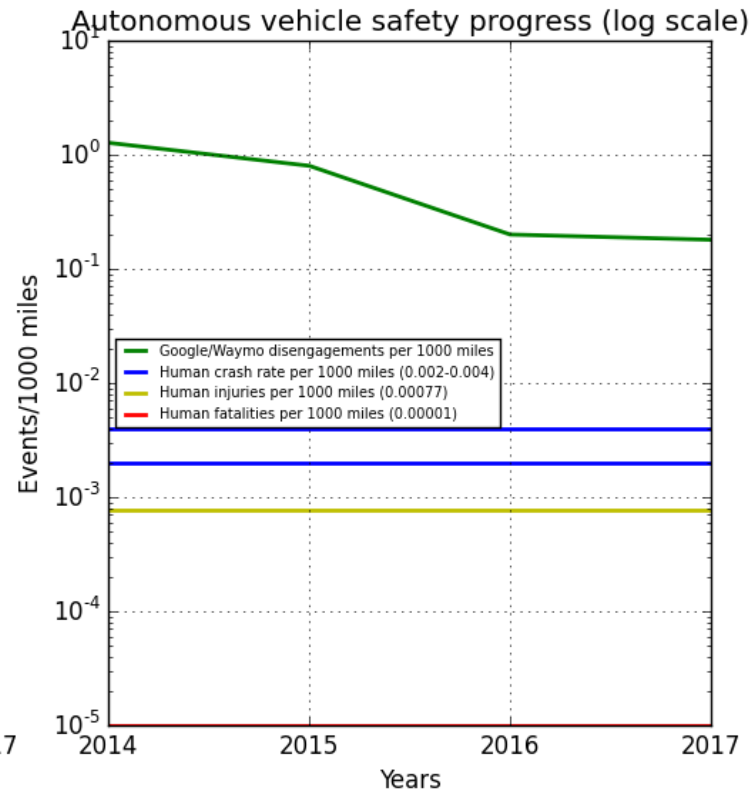


~ neural net classifies every pixel

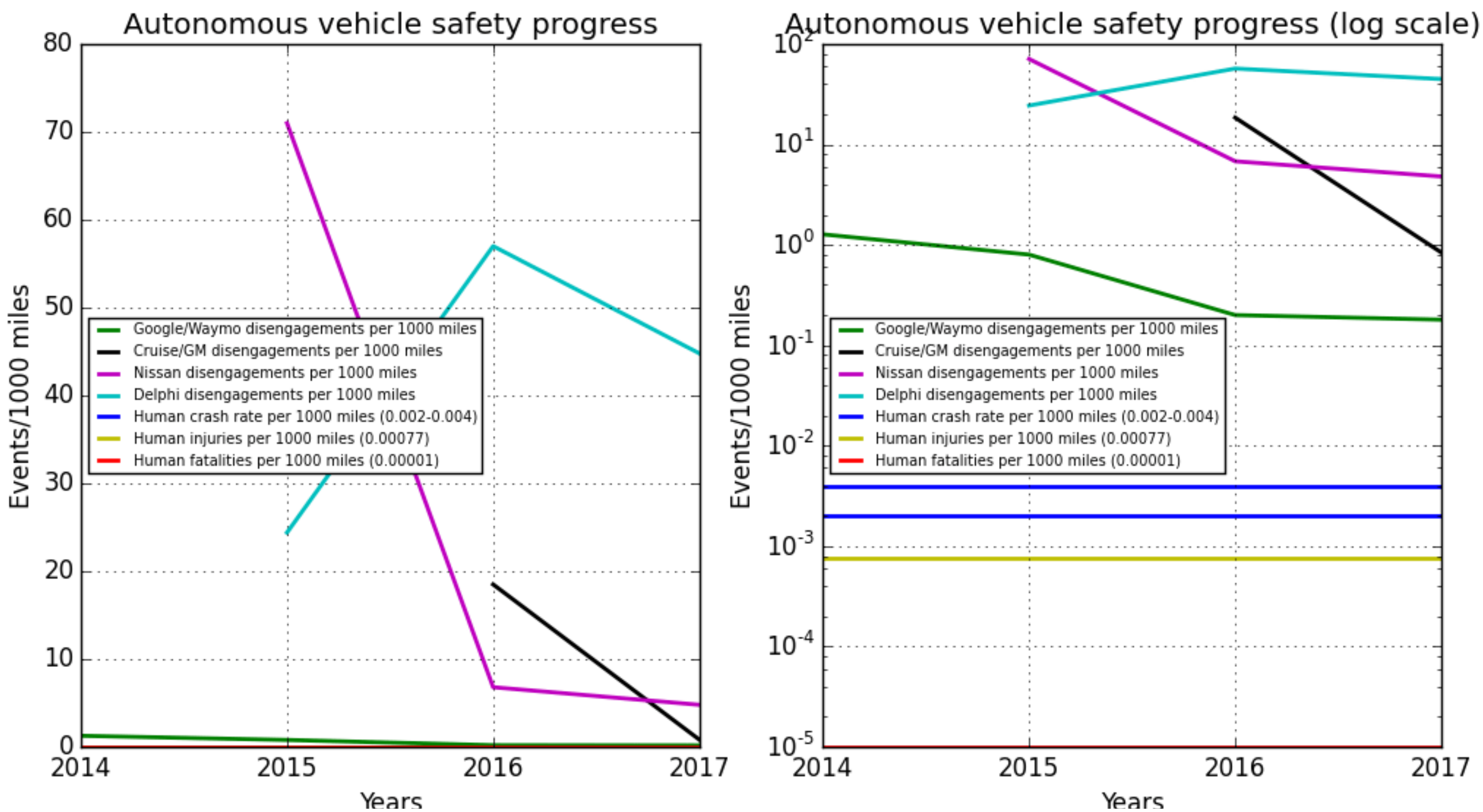
PSPNet50

Self-Driving Cars -- Stats





Self-Driving Cars -- Stats



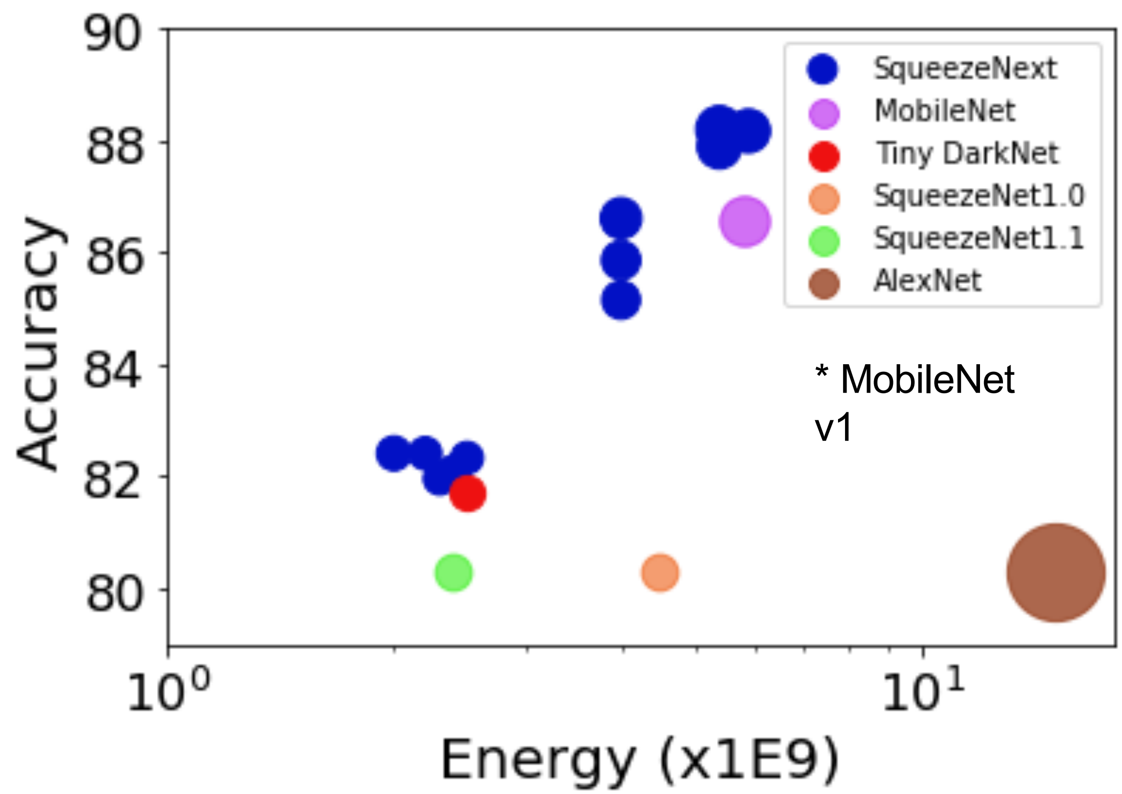
Energy-Inference-Accuracy Landscape on the Squeezelator

SqueezeNext vs

SqueezeNet/AlexNet

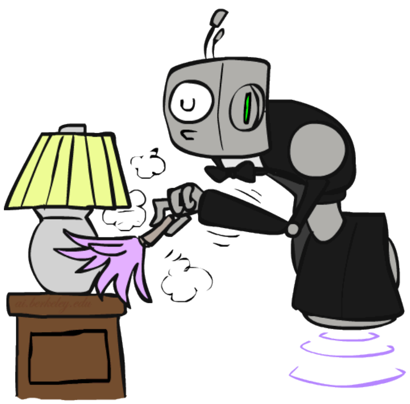
- 8% more accurate
- 2.25x better than SqueezeNet
- 7.5x better than AlexNet

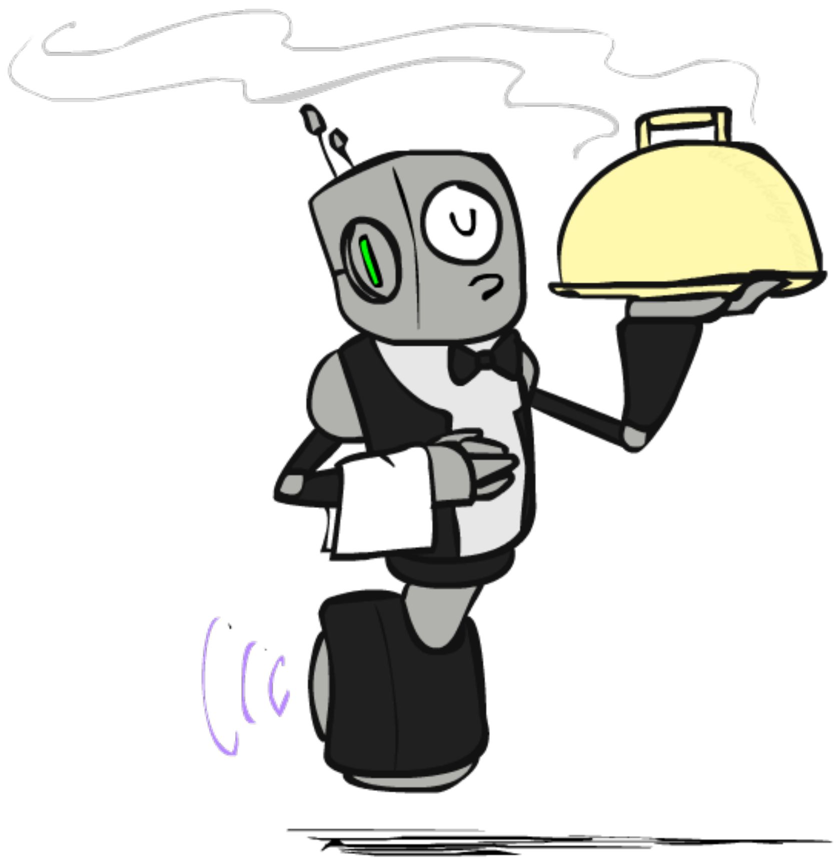
ImageNet energy-accuracy for different NNs



[slide credit: Kurt Keutzer]

Personal Robotics



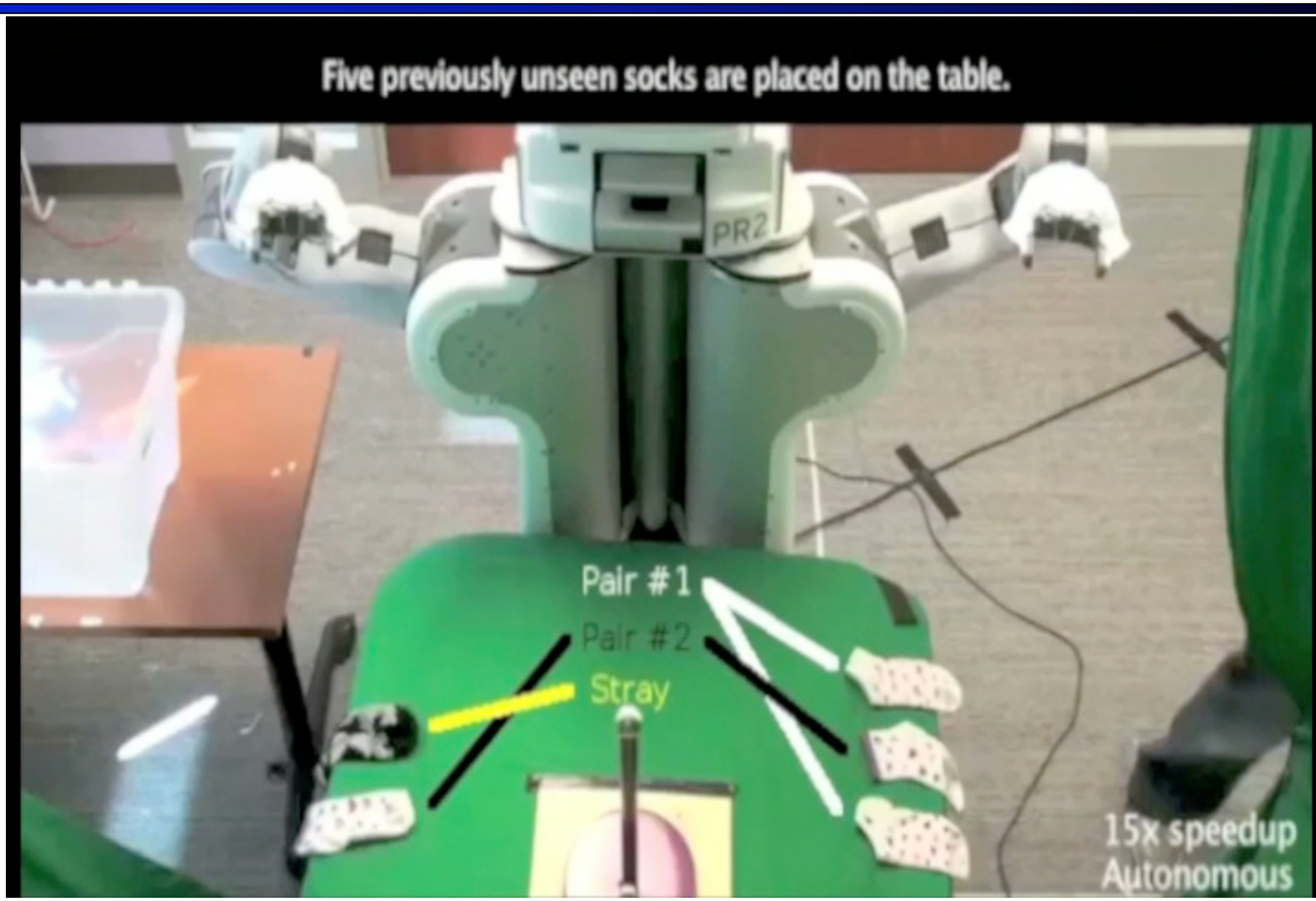


PR-1

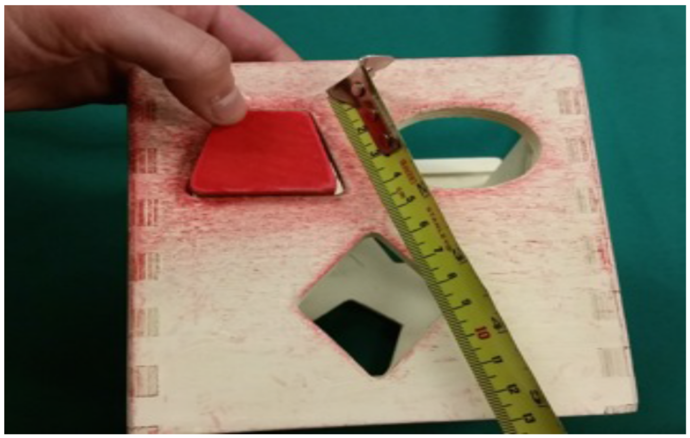
[Wyrobek, Berger, van der Loos, Salisbury, ICRA 2008]

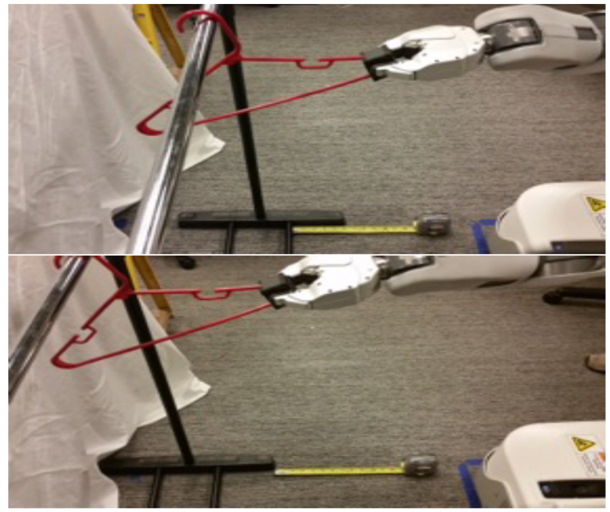
Challenge Task: Robotic Laundry

Sock Sorting



How about a range of skills?





[Levine*, Finn*, Darrell, Abbeel, JMLR 2016]

Reinforcement Learning

[Levine*, Finn*, Darrell, Abbeel, JMLR 2016]

Learned Skills

[Levine*, Finn*, Darrell, Abbeel, JMLR 2016]

[Levine et al, 2016]