

Introduction to Cognitive Robotics

Module 10: Using Turtlesim with CRAM

Lecture 8: Using location designators with TurtleSim

www.cognitiverobotics.net

The CRAM Beginner Tutorials

Based on CRAM tutorials
<http://cram-system.org/tutorials>

Using Location Designators with TurtleSim

Based on Using location designators with the TurtleSim
http://cram-system.org/tutorials/beginner/location_designators_2

Using Location Designators with TurtleSim

Location Designators: An Overview

- Location designators provide a way to describe a location in symbolic terms ...
- ... and have the actual coordinates determined later, when needed at run time
- Location designators are resolved in a different manner compared to motion designators
 - Motion designators are resolved by inference (reasoning) with Prolog using a set of facts and rules
 - Location designators make use of a pair of different types of functions

Using Location Designators with TurtleSim

Location Designators: An Overview

These functions are

1. **location-generator**

This creates a lazy list of candidate poses

2. **location-validator**

This checks that a candidate pose is actually valid
i.e. that it is feasible for the robot, e.g. not in collision with objects in the environment

Using Location Designators with TurtleSim

Location Designators: An Overview

- Both generator and validator functions need to be written by the programmer for their specific application
- They must be registered as generators or validators (as appropriate for given designator constraints)
- It is also possible to define and register **several** generators and validators for the **same designator**
- Having more generators means you have to check more candidates
- **Different validators can collaborate to check a candidate**

Using Location Designators with TurtleSim

Location Designators: An Overview

Several return values are possible for validators:

- **:accept** means the candidate is accepted by this validator
- **:unknown** means this validator cannot decide and leaves the decision to the others
- **:maybe-reject** means the candidate will be rejected unless some other validator explicitly accepts it
- **:reject** immediately invalidates the candidate, no further processing needed

Using Location Designators with TurtleSim

Location Designators: An Overview

Therefore, a candidate will be accepted if

No validator rejected it

AND

((at least one validator returned **:accept**)

OR

(all validators returned **:unknown**))

Using Location Designators with TurtleSim

Writing a location designator generator function

We will the code in `location-designators.lisp`

Using Location Designators with TurtleSim

Writing a location designator generator function

As before, when developing new code, we need to

- (Update the dependencies in `package.xml`) ← We don't need to do this as there are no new packages being used
- Update the dependencies in `cram-my-beginner-tutorial.asd` ← We need to do this because we are going to put the new code in a separate file
- (Update the dependencies in `package.lisp`) ← We don't need to do this as there are no new packages being used
- Add the new code to `location-designators.lisp` ← We will place the new code in a separate Lisp file
- Test the code
 - Run the ROS master
 - Run the Lisp REPL, loading the new program, creating a ROS node
 - Run turtlesim
 - Run turtlesim_teleop
 - Call the new functions

Using Location Designators with TurtleSim

Writing a location designator generator function

Update the ASDF dependencies

Make sure you are in the `cram_my_beginner_tutorial` sub-directory

```
~$ cd ~/workspace/ros/src/cram_my_beginner_tutorial  
~/workspace/ros/src/cram_my_beginner_tutorial$
```

Using Location Designators with TurtleSim

Writing a location designator generator function

Update the ASDF dependencies

Edit `cram-my-beginner-tutorial.asd`

```
~/workspace/ros/src/cram_my_beginner_tutorial$ emacs cram-my-beginner-tutorial.asd
```

Using Location Designators with TurtleSim

```
(defsystem cram-my-beginner-tutorial
  :depends-on (roslisp cram-language
              turtlesim-msg turtlesim-srv
              cl-transforms geometry_msgs-msg
              cram-designators cram-prolog
              cram-process-modules cram-language-designator-support
              cram-executive)

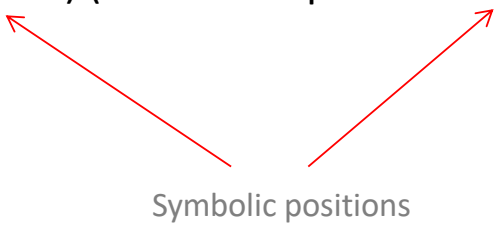
  :components
  ((:module "src"
    :components
    (:file "package")
    (:file "control-turtlesim" :depends-on ("package"))
    (:file "simple-plans" :depends-on ("package" "control-turtlesim"))
    (:file "motion-designators" :depends-on ("package"))
    (:file "location-designators" :depends-on ("package")) ← Add this line
    (:file "process-modules" :depends-on ("package"
                                         "control-turtlesim"
                                         "simple-plans"
                                         "motion-designators"))
    (:file "selecting-process-modules" :depends-on ("package"
                                                  "motion-designators"
                                                  "process-modules"))))))
```

Using Location Designators with TurtleSim

Writing a location designator generator function

We would like to specify locations for the turtle to go using spatial relations, e.g.:

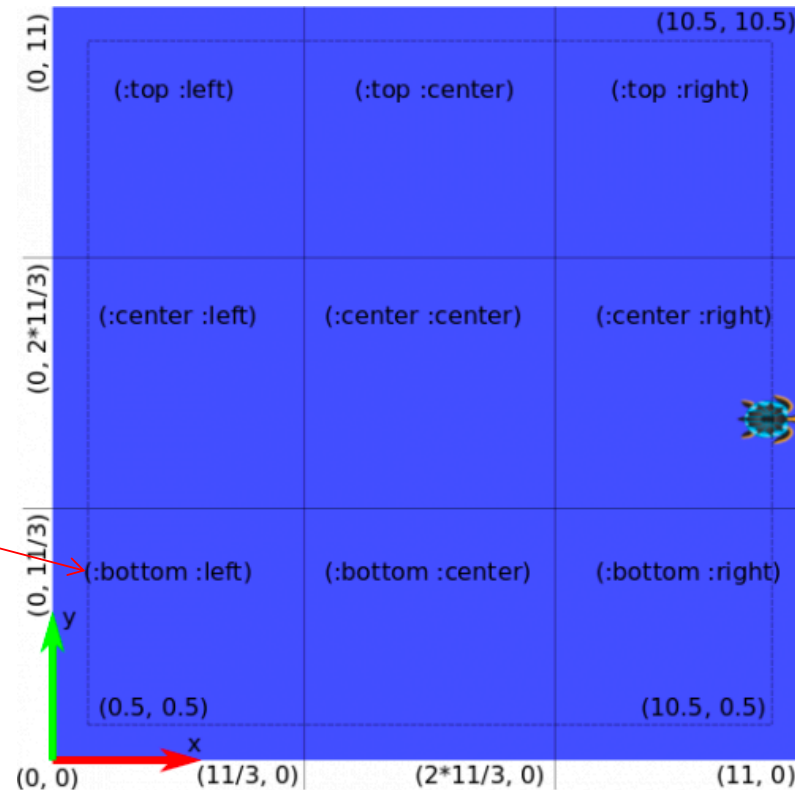
```
TUT> (defparameter goal-desig
      (make-designator :location '(:vertical-position :bottom) (:horizontal-position :left))))
TUT> goal-desig
#<A LOCATION
  (VERTICAL-POSITION BOTTOM)
  (HORIZONTAL-POSITION LEFT)>
```



Symbolic positions

Using Location Designators with TurtleSim

Writing a location designator generator function



Symbolic positions, e.g. **:bottom :left**

We want the designator to resolve by producing coordinates in whichever of the nine sectors are specified by the nine combinations of

```
{:top, :center, :bottom} ×  
{:left, :center, :right}
```

Using Location Designators with TurtleSim

Writing a location designator generator function

Create a new Lisp file for the location designators code:

Make sure you are in the `cram_my_beginner_tutorial/src` sub-directory

```
~$ cd ~/workspace/ros/src/cram_my_beginner_tutorial/src  
~/workspace/ros/src/cram_my_beginner_tutorial/src$
```


Using Location Designators with TurtleSim

Writing a location designator generator function

Create a new Lisp file for the location designators code:

Edit **location-designators.lisp**

```
~/workspace/ros/src/cram_my_beginner_tutorial/src$ emacs location-designators.lisp
```

Using Location Designators with TurtleSim

Writing a location designator generator function

Create a new Lisp file for the location designators code:

Edit **location-designators.lisp**

Copy and paste the code from the following slide

```

(in-package :tut)

(defun navigation-goal-generator (designator)
  (declare (type location-designator designator))
  (with-desig-props (vertical-position horizontal-position) designator
    (let ((x-offset (ecase horizontal-position
                     (:left 0)
                     (:center (/ 11.0 3.0))
                     (:right (* (/ 11.0 3.0) 2))))
          (y-offset (ecase vertical-position
                     (:bottom 0)
                     (:center (/ 11.0 3.0))
                     (:top (* (/ 11.0 3.0) 2))))))
      (loop repeat 5
            collect (cl-transforms:make-3d-vector
                    (+ x-offset (random (/ 11.0 3.0)))
                    (+ y-offset (random (/ 11.0 3.0)))
                    0))))))

```

```

(in-package :tut)

(defun navigation-goal-generator (designator)
  (declare (type location-designator designator))
  (with-desig-props (vertical-position horizontal-position) designator
    (let ((x-offset (ecase horizontal-position
                      (:left 0)
                      (:center (/ 11.0 3.0))
                      (:right (* (/ 11.0 3.0) 2))))
          (y-offset (ecase vertical-position
                      (:bottom 0)
                      (:center (/ 11.0 3.0))
                      (:top (* (/ 11.0 3.0) 2))))
            (loop repeat 5
                  collect (cl-transforms:make-3d-vector
                          (+ x-offset (random (/ 11.0 3.0)))
                          (+ y-offset (random (/ 11.0 3.0)))
                          0))))))

(register-location-generator 5 navigation-goal-generator)

```

the generator has one parameter: a designator ...

Declare the type of the designator to be a location-designator

Use the vertical-position and horizontal-position designator properties

x origin for :left, :center, and :right sectors

y origin for :bottom, :center, and :top sectors

Generate and return 5 random sets of coordinates in the specified sector offset from the x and y origins

the function generator returns a list of 5 3d-vectors

Register the function as a location designator generator

The priority of the generator
Generators are called in priority order: lower values imply higher priority and the earlier they are called

Using Location Designators with TurtleSim

Writing a location designator generator function

Now, let's experiment with this code

First, we need to make sure a ROS master is running

If you have not already done it, open a terminal and enter

```
~$ roscore
```

Using Location Designators with TurtleSim

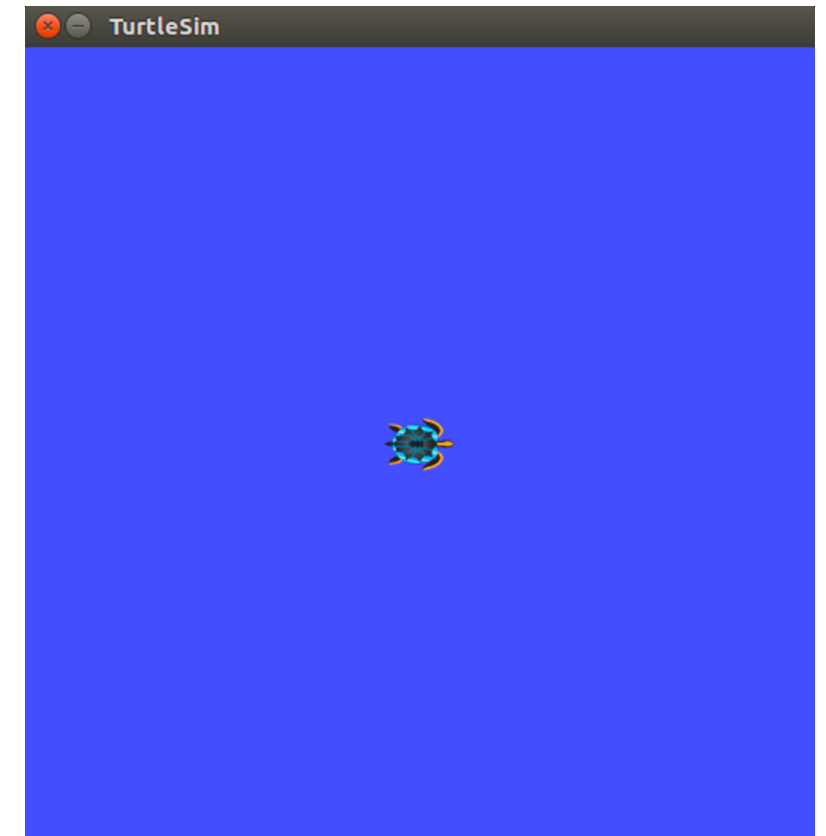
Writing a location designator generator function

Now, start turtlesim

Open a new terminal and enter

```
~$ rosrn turtlesim turtlesim_node
```

This is what you should see



Using Location Designators with TurtleSim

Launch the Lisp REPL

If you have not already done it, open a terminal and enter

```
~/workspace/ros$ roslisp_repl
```

Load the system

```
CL-USER> (ros-load:load-system "cram_my_beginner_tutorial" :cram-my-beginner-tutorial)
```

Switch to the package

```
CL-USER> (in-package :tut)
```

```
TUT>
```

Using Location Designators with TurtleSim

Start a ROS node

The name doesn't matter




```
TUT> (start-ros-node "turtle1")  
[(ROSLISP TOP) INFO] 1292688669.674: Node name is turtle1  
[(ROSLISP TOP) INFO] 1292688669.687: Namespace is /  
[(ROSLISP TOP) INFO] 1292688669.688: Params are NIL  
[(ROSLISP TOP) INFO] 1292688669.689: Remappings are:  
[(ROSLISP TOP) INFO] 1292688669.691: master URI is 127.0.0.1:11311  
[(ROSLISP TOP) INFO] 1292688670.875: Node startup complete
```


Using Location Designators with TurtleSim

Call the function to perform the initialization

```
TUT> (init-ros-turtle "turtle1")
```

Use turtle1 ... remember, this forms the prefix on the topic names
This is the name of the first turtle that turtlesim spawns



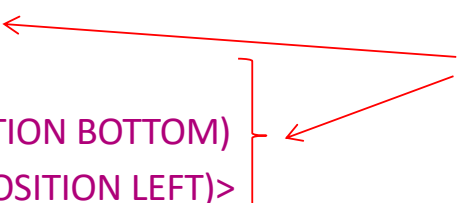
Using Location Designators with TurtleSim

Writing a location designator generator function

Define the example location designator

```
TUT> (defparameter goal-desig
      (make-designator :location '(:vertical-position :bottom) (:horizontal-position :left))))
TUT> goal-desig
#<A LOCATION
  (VERTICAL-POSITION BOTTOM)
  (HORIZONTAL-POSITION LEFT)>
```

← Check the value of goal-desig



Using Location Designators with TurtleSim

Writing a location designator generator function

Now, test the example designator resolving function

```
TUT> (navigation-goal-generator goal-desig)  
(#<3D-VECTOR (1.0404995679855347d0 0.03507864475250244d0 0.0d0)>  
#<3D-VECTOR (3.0929160118103027d0 0.8247395753860474d0 0.0d0)>  
#<3D-VECTOR (3.048727035522461d0 1.0249313116073608d0 0.0d0)>  
#<3D-VECTOR (2.1428534984588623d0 2.775157928466797d0 0.0d0)>  
#<3D-VECTOR (3.3696107864379883d0 0.026859402656555176d0 0.0d0)>)
```

The generator function takes a location designator as an argument and returns a **list** of solutions

The **5** generated sets of random coordinates in the specified sector (:bottom :left) i.e. in the range $0 \leq x, y \leq 3.667$ (11//3)

Note: it returns them as a list

Using Location Designators with TurtleSim

Writing a location designator generator function

And now, try resolving (referencing) the example location designator

```
TUT> (reference goal-desig)
```

```
#<3D-VECTOR (1.142098307609558d0 2.184809684753418d0 0.0d0)>
```

It resolves to a 3d-vector with appropriate values



Using Location Designators with TurtleSim

Writing a location designator generator function

And now, try resolving (referencing) the example location designator

TUT> (reference goal-desig)

#<3D-VECTOR (1.142098307609558d0 2.184809684753418d0 0.0d0)>



Why are these values not the same as the first element. of the list we got when we performed the evaluation previously?

TUT> (navigation-goal-generator goal-desig)

(#<3D-VECTOR (1.0404995679855347d0 0.03507864475250244d0 0.0d0)>

#<3D-VECTOR (3.0929160118103027d0 0.8247395753860474d0 0.0d0)>

#<3D-VECTOR (3.048727035522461d0 1.0249313116073608d0 0.0d0)>

#<3D-VECTOR (2.1428534984588623d0 2.775157928466797d0 0.0d0)>

#<3D-VECTOR (3.3696107864379883d0 0.026859402656555176d0 0.0d0)>)

Because when referencing goal-desig, the generator creates a new and different list of candidates

Using Location Designators with TurtleSim

Writing a location designator generator function

And now, try resolving (referencing) the example location designator

```
TUT> (reference goal-desig)
```

```
#<3D-VECTOR (1.142098307609558d0 2.184809684753418d0 0.0d0)>
```

```
TUT> (reference goal-desig)
```

```
#<3D-VECTOR (1.142098307609558d0 2.184809684753418d0 0.0d0)>
```

It resolves to a 3d-vector with appropriate values

On the second resolution, it also resolves to a 3d-vector with appropriate values

... but why does it have the same coordinates?
Surely, the random number generator in `navigation-goal-generator` didn't create the exact same numbers twice?

It didn't; it generated 5 solution ... but to get the other elements in the list of solutions we need another function: `next-solution`

Using Location Designators with TurtleSim

Writing a location designator generator function

To get the other elements in the list of solutions we need another function: `next-solution`

Call `next-solution` with the location designator `goal-desig` as an argument

```
TUT> (next-solution goal-desig)
```

That's odd: it returns a location designator, not a 3d-vector with the coordinates

```
#<LOCATION-DESIGNATOR ((:VERTICAL-POSITION :BOTTOM) (:HORIZONTAL-POSITION :LEFT)) {10086B5A23}>
```

- Confusingly, `next-solution` doesn't actually return the next solution, but rather **a new designator**
 - This designator has identical properties to the `goal-desig` location designator
 - If no other solution exists, then `next-solution` returns `nil`
- If we actually want to see this solution, assuming it exists, **we need to resolve it**, i.e. reference it ...

Using Location Designators with TurtleSim

Writing a location designator generator function

To see this solution, assuming it exists, we need to resolve it, i.e. reference it ...

```
TUT> (reference (next-solution goal-desig))
```

```
#<3D-VECTOR (0.261885404586792d0 2.649489164352417d0 0.0d0)>
```

- If we called (reference (next-solution goal-desig)) again, we would get this same solution again
- If goal-desig stays the same, then the next solution designator also stays the same, and so does the solution associated with it

Using Location Designators with TurtleSim

Writing a location designator generator function

One way to iterate over the solutions would be:

```
TUT> (loop for desig = goal-desig then (next-solution desig)
      while desig
      do (print (reference desig)))
#<3D-VECTOR (1.142098307609558d0 2.184809684753418d0 0.0d0)>
#<3D-VECTOR (0.261885404586792d0 2.649489164352417d0 0.0d0)>
#<3D-VECTOR (2.560281276702881d0 1.5541117191314697d0 0.0d0)>
#<3D-VECTOR (3.182616949081421d0 1.329969882965088d0 0.0d0)>
#<3D-VECTOR (1.3107243776321411d0 2.9240825176239014d0 0.0d0)>
NIL
```

Using Location Designators with TurtleSim

Writing a location designator generator function

One way to iterate over the solutions would be:

```
TUT> (loop for desig = goal-desig then (next-solution desig)
      while desig
      do (print (reference desig)))
#<3D-VECTOR (1.142098307609558d0 2.184809684753418d0 0.0d0)>
#<3D-VECTOR (0.261885404586792d0 2.649489164352417d0 0.0d0)>
#<3D-VECTOR (2.560281276702881d0 1.5541117191314697d0 0.0d0)>
#<3D-VECTOR (3.182616949081421d0 1.329969882965088d0 0.0d0)>
#<3D-VECTOR (1.3107243776321411d0 2.9240825176239014d0 0.0d0)>
NIL
```

14.5 The Loop Facility

The `loop` macro was originally designed to help inexperienced Lisp users write iterative code. Instead of writing Lisp code, you express your program in a form meant to resemble English, and this is then translated into Lisp. Unfortunately, `loop` is more like English than its designers ever intended: you can use it in simple cases without quite understanding how it works, but to understand it in the abstract is almost impossible.

There are three phases in the evaluation of a `loop` expression, and a given clause can contribute code to more than one phase. The phases are as follows:

1. *Prologue*. Evaluated once as a prelude to iteration. Includes setting variables to their initial values.
2. *Body*. Evaluated on each iteration. Begins with the termination tests, followed by the body proper, then the updating of iteration variables.
3. *Epilogue*. Evaluated once iteration is completed. Concludes with the return of the value(s) of the `loop` expression.

Using Location Designators with TurtleSim

Writing a location designator validation function

It is sometimes necessary to validate the generated solutions

- For example, the points we get from `navigation-goal-generator` range from 0 to 11
- But whenever the turtle has a coordinate above 10.5 or less than 0.5 a part of it disappears from the screen
- Let's improve our location designator resolution by rejecting the points that lie outside of the range 0.5 -10.5

Using Location Designators with TurtleSim

Writing a location designator validation function

Update the location designators code:

Edit `location-designators.lisp`

Copy and paste the code from the following slide

```
(defun navigation-goal-validator (designator solution)
  (declare (type location-designator designator))
  (when (and (desig-prop-value designator :vertical-position)
             (desig-prop-value designator :horizontal-position))
    (when (typep solution 'cl-transforms:3d-vector)
      (when
        (and
          (>= (cl-transforms:x solution) 0.5)
          (>= (cl-transforms:y solution) 0.5)
          (<= (cl-transforms:x solution) 10.5)
          (<= (cl-transforms:y solution) 10.5))
        :accept))))

(register-location-validation-function
 5 navigation-goal-validator)
```

The validation function has two parameters: a location designator and a solution

```
(defun navigation-goal-validator (designator solution)
  (declare (type location-designator designator))
  (when (and (desig-prop-value designator :vertical-position)
            (desig-prop-value designator :horizontal-position))
    (when (typep solution 'cl-transforms:3d-vector)
      (when
        (and
          (>= (cl-transforms:x solution) 0.5)
          (>= (cl-transforms:y solution) 0.5)
          (<= (cl-transforms:x solution) 10.5)
          (<= (cl-transforms:y solution) 10.5))
        :accept))))
```

If the designator property values are what we expect
(refer back to the definition of the function generator)

If the type of solution is `cl-transforms:3d-vector`

if the values of the x and y coordinates are in the required range
the return `:accept` (i.e. T) and reject (NIL) everything else

```
(register-location-validation-function 5 navigation-goal-validator)
```

Register the function as a location designator validator

The priority of the validator
Just like generators, validators are called in priority order:
lower values imply higher priority and the earlier they are called

Using Location Designators with TurtleSim

Writing a location designator validation function

Re-load the system (or recompile)

```
TUT> (ros-load:load-system "cram_my_beginner_tutorial" :cram-my-beginner-tutorial)
```

Using Location Designators with TurtleSim

Writing a location designator validation function

Check to see if the validation function works

```
TUT> (defparameter another-goal
      (make-designator :location '(:vertical-position :bottom) (:horizontal-position :left))))
```

← Define a new location designator

```
ANOTHER-GOAL
TUT> (loop for desig = another-goal then (next-solution desig)
      while desig
      do (print (reference desig)))
```

← Print all the coordinates after they have been validated

```
#<3D-VECTOR (1.5110043287277222d0 2.1800525188446045d0 0.0d0)>
#<3D-VECTOR (2.030768394470215d0 2.731144428253174d0 0.0d0)>
#<3D-VECTOR (0.7122993469238281d0 3.623168706893921d0 0.0d0)>
NIL
```

← In this case, only three of the five generated solutions have been validated; the other two must have been outside the allowed range

Using Location Designators with TurtleSim

Using a location designator

Append the following code to `motion-designators.lisp`

Using Location Designators with TurtleSim

```
(def-fact-group goal-motions (motion-grounding)
  (<- (motion-grounding ?desig (go-to ?point))
    (desig-prop ?desig (:type :going-to))
    (desig-prop ?desig (:goal ?point))))
```



This will resolve any motion designator with properties

```
( (:type :going-to) (:goal some-location-designator) )
```

into

```
(go-to some-location-designator) instruction.
```

Using Location Designators with TurtleSim

Using a location designator

Append the following code to `process-modules.lisp`

- Specifically,
add the `go-to` part to the case in the `turtlesim-navigation` process module

```

(in-package :tut)

(def-process-module turtlesim-navigation (motion-designator)
  (roslisp:ros-info (turtle-process-modules)
    "TurtleSim navigation invoked with motion designator `~a'."
    motion-designator)
  (destructuring-bind (command motion) (reference motion-designator)
    (ecase command
      (drive
       (send-vel-cmd
        (turtle-motion-speed motion)
        (turtle-motion-angle motion)))
      (move
       (move-to motion))
      (go-to
       (when (typep motion 'location-designator)
         (let ((target-point (reference motion)))
           (roslisp:ros-info (turtle-process-modules)
             "Going to point ~a." target-point)
           (move-to target-point)))))))
  ...

```

```

(in-package :tut)

(def-process-module turtlesim-navigation (motion-designator)
  (roslisp:ros-info (turtle-process-modules)
    "TurtleSim navigation invoked with motion designator `~a'."
    motion-designator)
  (destructuring-bind (command motion) (reference motion-designator)
    (ecase command
      (drive
       (send-vel-cmd
        (turtle-motion-speed motion)
        (turtle-motion-angle motion)))
      (move
       (move-to motion))
      (go-to ← We now have a third type of motion designator, i.e. a new command go-to
       (when (typep motion 'location-designator)
         (let ((target-point (reference motion)))
           (roslisp:ros-info (turtle-process-modules)
             "Going to point ~a." target-point)
           (move-to target-point)))))))
...

```

```

(in-package :tut)

(def-process-module turtlesim-navigation (motion-designator)
  (roslisp:ros-info (turtle-process-modules)
    "TurtleSim navigation invoked with motion designator `~a'."
    motion-designator)
  (destructuring-bind (command motion) (reference motion-designator)
    (ecase command
      (drive
       (send-vel-cmd
        (turtle-motion-speed motion)
        (turtle-motion-angle motion)))
      (move
       (move-to motion))
      (go-to
       (when (typep motion 'location-designator)
         (let ((target-point (reference motion)))
           (roslisp:ros-info (turtle-process-modules)
             "Going to point ~a." target-point)
           (move-to target-point)))))))
  ...

```

The diagram consists of three red arrows pointing from explanatory text on the right to specific parts of the code on the left. The first arrow points from the text "If `motion` is a location designator ..." to the `(when (typep motion 'location-designator))` line. The second arrow points from the text "resolve the designator and assign the value to `target-point`" to the `(let ((target-point (reference motion)))` line. The third arrow points from the text "and call `move-to` to make the turtle go to that location" to the `(move-to target-point))` line.

Using Location Designators with TurtleSim

Using a location designator

And append the following code to `process-modules.lisp`

Specifically, add the `goto-location` function in the `turtlesim-navigation` process module

```

(in-package :tut)

...

(defun drive (?speed ?angle)
  (top-level
   (with-process-modules-running (turtlesim-navigation)
     (let ((trajectory (desig:a motion (type driving) (speed ?speed) (angle ?angle))))
       (pm-execute 'turtlesim-navigation trajectory))))))

(defun goto-location (?horizontal-position ?vertical-position)
  (top-level
   (with-process-modules-running (turtlesim-navigation)
     (let* ((?area (desig:a location
                    (horizontal-position ?horizontal-position)
                    (vertical-position ?vertical-position)))
            (goal (desig:a motion (type going-to) (goal ?area))))
       (cram-executive:perform goal))))))

```

Because we use **perform**, we need to make sure the correct process module for our **going-to** designator can be found

For that we add a rule to the fact-group **available-turtle-process-modules** from the **selecting-process-modules.lisp** file

Using Location Designators with TurtleSim

Using a location designator

The complete `process-modules.lisp` module should now look like the following

```

(in-package :tut)

(def-process-module turtlesim-navigation (motion-designator)
  (roslisp:ros-info (turtle-process-modules)
    "TurtleSim navigation invoked with motion designator '~a'."
    motion-designator)
  (destructuring-bind (command motion) (reference motion-designator)
    (ecase command
      (drive
        (send-vel-cmd
          (turtle-motion-speed motion)
          (turtle-motion-angle motion)))
      (move
        (move-to motion))
      (go-to
        (when (typep motion 'location-designator)
          (let ((target-point (reference motion)))
            (roslisp:ros-info (turtle-process-modules)
              "Going to point ~a." target-point)
            (move-to target-point)))))))

(def-process-module turtlesim-pen-control (motion-designator)
  (roslisp:ros-info (turtle-process-modules)
    "TurtleSim pen control invoked with motion designator '~a'."
    motion-designator)
  (destructuring-bind (command motion) (reference motion-designator)
    (ecase command
      (set-pen
        (call-set-pen
          (pen-motion-r motion)
          (pen-motion-g motion)
          (pen-motion-b motion)
          (pen-motion-width motion)
          (pen-motion-off motion))))))

(defun drive (?speed ?angle)
  (top-level
    (with-process-modules-running (turtlesim-navigation)
      (let ((trajectory (desig:a motion (type driving) (speed ?speed) (angle ?angle))))
        (pm-execute 'turtlesim-navigation trajectory))))))

(defun move (?x ?y)
  (top-level
    (with-process-modules-running (turtlesim-navigation)
      (let ((goal (desig:a motion (type moving) (goal (?x ?y) 0))))
        (pm-execute 'turtlesim-navigation goal))))))

(defun goto-location (?horizontal-position ?vertical-position)
  (top-level
    (with-process-modules-running (turtlesim-navigation)
      (let* ((?area (desig:a location
        (horizontal-position ?horizontal-position)
        (vertical-position ?vertical-position)))
        (goal (desig:a motion (type going-to) (goal ?area))))
        (cram-executive:perform goal))))))

```

Using Location Designators with TurtleSim

Using a location designator

Because we use `perform` in the `goto-location` function, we need to make sure the correct process module for our going-to designator can be found

For that we add a rule to the fact-group `available-turtle-process-modules` from the `selecting-process-modules.lisp` file

Using Location Designators with TurtleSim

Using a location designator

Add the following code to `selecting-process-modules.lisp`

Using Location Designators with TurtleSim

```
(in-package :tut)

(def-fact-group available-turtle-process-modules (available-process-module
                                                matching-process-module)

  (<- (available-process-module turtlesim-navigation))
  (<- (available-process-module turtlesim-pen-control))

  (<- (matching-process-module ?desig turtlesim-navigation)
      (desig-prop ?desig (:type :driving)))
  (<- (matching-process-module ?desig turtlesim-navigation)
      (desig-prop ?desig (:type :moving)))
  (<- (matching-process-module ?desig turtlesim-navigation)
      (desig-prop ?desig (:type :going-to)))
  (<- (matching-process-module ?desig turtlesim-pen-control)
      (desig-prop ?desig (:type :setting-pen))))

(defun perform-some-motion (motion-desig)
  (top-level
   (with-process-modules-running (turtlesim-navigation turtlesim-pen-control)
     (cram-executive:perform motion-desig))))
```

← Add this

Using Location Designators with TurtleSim

Using a location designator

Re-load the system (or recompile)

```
TUT> (ros-load:load-system "cram_my_beginner_tutorial" :cram-my-beginner-tutorial)
```

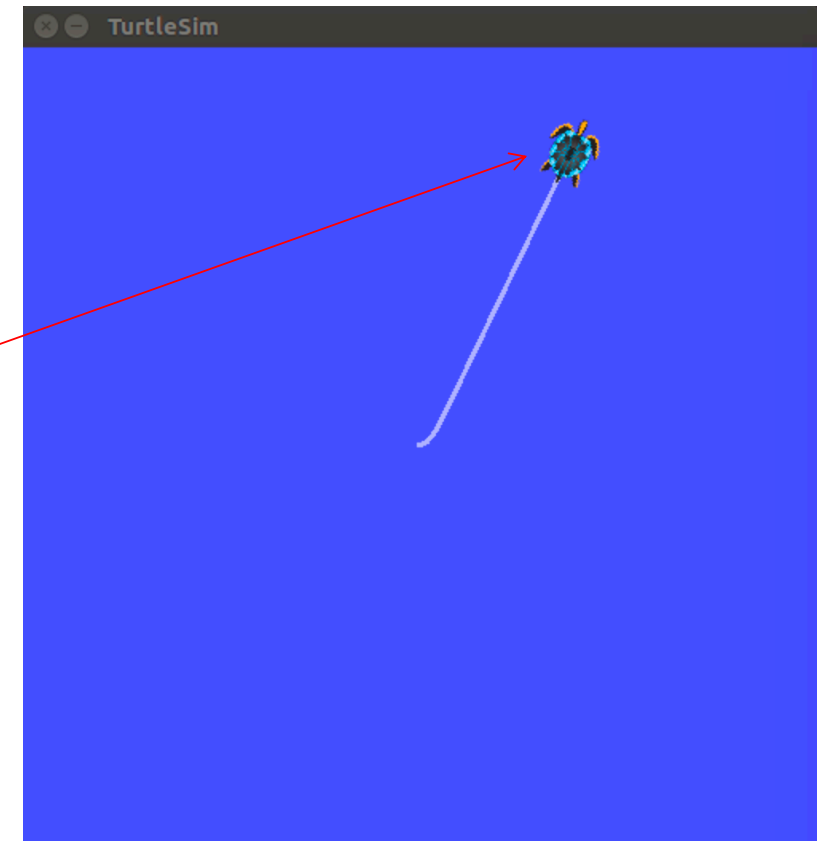
Automatically Choosing a Process Module for a Motion

Using a location designator

Let's try goto-location

```
TUT> (goto-location :right :top)
```

The turtle drives to the top-right sector



Using Location Designators with TurtleSim

Using a location designator

Let's try goto-location

```
TUT> (goto-location :right :top)
```

```
[(TURTLE-PROCESS-MODULES) INFO] 1562698457.619: TurtleSim navigation invoked with motion designator `#<A MOTION (TYPE GOING-TO) (GOAL #<A LOCATION (HORIZONTAL-POSITION RIGHT) (VERTICAL-POSITION TOP)>>`>'.  
[(TURTLE-PROCESS-MODULES) INFO] 1501153970.691: Going to point #<3D-VECTOR (10.131428718566895d0 8.874866485595703d0 0.0d0)>.
```

```
T
```


CRAM Beginner Tutorials

Create a CRAM Package

http://cram-system.org/tutorials/beginner/package_for_turtlesim

Controlling turtlesim from CRAM

http://cram-system.org/tutorials/beginner/controlling_turtlesim_2

Implementing simple plans to move a turtle

http://cram-system.org/tutorials/beginner/simple_plans

Using Prolog for reasoning

http://cram-system.org/tutorials/beginner/cram_prolog

Creating motion designators for the TurtleSim

http://cram-system.org/tutorials/beginner/motion_designators

Creating process modules

http://cram-system.org/tutorials/beginner/process_modules_2

Automatically choosing a process module for a motion

http://cram-system.org/tutorials/beginner/assigning_actions_2

Using location designators with the TurtleSim

http://cram-system.org/tutorials/beginner/location_designators_2

Background Reading

G. Kazhoyan, Lecture notes: Robot Programming with Lisp 7. Coordinate Transformations, TF, ActionLib, slides 5-8.

https://ai.uni-bremen.de/_media/teaching/7_more_ros.pdf

<http://wiki.ros.org/tf/Overview/Transformations>

T. Rittweiler, CRAM – Design and Implementation of a Reactive Plan Language, Bachelor Thesis, Technical University of Munich, 2010.

<https://common-lisp.net/~trittweiler/bachelor-thesis.pdf>