

Joint Actions for a Aibo Team



- Design and develop the behaviors that make use of information from their teammates
- Evaluate your design in a game of 'fooling around'



Assignment 2004



Goals

- Evaluate Aibo software architectures of two teams
- Port software to Aibo ERS-7





Conclusion



- Advise German architecture for the Dutch Team.
- Interesting CMU modules for future research:
 - Vision
 - Localization



Conclusion



German team software package better!

Strengths:

- Clean modular code
- Documentation
- Tool support
- XABSL for behaviors





Dutch Aibo Team 2004



- German Open 2004 (Paderborn)
 - 6 goals scored; 11 goals received
 - Games: 1 win, 3 losses
- Lissabon 2004
 - 16 goals scored; 11 goals received
 - Games: 2 wins, 3 losses
 - Technical challenge: 7th position
 - Open challenge: most points
 - Variable lighting challenge: zero points
 - SLAM challenge: 5th rank
 - Qualified for Osaka 2005!





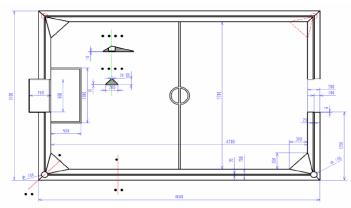




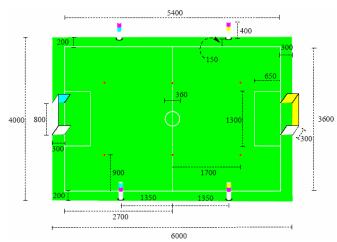
Assignment 2005

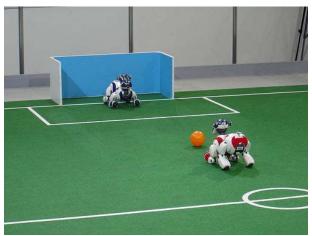


Improve field localization











Conclusion



- DT2005 Aibo is able to localize
 - Position is fine during set-up
 - After kick-off positioning is incorrect



 There remain unsolved hard-coded dependencies in the perception modules



Dutch Aibo Team 2005



- German Open 2005 (Paderborn)
 - Soccer ¼ final:
 - 8 goals scored; 9 goals received
 - Games: 1 win, 3 losses
- Osaka 2005
 - Soccer 9th position:
 - 15 goals scored; 13 goals received
 - Games: 2 wins, 1 draw, 2 losses
 - Technical challenge:
 - Open challenge: zero points
 - Variable lighting challenge: zero points







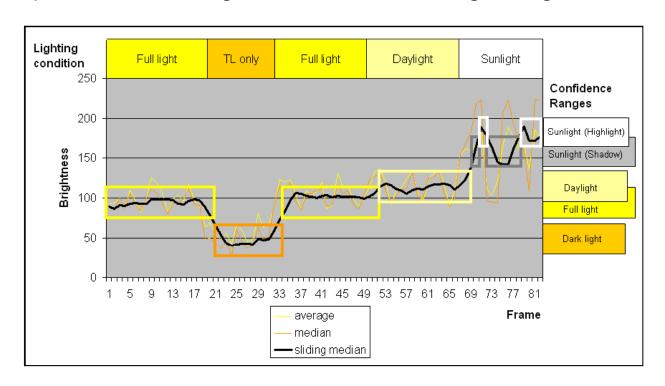




Dutch Aibo Team 2005



- Achievements:
 - Robust role assignment
 - Good self-localization:
 - average error: 63.5 mm, 2.94 deg
 - Multiple colortable algorithm for variable lightning conditions





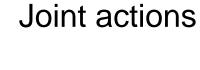


Assignment 2006



Improve team play

Single player behavior











Evaluation



Fooling Around: an extension of the Passing Challenge

