
Contents

1	Introduction	3
1.1	Motivation	3
1.2	Addressing the Challenges	7
1.3	Architecture of an FPGA-based Robot	8
1.4	Contributions of this Research	9
1.5	Organization of the Book	11
2	Literature Survey	13
2.1	Sensors and Processors for Mobile Robots	13
2.2	Robotic Operation in Known and Unknown Environments	15
2.2.1	Environment with Prior Knowledge of Object Geometries and Locations	15
2.2.2	Unknown Environments	16
2.3	FPGA-based Design	22
2.4	Summary	23
3	Design and Development of an FPGA-based Robot	25
3.1	Motivation	25
3.2	Overall Structure of the Mobile Robot	26
3.3	Design of Ultrasonic Range Finder	28
3.4	Power Delivery to FPGA Board and Ultrasonic Range Finders	29
3.5	Logic Level Translator	30

3.6	FPGA Board	31
3.6.1	Interface Modules	31
3.6.2	Pulse Width to Distance Converter (PWDC)	31
3.6.3	Universal Asynchronous Transmitter (UAT)	32
3.7	Description of Stepper Motor Interface	32
3.8	Summary	34
4	Hardware-Efficient Robotic Exploration	35
4.1	Introduction	35
4.2	Assumptions and Terminology	36
4.3	The Proposed Algorithm	37
4.3.1	Key Ideas	37
4.3.2	Pseudo-Code for the Proposed Algorithm	39
4.4	The Proposed Architecture for FPGA-based Processing	44
4.4.1	Pulse Width to Distance Converters	45
4.4.2	Content Addressable Memory	45
4.4.3	Stack Memory	47
4.4.4	Universal Asynchronous Transmitter (UAT)	47
4.4.5	Delay Element	47
4.4.6	Adjacency Information Storing Memory Blocks: APX, APY, AMX and AMY	48
4.4.7	Memory Blocks Used for Map Construction: DPX, DPY, DMX, DMY, Visited Grid point_x and Grid point_y	48
4.4.8	Input Gating for Reducing Energy Consumption	49
4.5	Experimental Results	50
4.6	General Remarks about Code and Demonstration	59
4.7	Conclusions	61
5	Hardware-Efficient Landmark Determination	63
5.1	Motivation for Landmark Determination	63
5.2	Assumptions and Terminology	64
5.3	Proposed Algorithm	66
5.3.1	Key Ideas	66
5.3.2	The New Algorithm	68
5.4	The Proposed Architecture	71
5.4.1	Random Number Generation	72

5.4.2	Processing Element (PE) Structure	74
5.4.3	Global Memory Organisation	76
5.4.4	Content Addressable Memory (CAM)	77
5.4.5	Special Memory	78
5.4.6	Adjacency Determination Unit	79
5.4.7	Input Gating for Reducing Energy Consumption	81
5.5	FPGA Implementation Results	81
5.6	Summary	86
6	The Road Ahead	87
6.1	Contributions of this Research	87
6.2	Extensions	88
6.2.1	Other Types of Maps	88
6.2.2	Navigation in Dynamic Environments	88
6.2.3	Localization and other Tasks	90
6.3	Concluding Remarks	90
A	Key Verilog Modules for Robotic Exploration	91
B	Suggestions for Mini-Projects	129
	References	133
	Index	139