Attractor dynamics approach to behavior generation: vehicle motion Part 2: sub-symbolic approach

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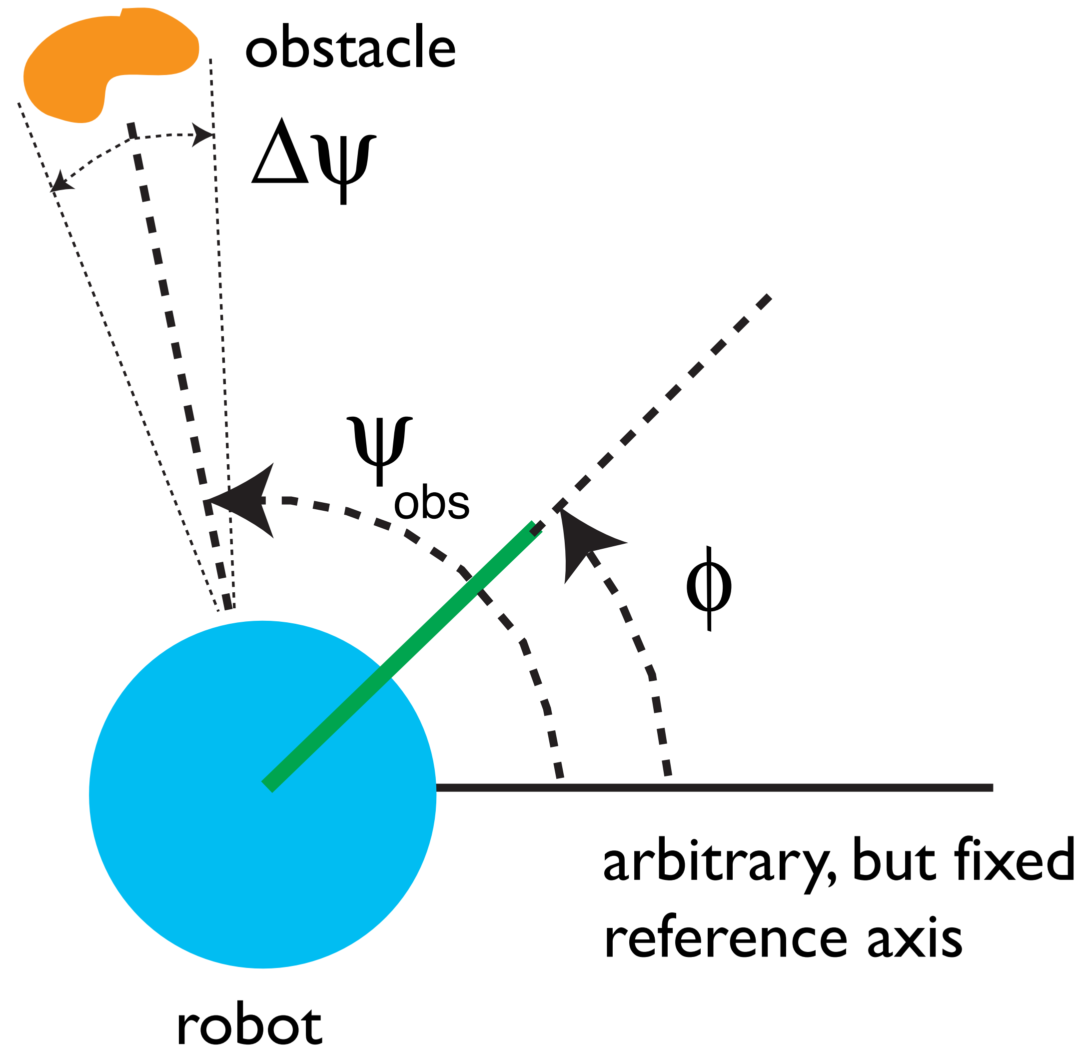
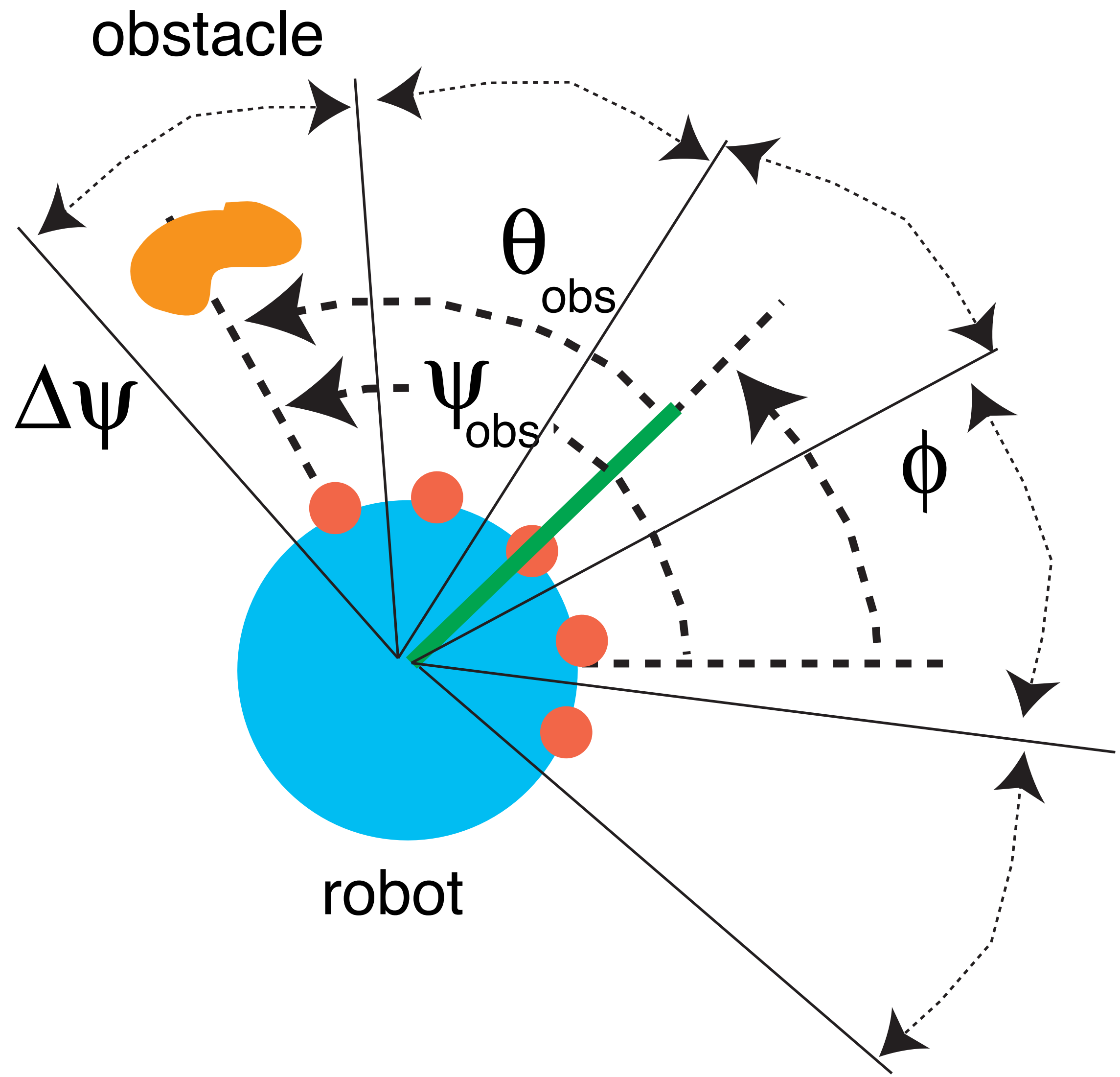
So far: “symbolic” approach

- high-level implementation: knowledge about objects in the world (“obstacles”, “targets”, etc)



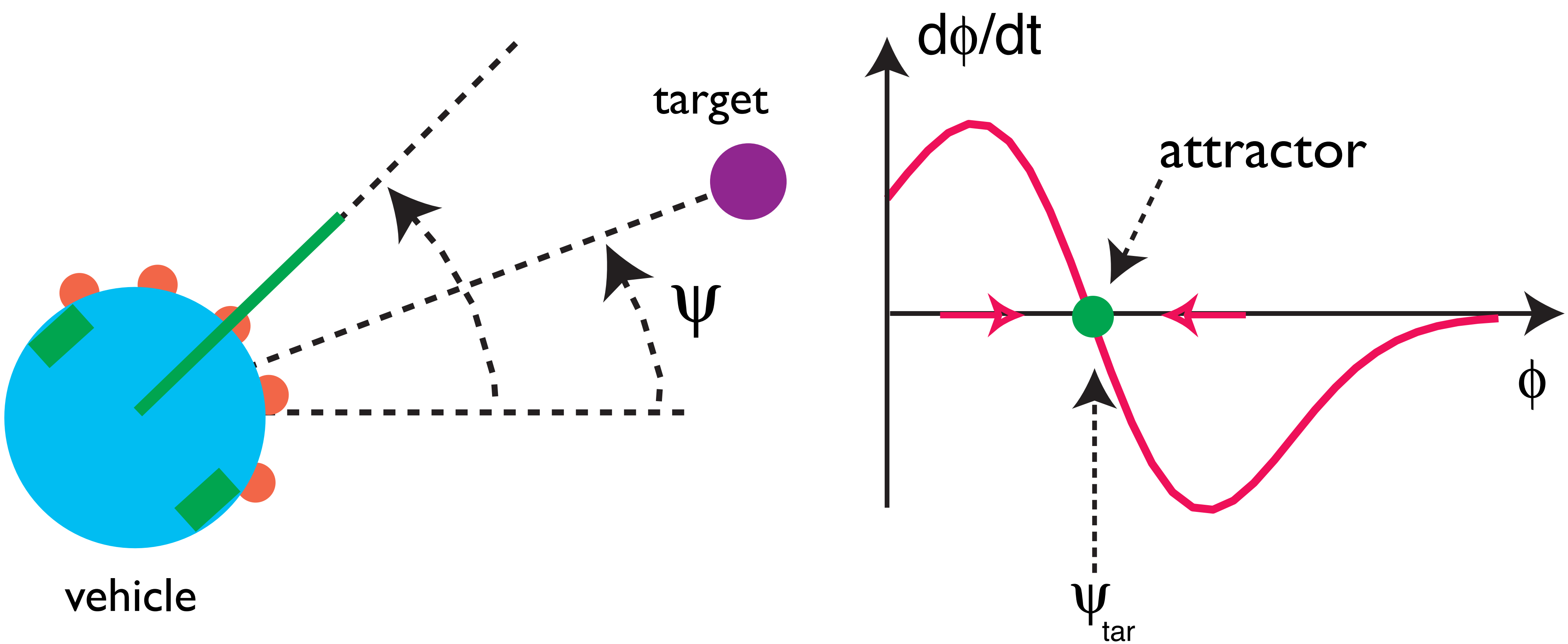
Now: "sub-symbolic" approach

- low-level implementation: use sensory information directly, not via objects



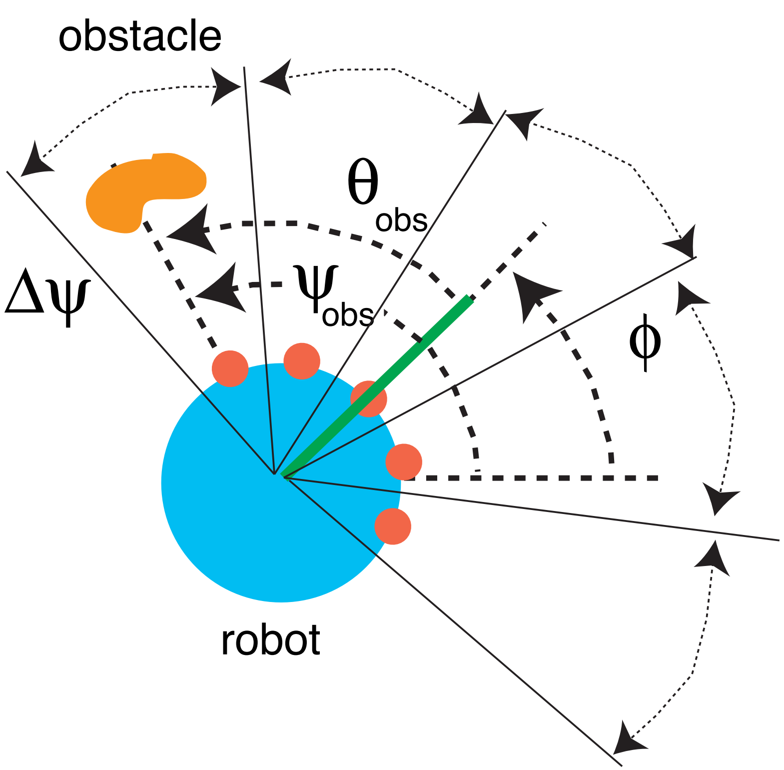
Target acquisition: still symbolic

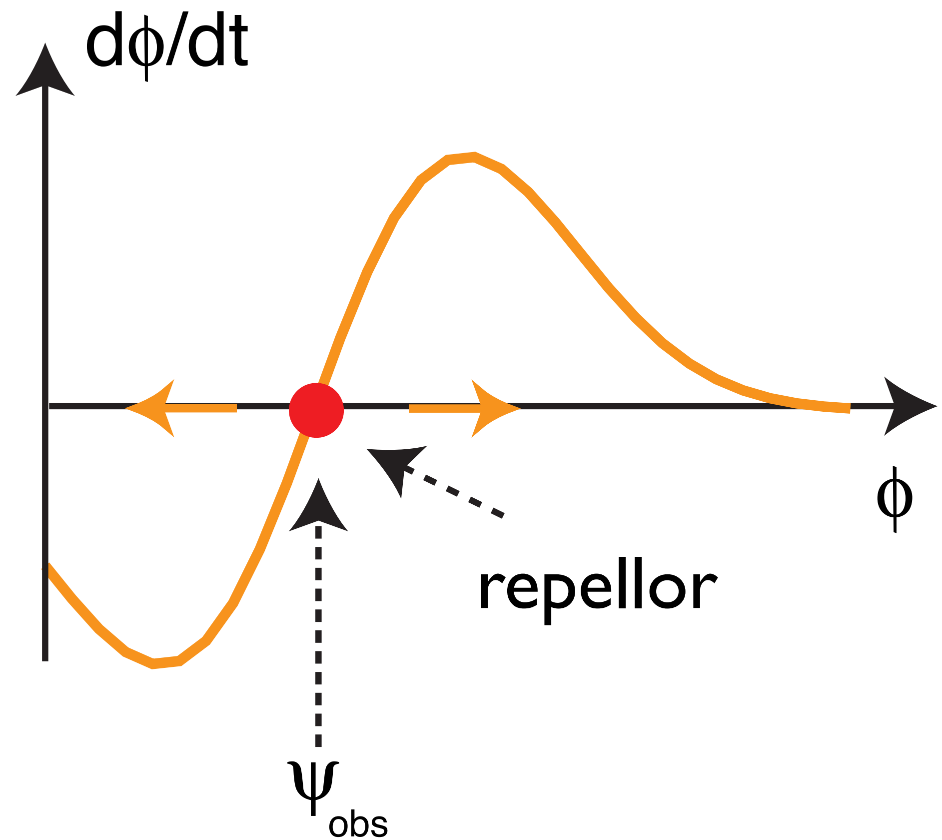
- targets are segmented… in the foreground
- => need neural fields to perform this segmentation from low-level sensory information: Dynamic Field Theory …



Obstacle avoidance: sub-symbolic

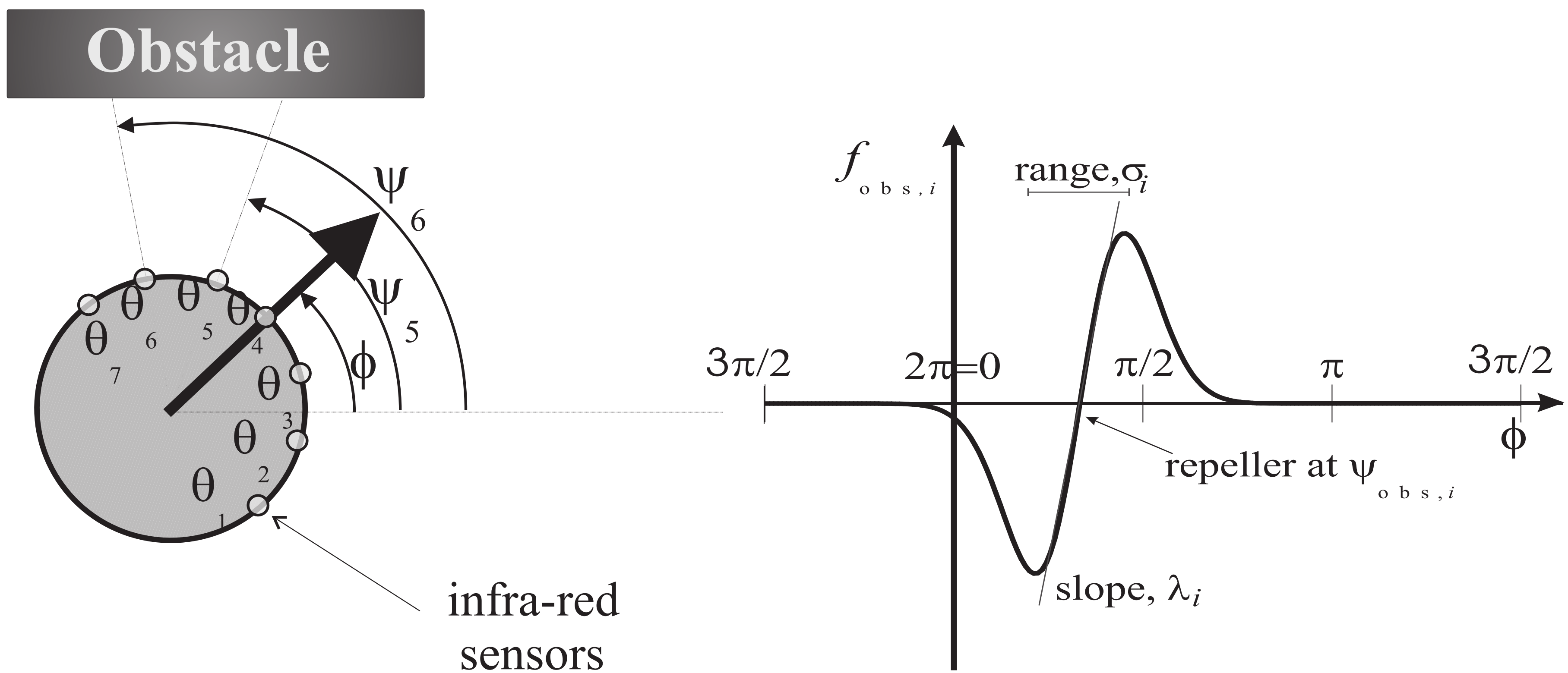
- obstacles need not be segmented
- do not care if obstacles are one or multiple: avoid them anyway…





Obstacle avoidance: sub-symbolic

- each sensor mounted at fixed angle θ
- that points in direction $\psi=\Phi+\theta$ in the world
- erect a repellor at that angle

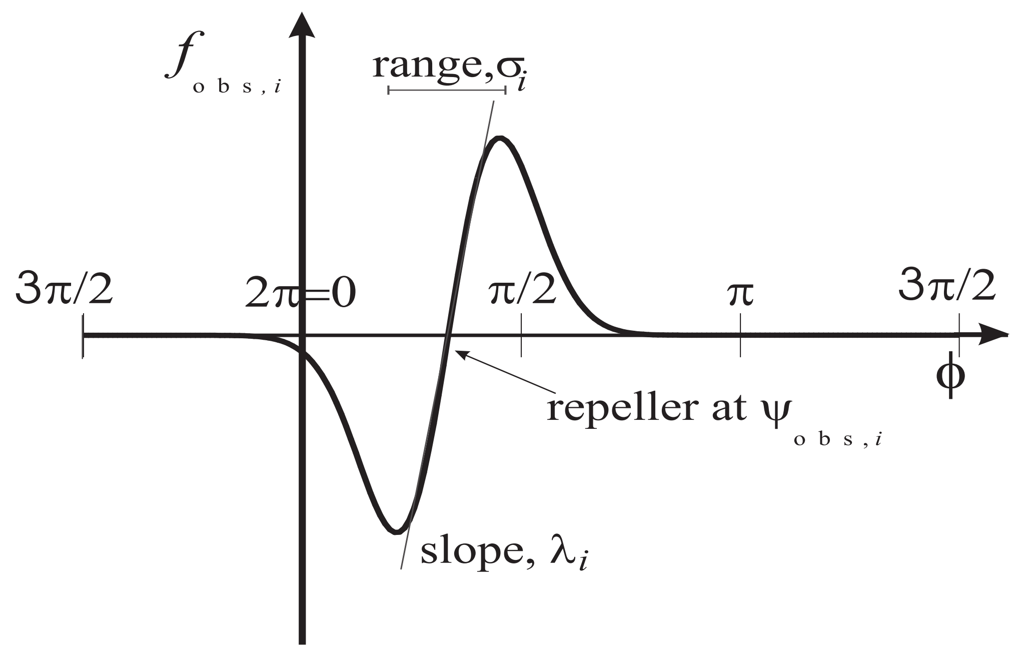


[from: Bicho, Jokeit, Schöner]

Obstacle avoidance: sub-symbolic

$$f_{\mathrm{obs},i}(\phi) = \lambda_i(\phi - \psi_i)\exp\left[-\frac{(\phi-\psi_i)^2}{2\sigma_i^2}\right] \qquad i = 1, 2, \ldots, 7$$

- Note: only Φ-ψ=-θ shows up, which is constant!
- => force-let does not depend on Φ !



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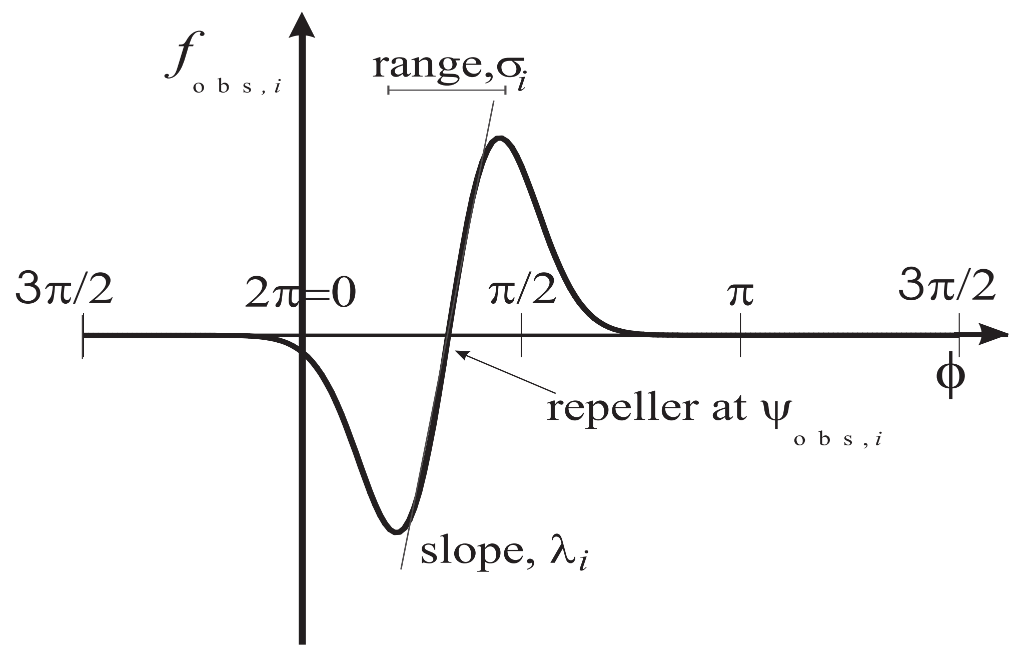
$$\lambda_i = \beta_1 \cdot \exp\left[-\frac{d_i}{\beta_2}\right]$$

- Repulsion strength decreases with distance, d_i
- => only close obstacles matter



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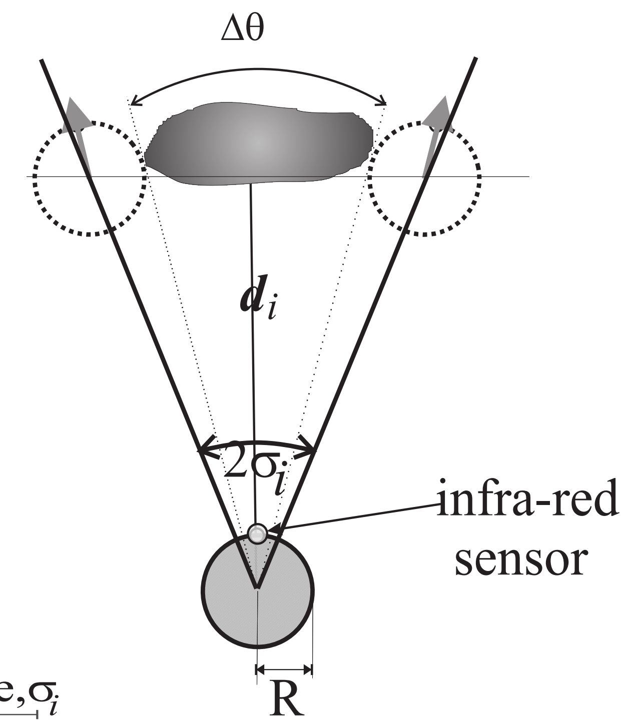
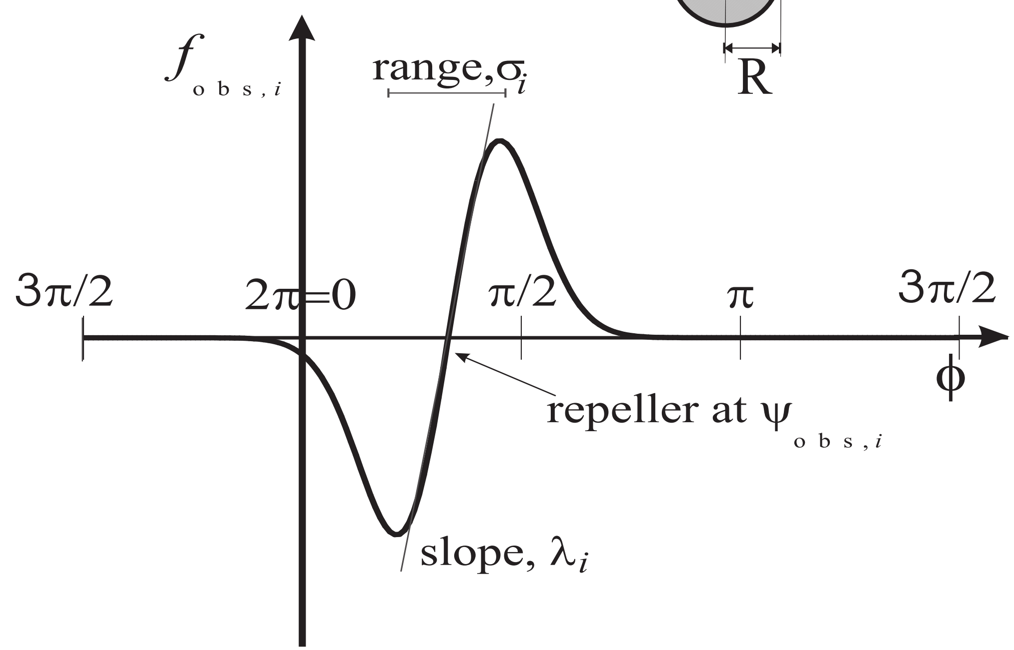
$$\sigma_i = \arctan\left[\tan\left(\frac{\Delta\theta}{2}\right) + \frac{R_{\text{robot}}}{R_{\text{robot}} + d_i}\right].$$



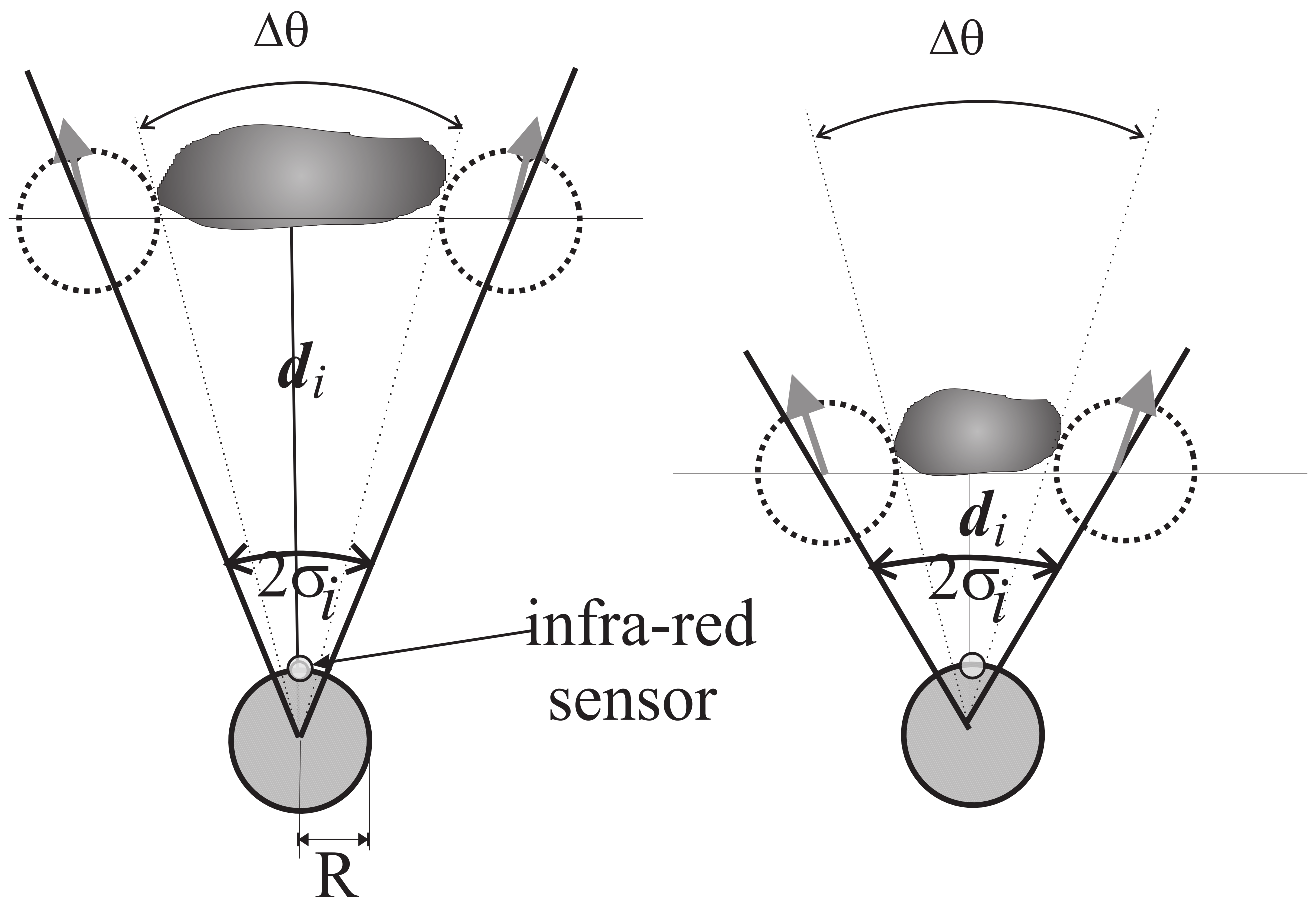
- angular range depends on sensor cone Δθ and size over distance



[from: Bicho, Jokeit, Schöner]

Obstacle avoidance: sub-symbolic

- => as a result, range becomes wider as obstacle moves closer

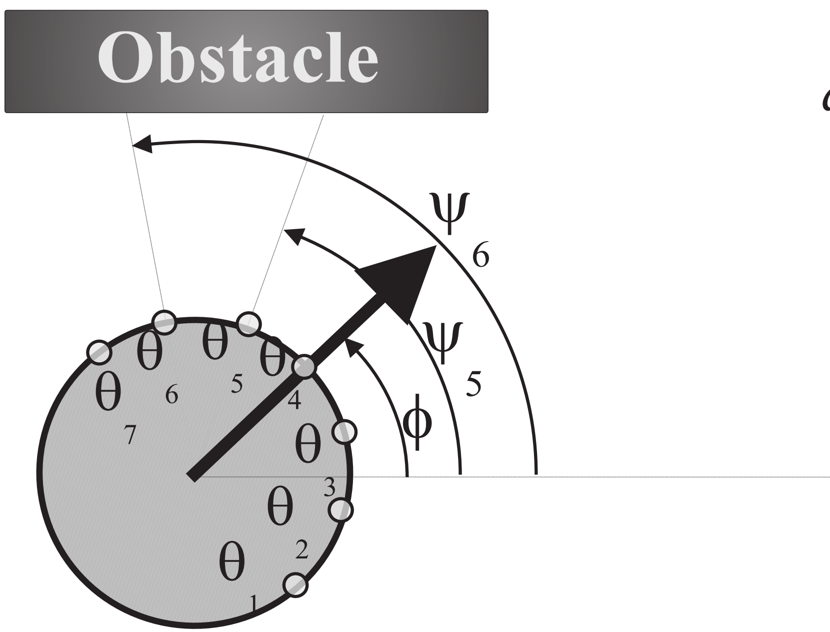


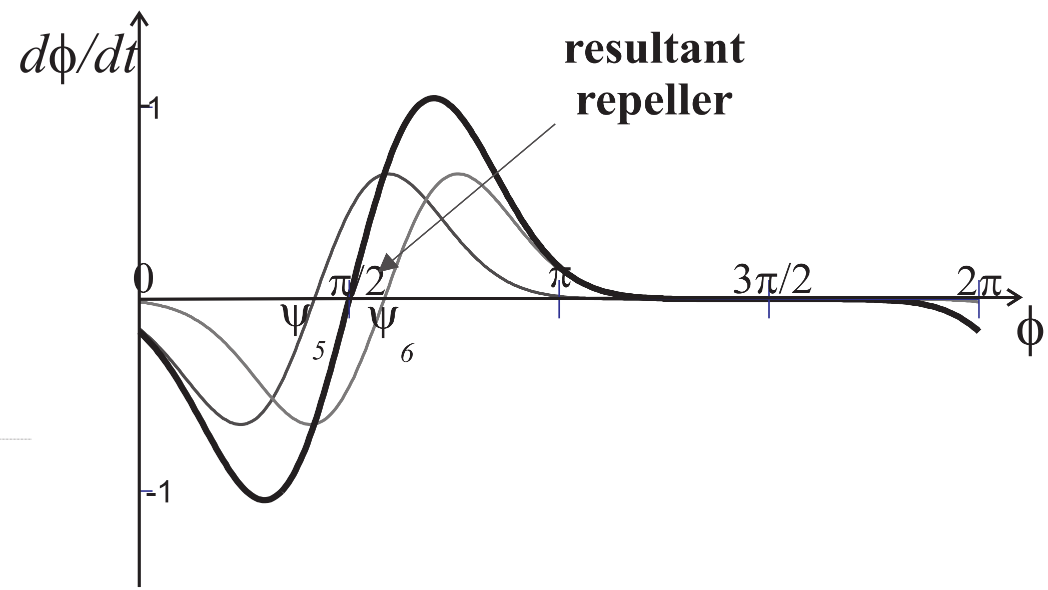
[from: Bicho, Jokeit, Schöner]

Obstacle avoidance: sub-symbolic

- summing contributions from all sensors

$$\frac{d\phi}{dt} = f_{\text{obs}}(\phi) = \sum_{i=1}^{7} f_{\text{obs},i}(\phi)$$

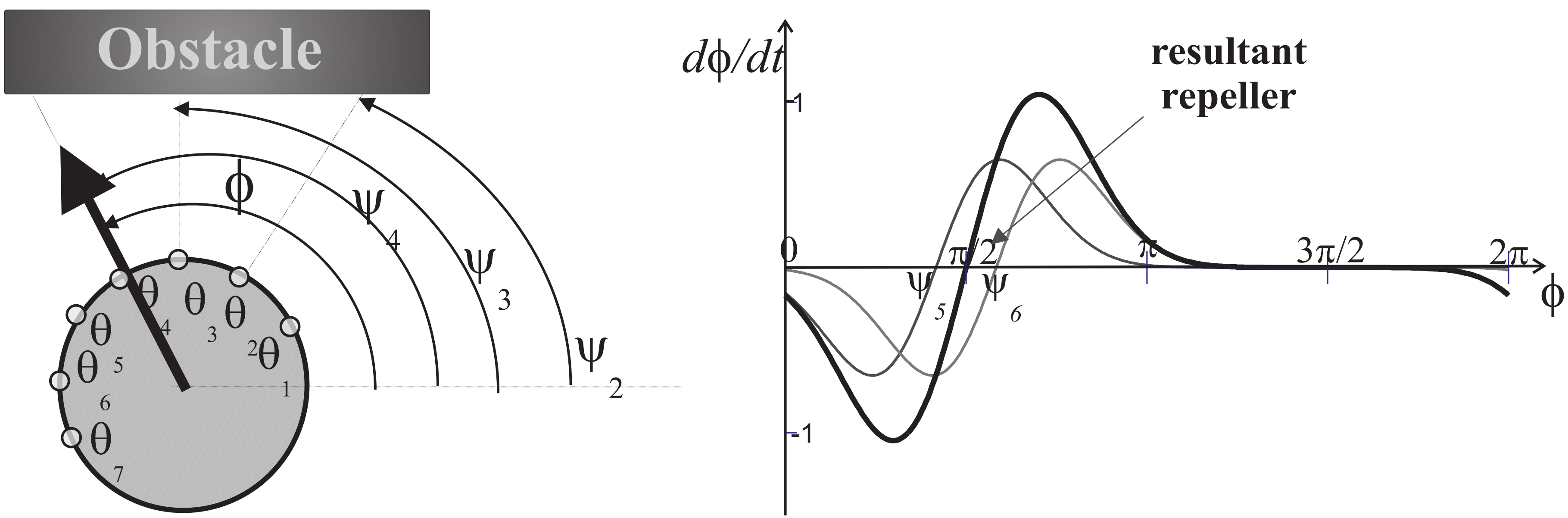




[from: Bicho, Jokeit, Schöner]

Obstacle avoidance: sub-symbolic

- but why does it work?
- shouldn't there be a problem when heading changes (e.g. from the dynamics itself)?



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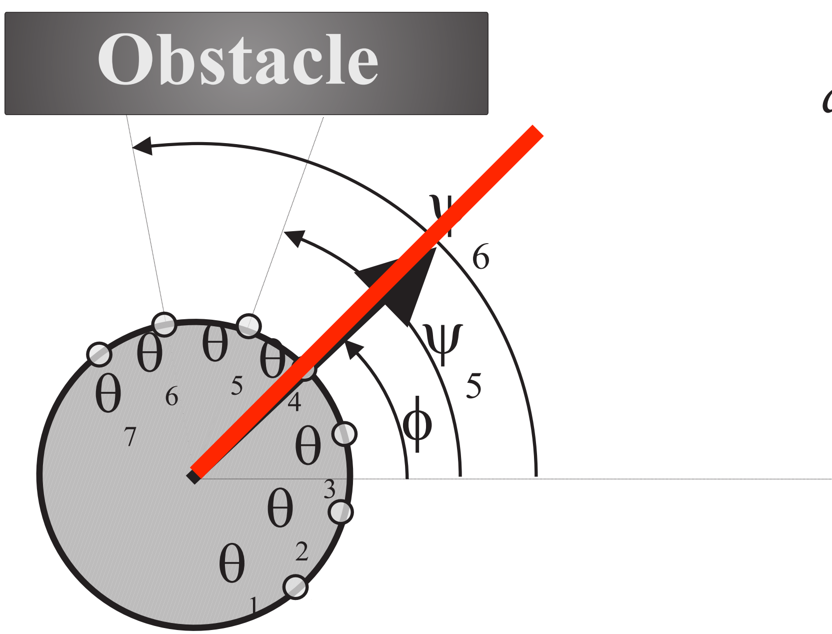

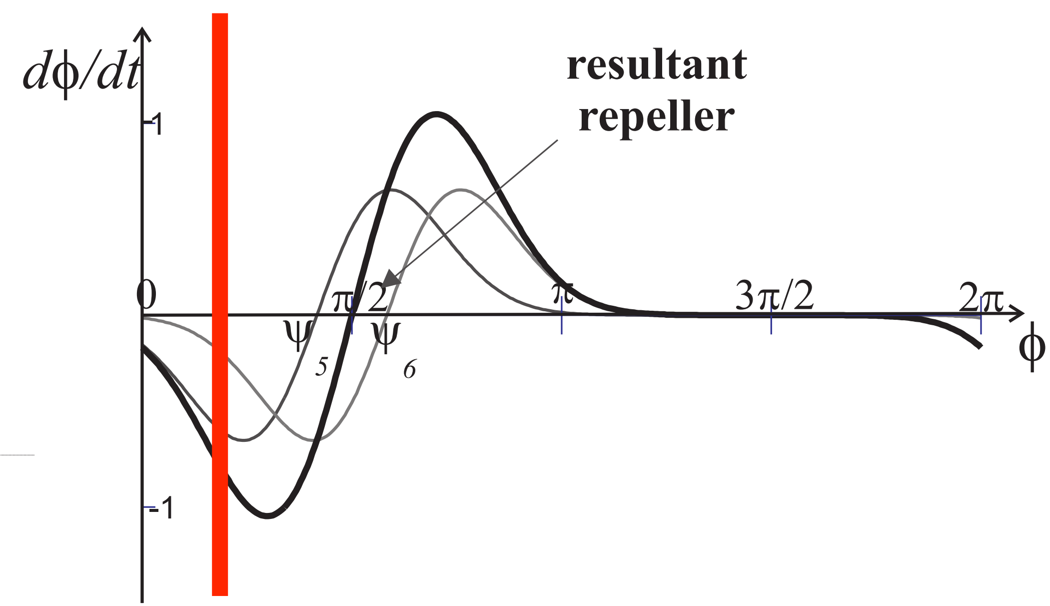

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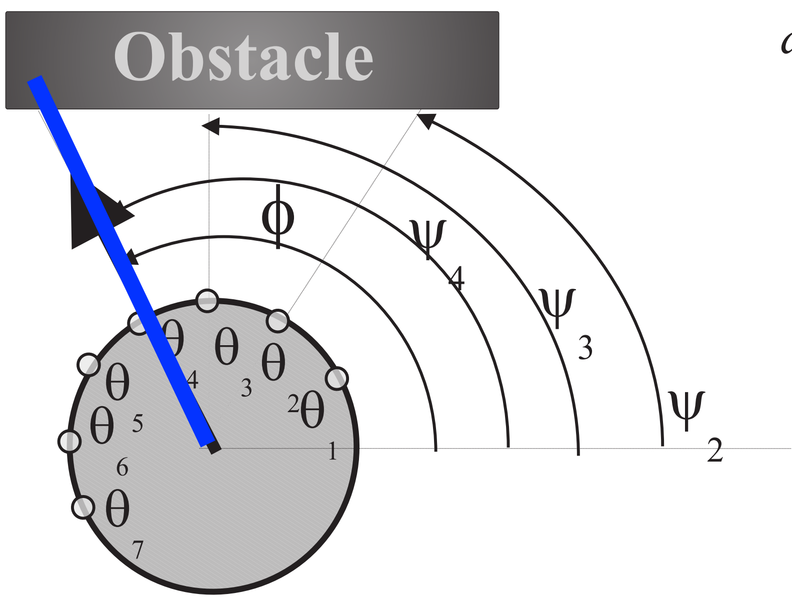

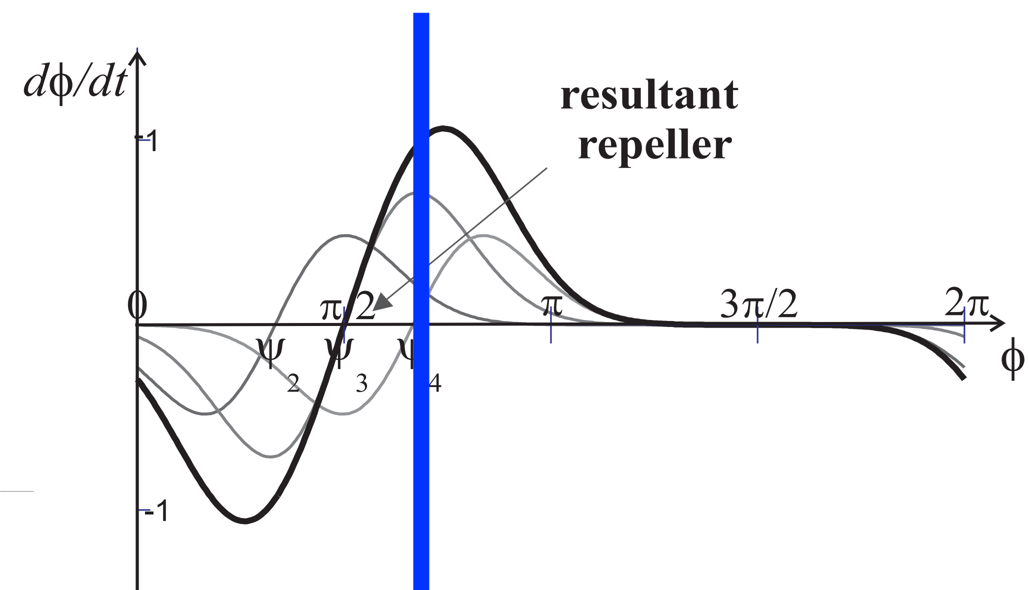

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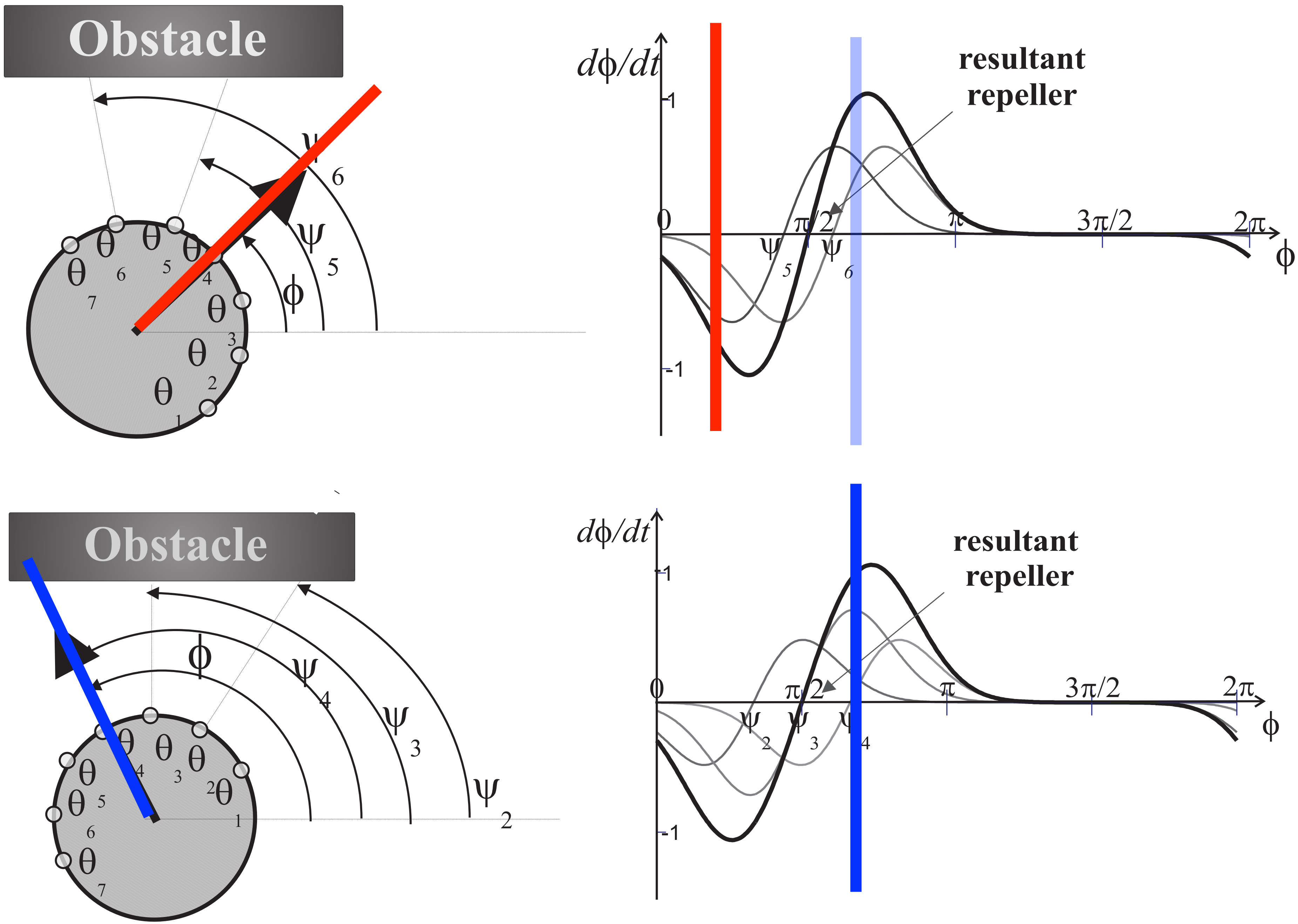


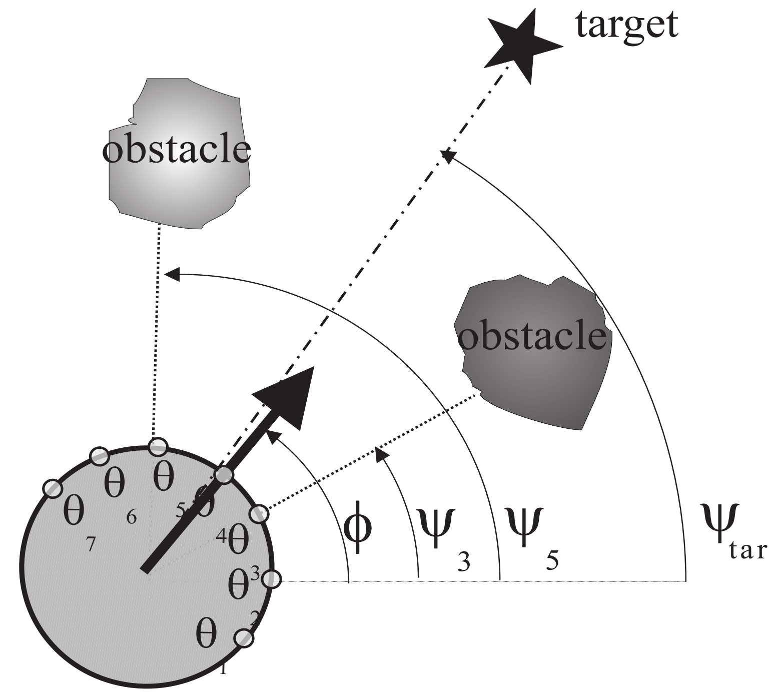
=> dynamics invariant!

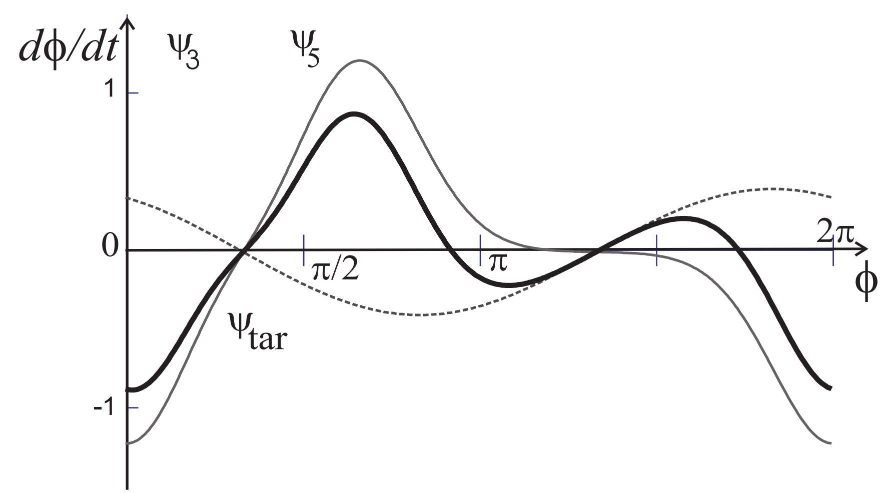
[from: Bicho, Jokeit, Schöner]

Behavioral Dynamics

- integrating the two behaviors

$$\frac{d\phi}{dt} = f_{\text{obs}}(\phi) + f_{\text{tar}}(\phi)$$

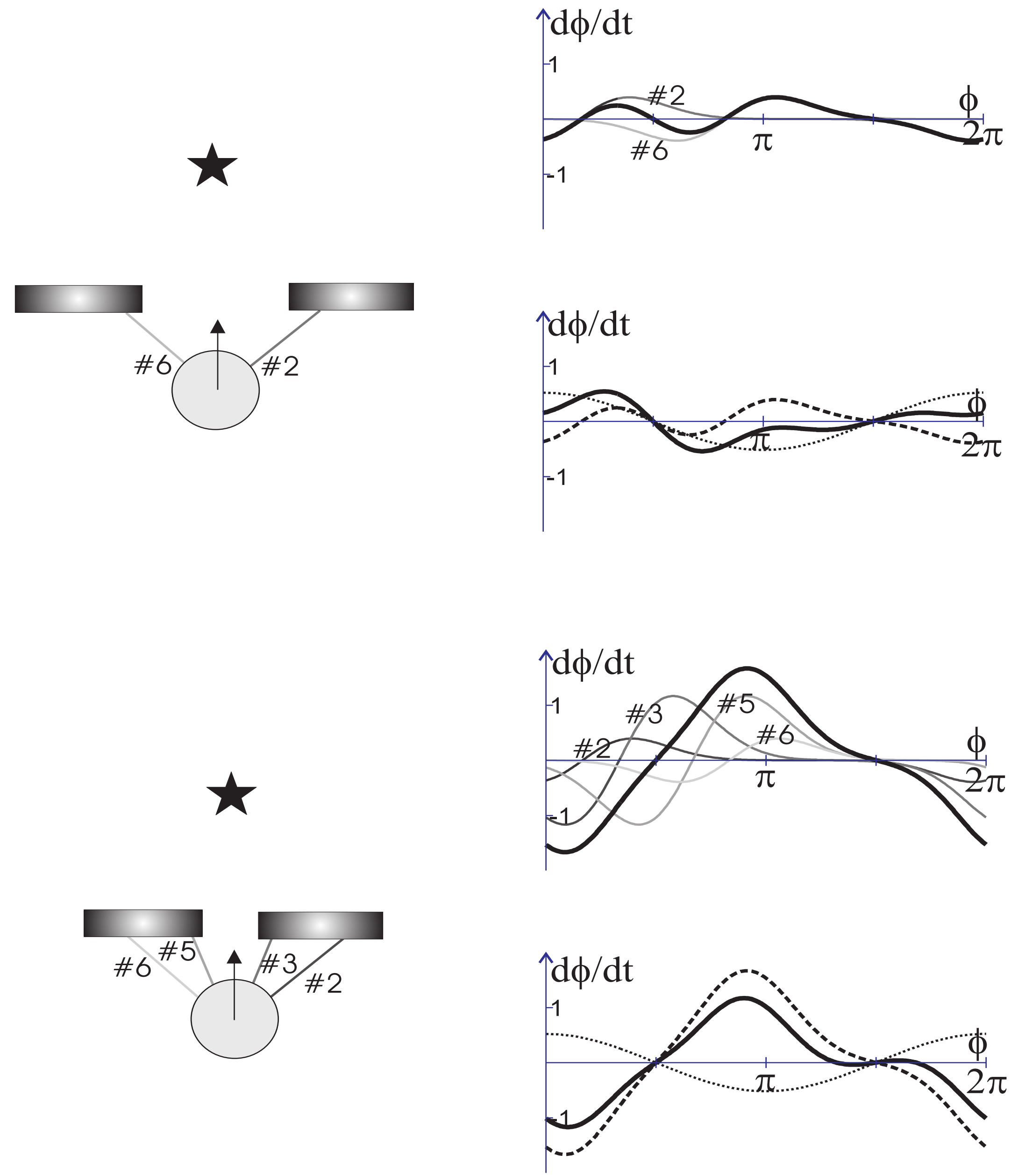




[from: Bicho, Jokeit, Schöner]

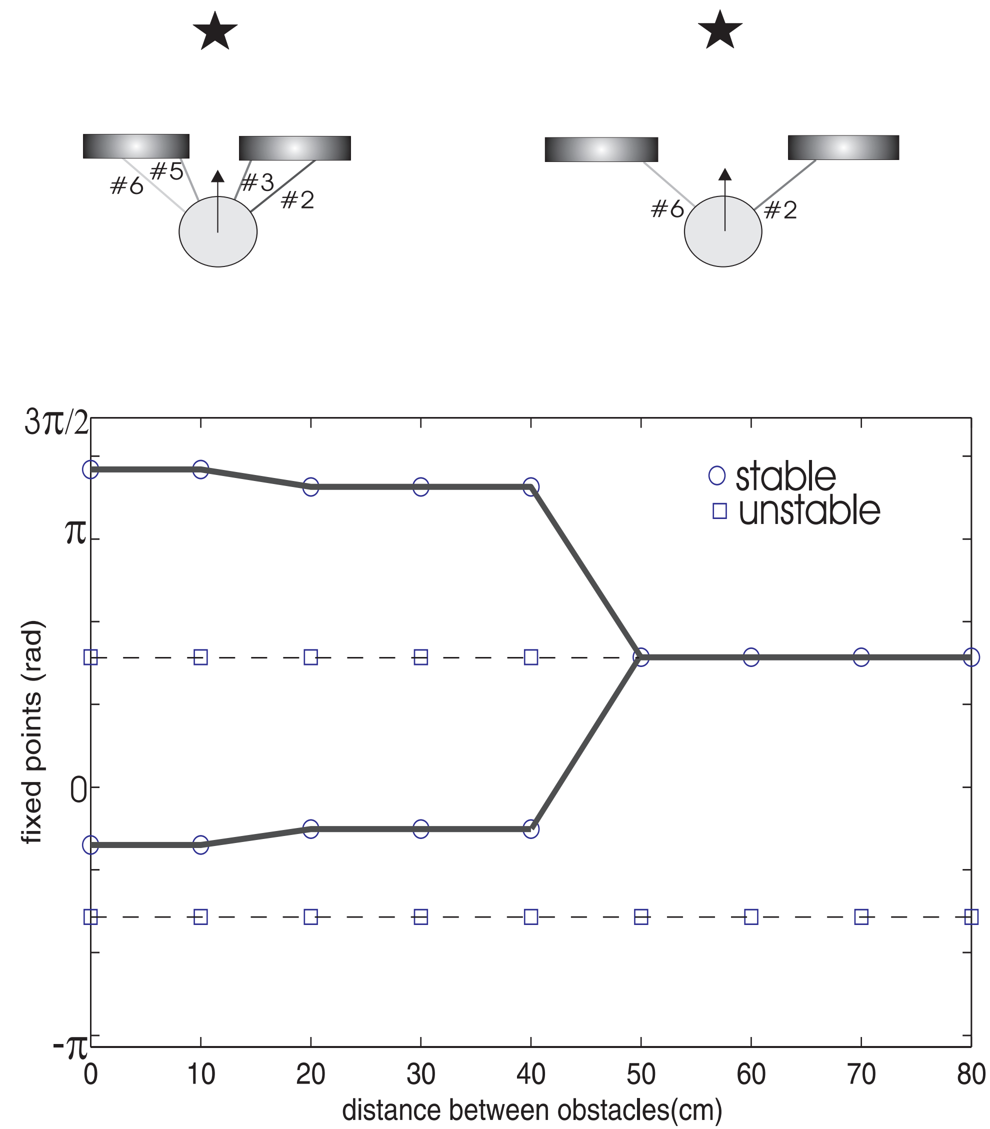
Bifurcations

- bifurcation as a function of the size of the opening between obstacles



Bifurcations

- bifurcation as a function of the size of the opening between obstacles
- =>tune distance dependence of repulsion so that bifurcation occurs at the right opening



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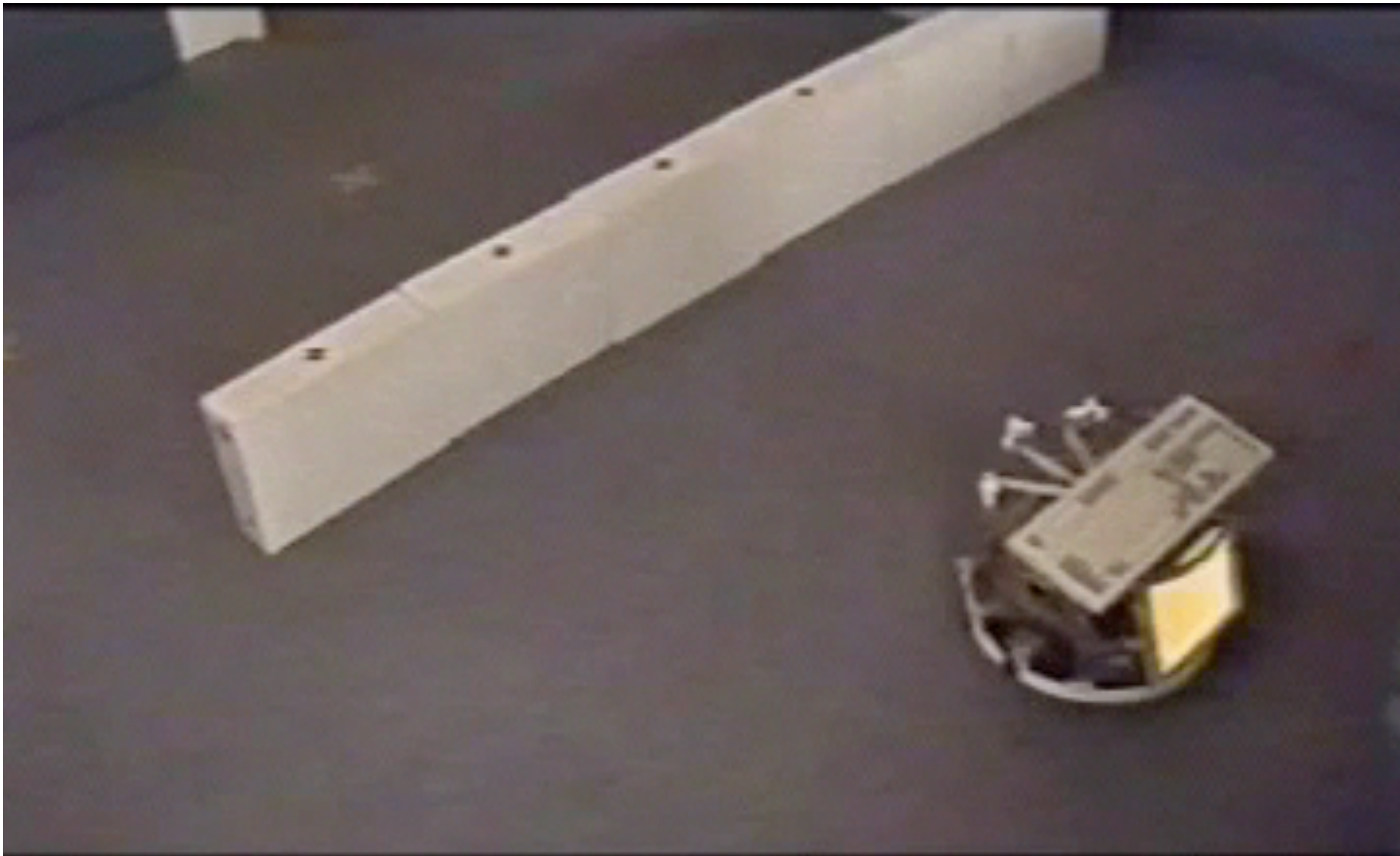
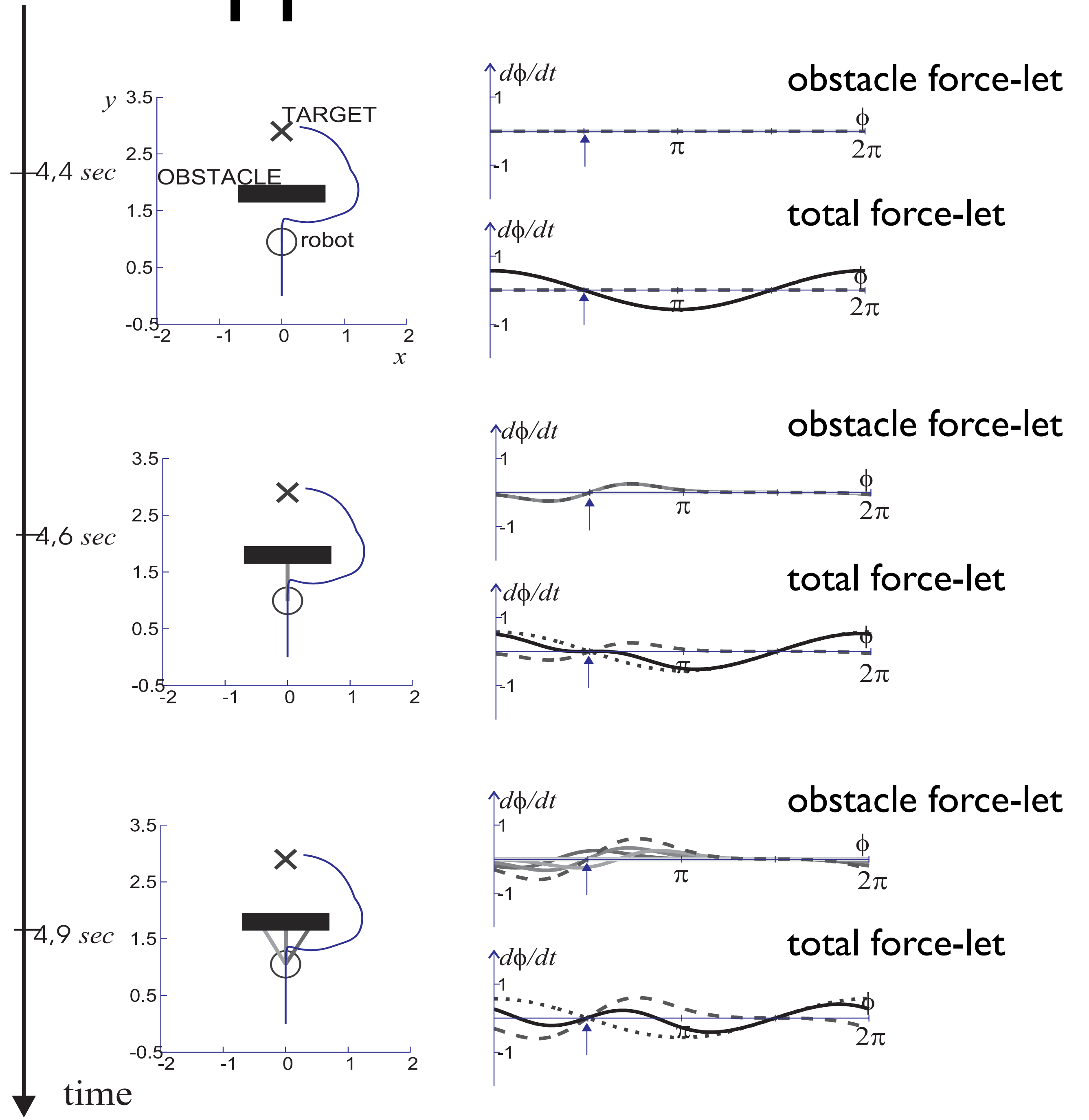


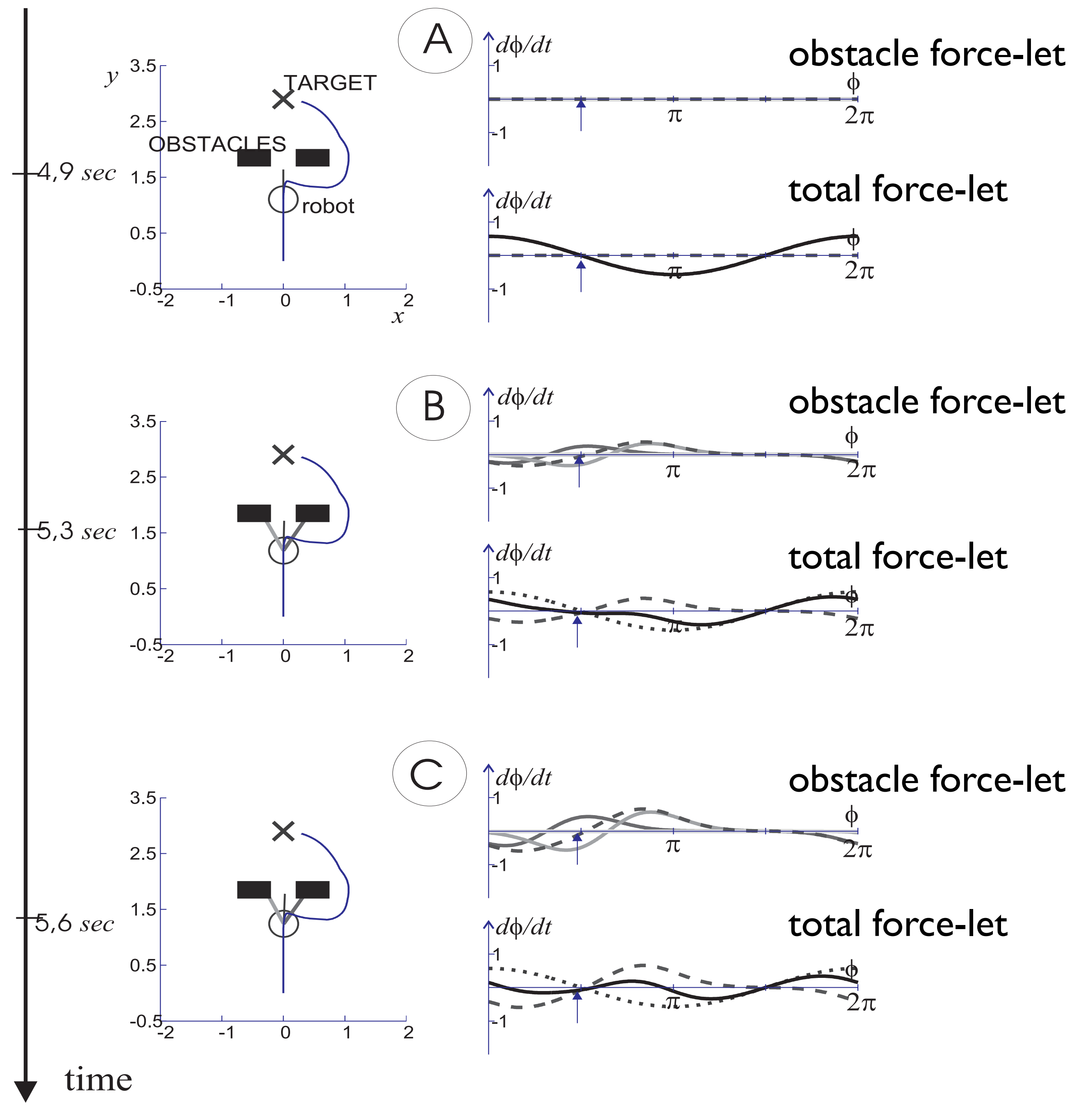
Bifurcation on approach to wall

- initially attractor dominates: weak repulsion
- bifurcation
- then obstacles dominate: strong repulsion and total repulsion



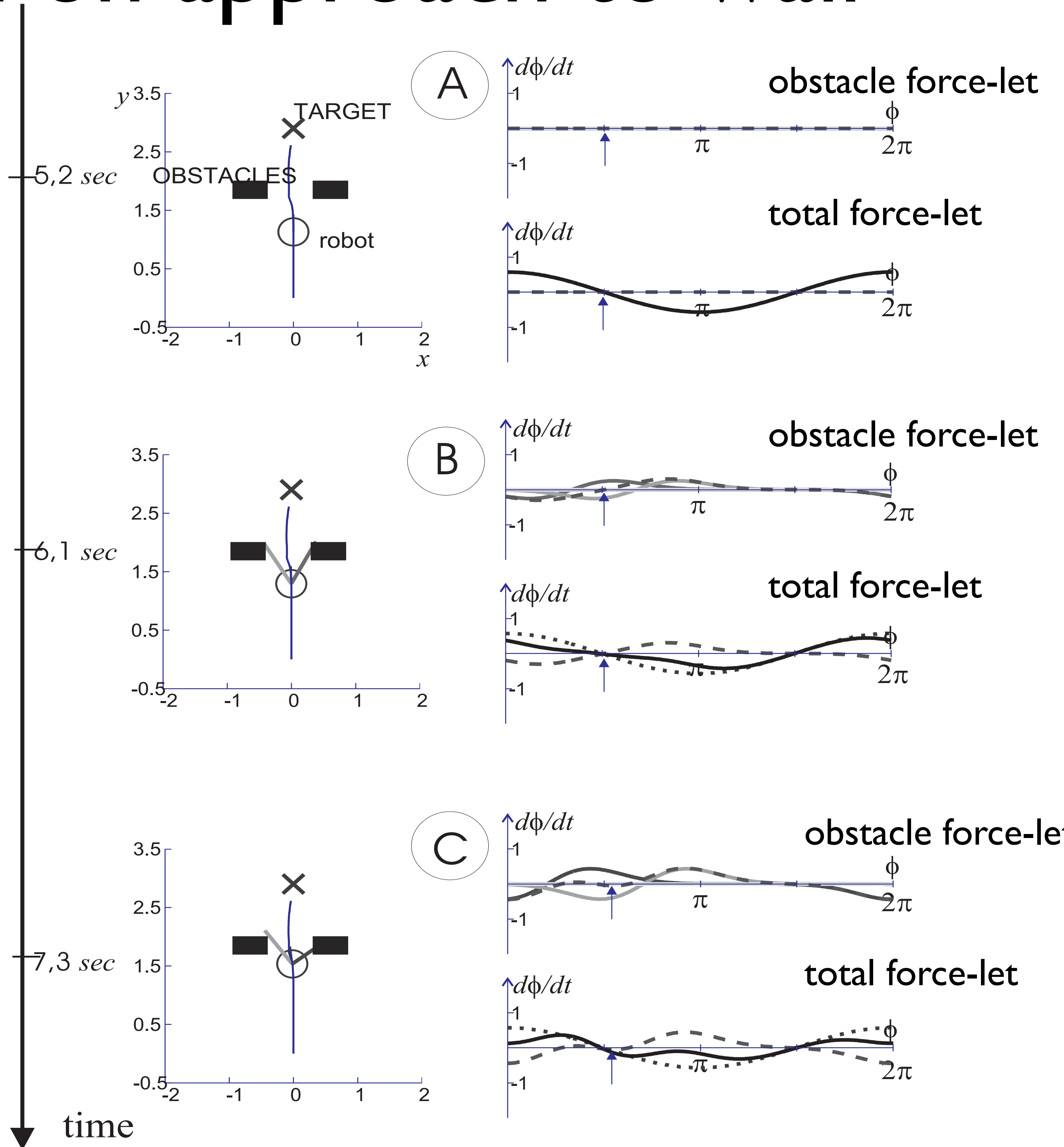
Bifurcation on approach to wall

- same with small opening



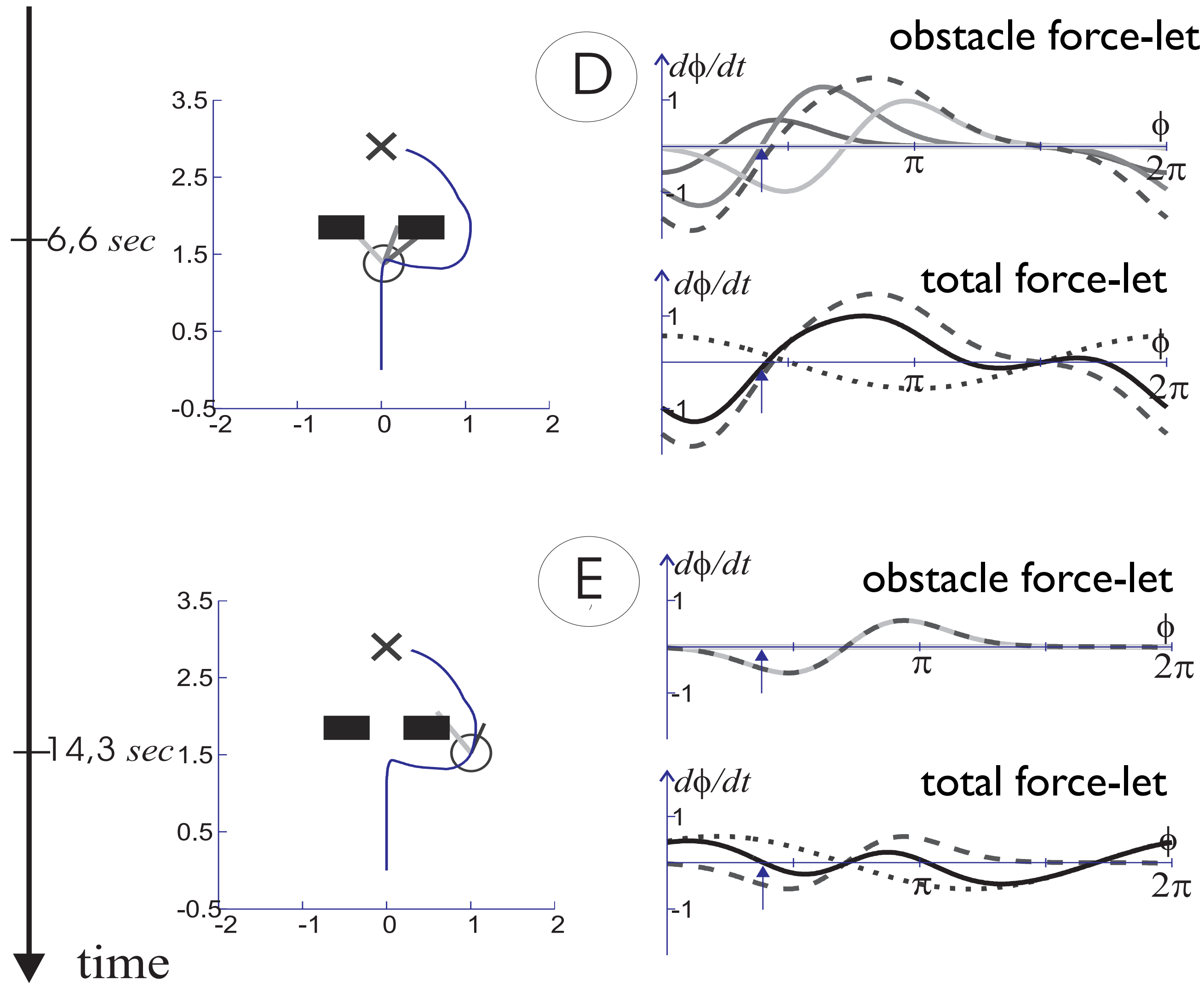
Bifurcation on approach to wall

- at larger opening: repulsion weak all the way through: attractor remains stable



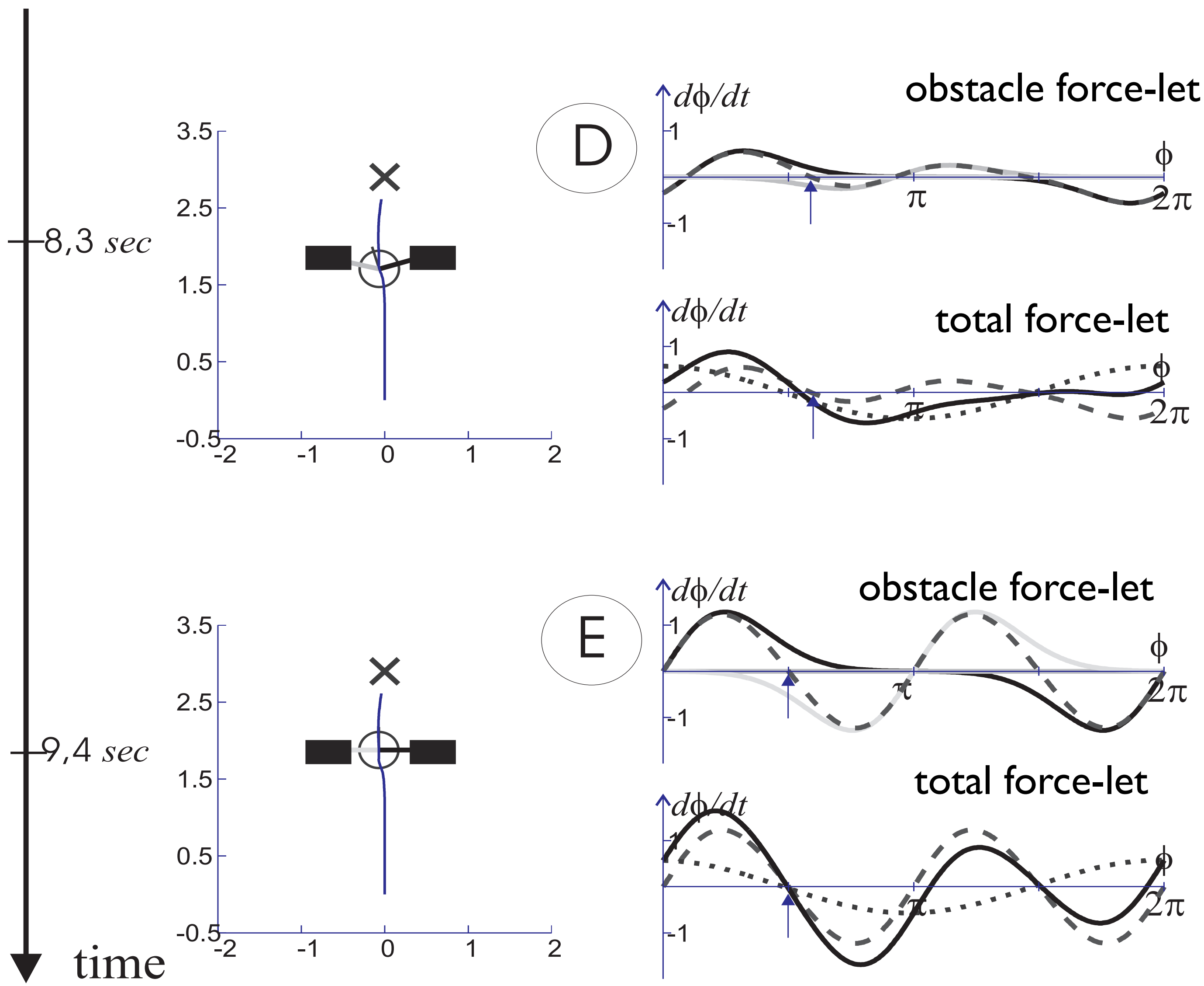
Tracking attractor

- as robot moves around obstacles, tracks the moving attractor

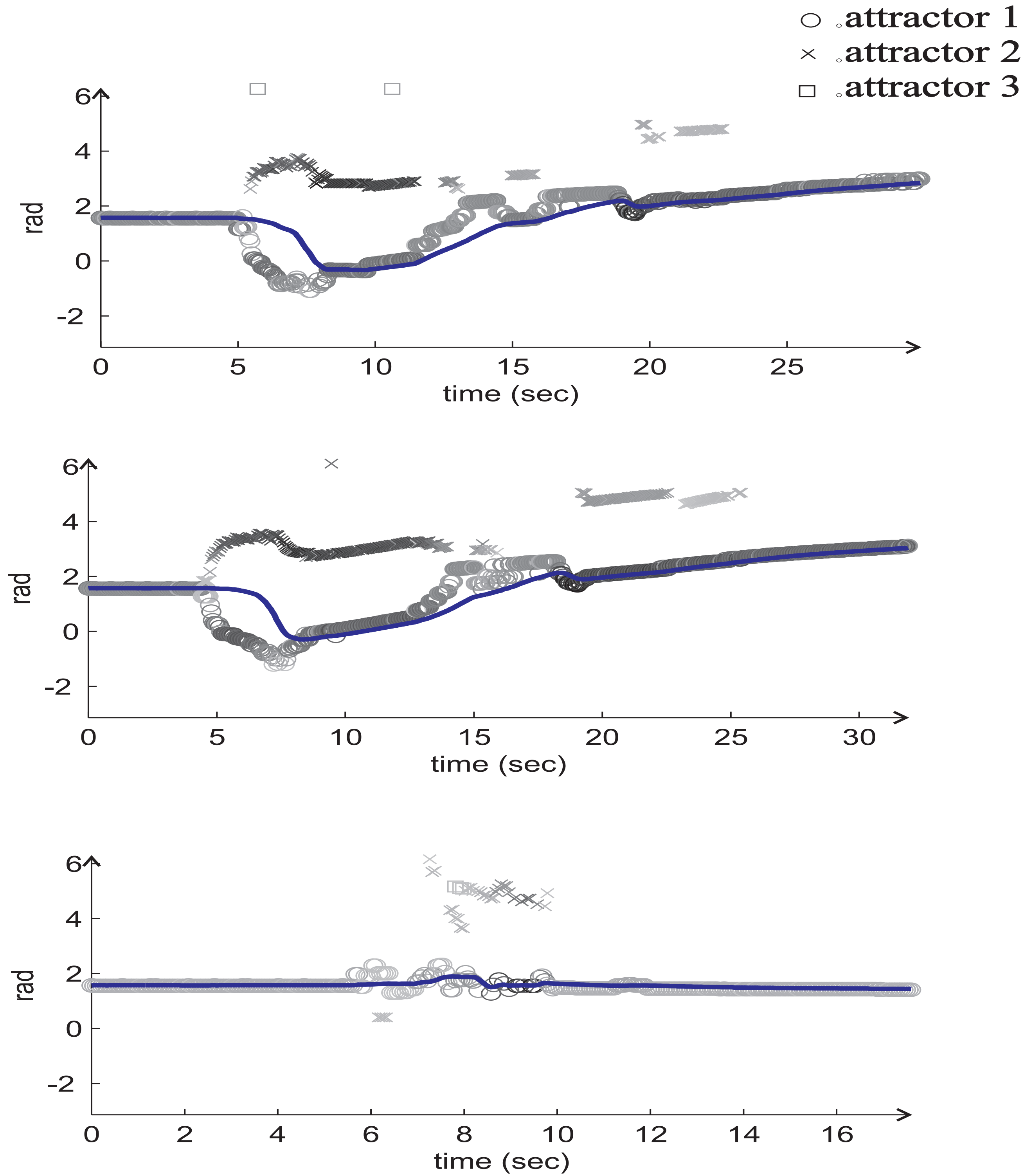


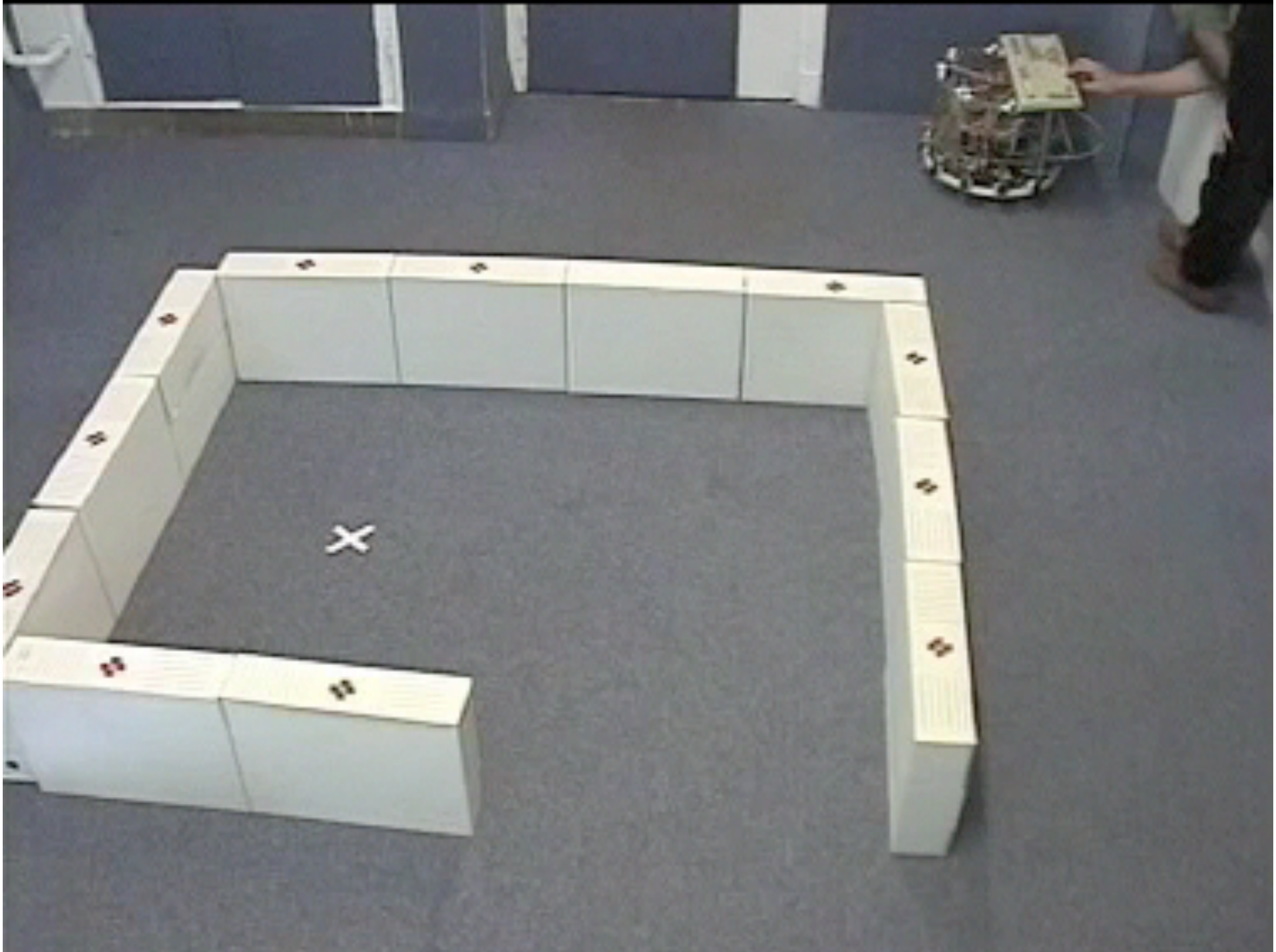
Tracking attractor

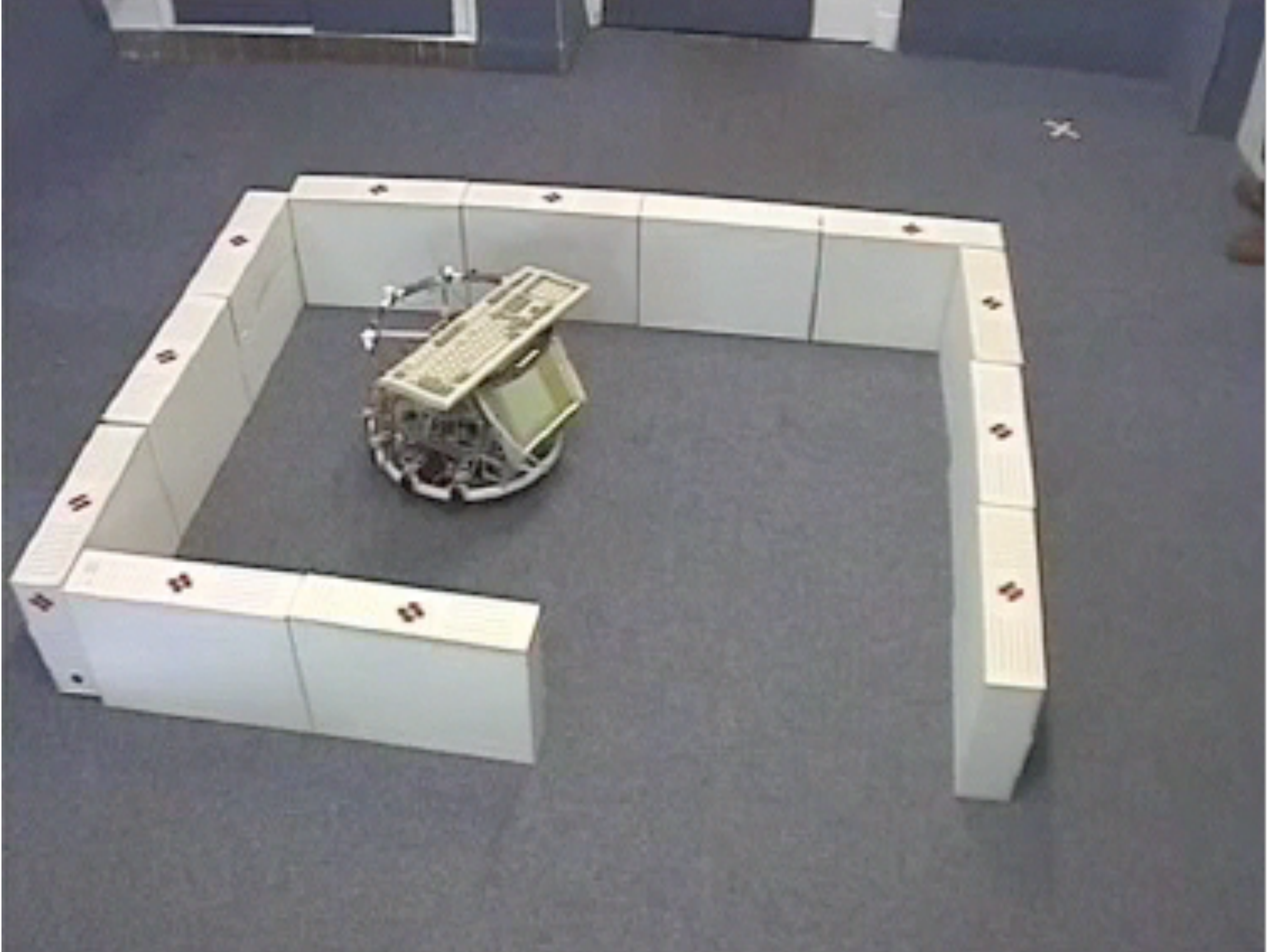
- as robot moves in between obstacles, the dynamics changes but not the attractor

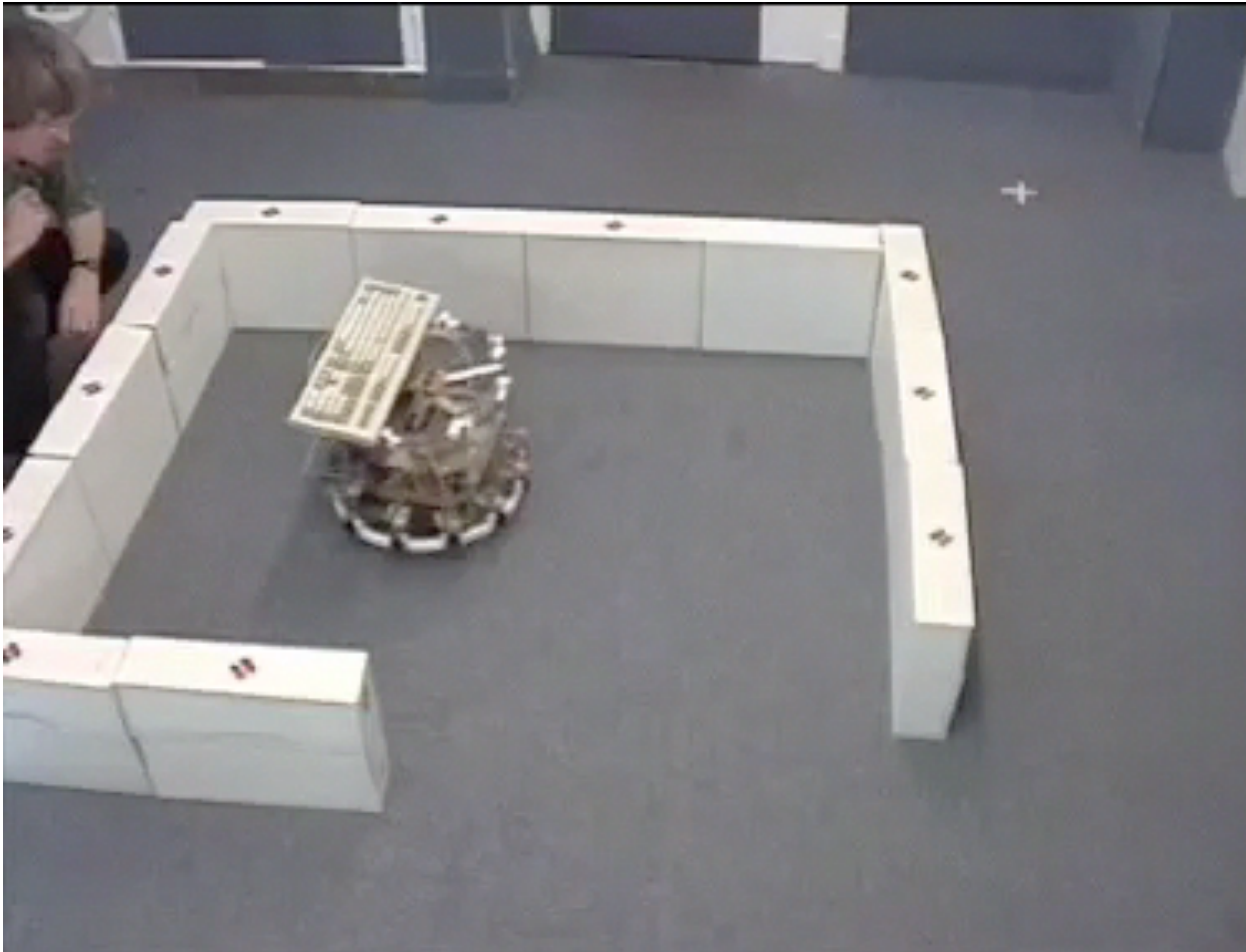


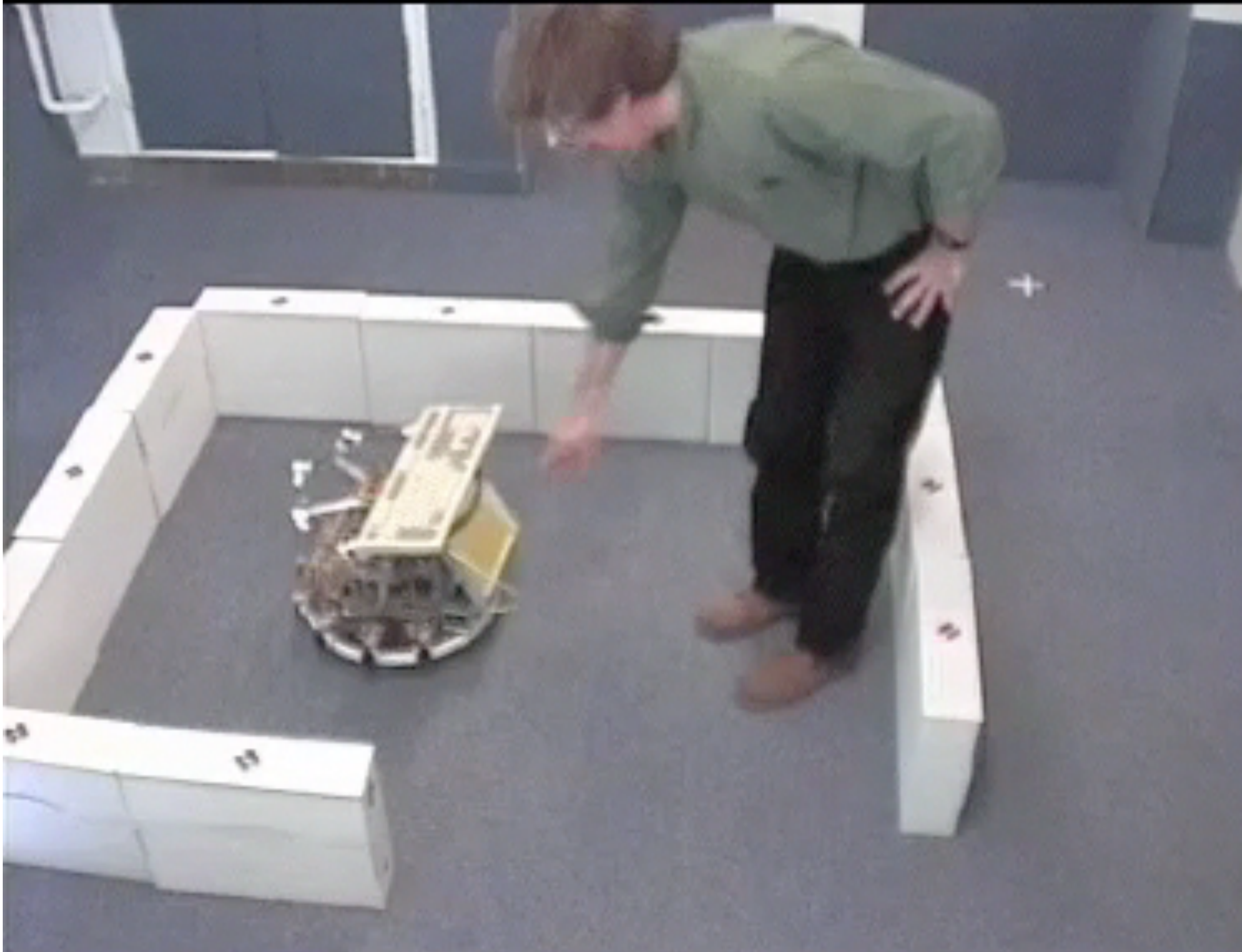
Tracking attractors











Observation:

- even though the approach is purely local, it does achieve global tasks
- based on the structure of the environment!

Conclusion

- attractor dynamics works on the basis low-level sensors information
- as long at the force-lets model the sensor-characteristics well enough to create approximate invariance of the dynamics under transformations of the coordinate frames

Summary

- behavioral variables
- attractor states for behavior
- attractive force-let: target acquisition
- repulsive force-let: obstacle avoidance
- bistability/bifurcations: decisions
- can be implemented with minimal requirements for perception