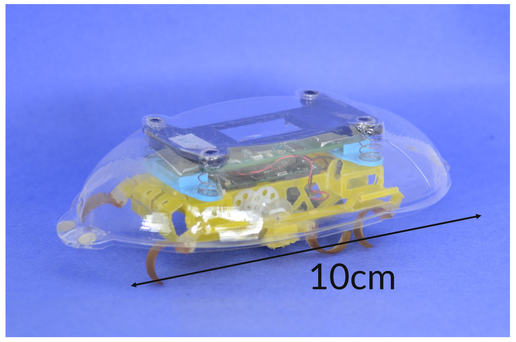
BIOMIMETIC MILLISYSTEMS LAB

Dept. of EECS, UC Berkeley
PI: RONALD S. FEARING (ronf@berkeley.edu)
PRESENTERS: Can Koc, Cem Koc, Brian Su

Terrain Classification with Force-Torque Sensor Equipped Millirobot

Tactile robot in natural environment.

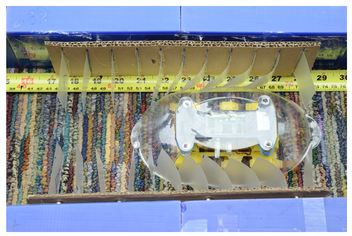


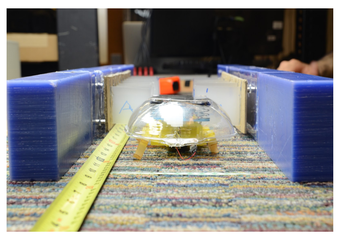
Robot model with tactile shell.

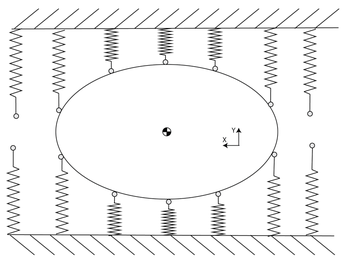
Objective

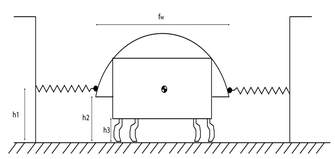
Goal:
Distinguish low and high resistance regions.

Why?
- Low vision environments, e.g. Dirt, moisture, dust.
- Navigating through brush or dense compliant obstacles









Method

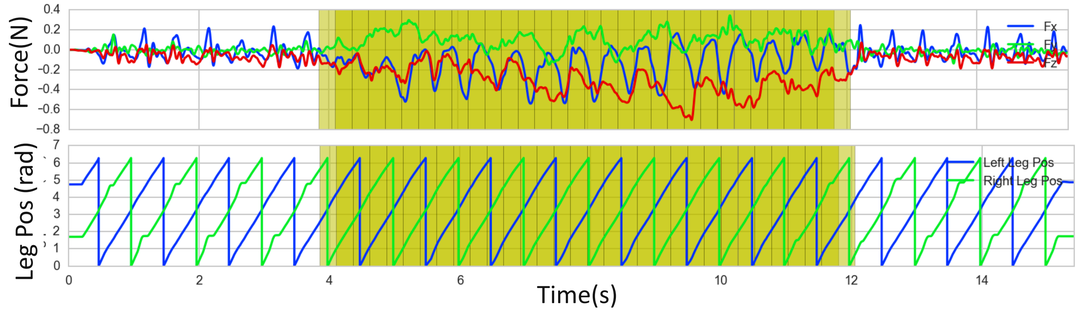
- Our experiment setup has 3 states: start (no touch), traversal (touch) and exit (no touch).
- Dataset consists of all the experiments from 4,6,8 and 10cm flap widths.
- After segmenting and applying windows we labeled the data as touch (1) or no touch (0).

- Training Set:
772 samples (1) + 853 samples (0).

- Test Set:
Single experiment with 4cm.

Results

- Input: shell forces, Fx, Fy,Fz, Gyro, Accelerometer, Leg Positions and Velocity.
- Trained random forests, gradient boosted trees, RBF SVM, and Neural Network
- All had a 10-fold CV average ROC score > 90%.



Classifier	10-fold CV avg ROC
Random Forests	97.4%
Gradient Boosted Trees	**97.6%**
RBF SVM	97.3%
Neural Network	92%

Gradient Trees Top Features	Random Forests Top Features
Fz_max	Fx_skew
Fx_skew	F_mag_energy
F_mag_max	F_mag_mean
Fz_mean	Mx_std
My_min	F_mag_max