

Tech United Eindhoven Team Description 2019

Wouter Houtman, Chiel Kengen, Peter van Lith, Roy ten Berge,
Milan Haverlag, Koen Meessen, Yanick Douven, Ferry Schoenmakers,
Dennis Bruijnen, Wouter Aangenent, Jorrit Olthuis, Marzieh Dolatabadi,
Stefan Kempers, Mathijs Schouten, Ruben Beumer, Johan Kon,
Wouter Kuijpers, Harrie van de Loo, and René van de Molengraft

Eindhoven University of Technology,
De Rondon 70, P.O. Box 513, 5600 MB Eindhoven, The Netherlands
`techunited@tue.nl`,
Home page: www.techunited.nl

Abstract. The Tech United Eindhoven Middle-Size league (MSL) team achieved a first place in RoboCup 2018. To break the sequence of winning only in even years (2012, 2014, 2016, 2018) the team has made a considerable amount of developments. For the sake of qualification for RoboCup 2019, this paper describes the most notable of those developments.

Keywords: RoboCup Soccer, Middle-Size League, multi-robot, online calibration

1 Introduction

Tech United Eindhoven represents the Eindhoven University of Technology in the RoboCup competitions. The team started participating in the Middle-Size League (MSL) in 2006 and has been playing the final of the world championship for 11 years now, while achieving the first place four times: 2012, 2014, 2016 and 2018. At the moment of writing, the MSL team consists of 6 PhD-, 8 MSc-, 4 BSc-, 6 former TU/e students, 3 TU/e staff members and two members not related to TU/e.

This paper describes the major scientific improvements of our soccer robots over the past year. First, in Section 2, an introduction of our fifth generation soccer robot is given. Section 3 focuses on our efforts towards our sixth generation soccer robot; the eight-wheeled platform. Section 4 continues with our efforts in hardware and software to obtain a more reproducible shot. Section 5 describes two of our efforts to integrate methods from the domain of artificial intelligence into our robots. Section 6 concludes this paper.

2 Robot Platform

Our robots have been named TURTLES (acronym for Tech United RoboCup Team: Limited Edition). The development of the TURTLES started in 2005.



Fig. 1. Fifth generation TURTLE robots, with on the left-handside the goalkeeper robot. (Photo: Bart van Overbeeke)

Through tournaments and numerous demonstrations, these platforms have evolved into the fifth generation TURTLE, a very robust platform. For an outline of our robot design the reader is referred to the schematic representation in [1]. A detailed list of hardware specifications, along with CAD files of the base, upper-body, ball handling and shooting mechanism, has been published on a ROP wiki ¹. The software controlling the robots is divided into four main processes: Vision, Worldmodel, Strategy and Motion. These processes communicate with each other through a real-time database (RTDB) designed by the CAMBADA team [2]. More detailed information on the software can be found in [3] or in the flow charts as part of the qualification package.

3 Eight-Wheeled Platform

Last year, the mechanical design, presented in Figure 2(a), and the first version of the low level control architecture of the eight-wheeled platform were presented [4]. The main advantages compared to the three-wheeled platform are the possibility to apply the torque delivered by the motors in the desired movement and the expectation to keep all wheels on the ground while accelerating. In this section, first the improvements in the low-level control will be discussed. As the eight-wheeled platform is non-holonomic while the current high-level software assumes the platform to be holonomic, some adaptations have to be made in order to be able to play soccer. The ideas on how to make this connection will be elaborated in Section 3.2.

¹ <http://www.roboticopenplatform.org/wiki/TURTLE>

3.1 Improved Low-level Control Architecture

This platform consists of four sets each having two hub-drive wheels and thus five times over-constrained. Each pair of wheels can rotate around its suspension by actuating the corresponding wheels in opposite direction [4]. In order to actuate the platform, last year a kinematic control scheme was presented. Here it was observed that the performance was limited due to interaction between the wheels. As a result, the control-architecture as shown in Figure 3 was designed.

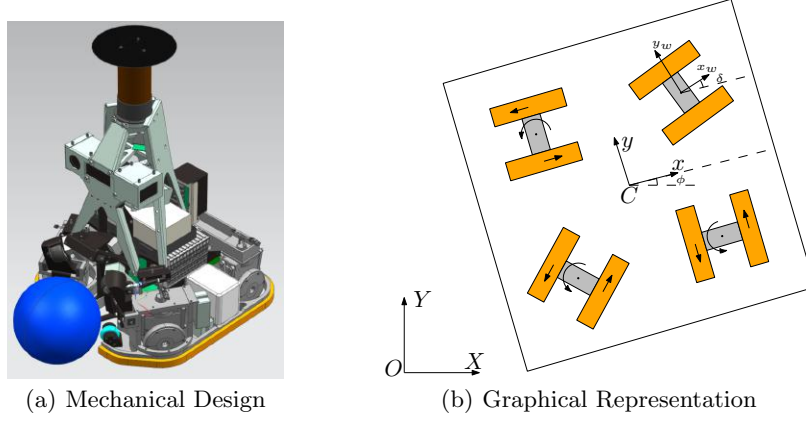


Fig. 2. The eight-wheeled platform with four suspended wheel combinations which are able to rotate around its center hinge.

For this controller, it is desired to manipulate the position x, y and orientation ϕ of the center C of the platform. First is looked at the left lower part of this figure, which is marked with "Reference Generation of Pivots". Here, the reference angle δ_{sp} of each wheel-unit $i = 1, 2, 3, 4$ is based on the desired platform velocity $v_{sp} = [\dot{x} \ \dot{y} \ \dot{\phi}]^T$ using the inverse kinematics G of the platform. Here it is still assumed that the platform is holonomic. As this is not the case and in order to prevent step-responses, each pivot-setpoint is smoothed with a second order setpoint generator. Next, in the right lower part of the same figure indicated with "Pivot Controllers", each reference angle of the pivots is controlled using a separate but identical position-to-force PD-controller C_δ . Here, the torque τ_w has an opposite direction for each wheel in a wheel-unit. By designing a feed-forward FF_δ for each pivot, the performance of these controllers is significantly increased. Now, using an estimate of the wheel-velocities v_w of each wheel and the rotation δ_i of each wheel unit, the platform-velocity v is determined using the forward kinematics J of the platform. This is required to control the motion of the platform, shown at the left-upper part of the figure. As the platform is non-holonomic, two velocity-to-torque PID-controllers are used to control three

degrees of freedom. The first controller C_t controls the translation by projecting the velocity-errors $\dot{e}_x$ and $\dot{e}_y$ of both the x and y direction into the direction of the setpoint. This is considered as the controllable direction, as the wheels are kinematically oriented according to this reference. The orientation is controlled using a separate controller C_r . Finally, the wrench w_p is distributed among the eight-wheels. It is still under investigation on how to improve this distribution.

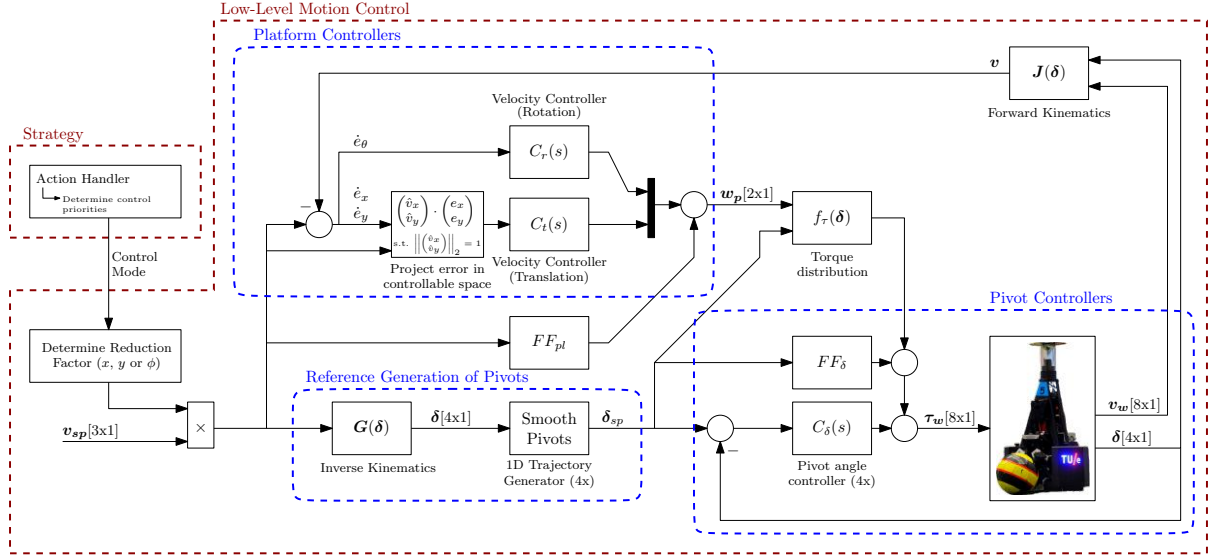


Fig. 3. Improved low-level control architecture of the eight-wheeled platform.

3.2 Integration into High-Level Software

The software used for the current three-wheeled platforms is designed assuming the platform to be holonomic. As a result, the motion software will attempt to control the position x, y, ϕ of the platform. For the eight-wheeled platform, this is however not possible due to the non-holonomic constraints set by the pivots. Therefore, in order to position at a specific location on the field, reducing small positioning errors requires the pivots to change orientation continuously. As a result, a large amount of energy is consumed in order to reduce these errors. However, in order to play soccer, it is not always necessary to control all three directions similarly. If, for example, the task of a robot is to intercept a pass, it is important that it positions itself on the line of the movement of the ball. In this situation, it is less important to position a bit more towards or a bit away from the ball. Therefore, as shown in Figure 3, depending on the action set by the high-level strategy, the relevant directions will be prioritized. This priority

mode is then communicated to the motion controller, where it is used to lower the velocity references in the non-relevant directions.

4 Accurate Shooting

During matches it has been observed that the variation in the lob shots of the robots is too large, causing a lot of shots at goal to miss [5]. This section elaborates on improvements of the shooting performance of the robots, to make lob shots more reproducible. To this extent, two solutions are proposed. One solution to gain improvements over short time, by adding a passive mechanism to the shooting mechanism. In addition, one solution is to improve the shooting performance over longer time, uses the Kinect as a feedback mechanism to calibrate the shooting mapping. This section is structured alike.

Thorough analysis of the cause of variation between the lob shots showed that a significant amount of variation was caused by the shooting lever not returning to its initial starting position before each shot. This results in the lever to have a different velocity when it impacts the ball. To eliminate this cause of variation, a passive mechanism was designed to retract the lever to its initial position, and to hold it at this position during driving.

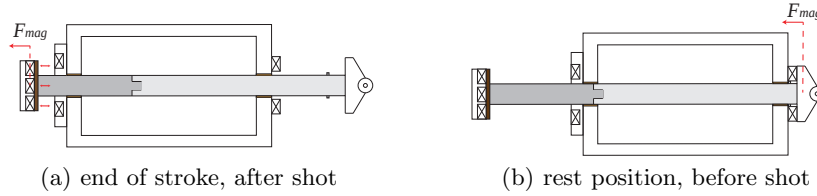


Fig. 4. Schematical representation of how two sets of magnets ensure a consistent initial position of the solenoid.

Figure 4(a) shows schematically how a set of repelling magnets push the lever backwards when it has moved fully forward after a shot. A second set of magnets at the front of the solenoid pulls the lever into the initial starting position, and hold it there, Figure 4(b). Experiments and theoretical analysis showed no observable decrease in shooting power using this mechanism. As a result, the reproducibility of the shot increased as the standard deviation decreased from 0.32 m/s to 0.08 m/s and from 1.06 degrees to 0.49 degrees for the ball's starting velocity and angle respectively.

Over longer periods of time (weeks, months), small changes in the shooting mechanism (lubrication, bearing performance) occur, which need to be compensated. To shoot at a specific target, the inverse dynamics of the shooting mechanism is

modelled in order to calculate the required robot inputs from a desired initial ball velocity v_0 and angle α_0 . For this mapping a second order polynomial describing the robot shooting dynamics was chosen, since this was proven to be sufficient from previous research [6]. Using an extended Kalman Filter (EKF), the polynomial coefficients can be recursively updated after each shot while taking the variation in the measured initial ball state into account. The state vector of the filter becomes $x = [a_0 \ a_1 \ a_2 \ a_3 \ a_4 \ a_5]^T$, $u = [K \ L]^T$. a_{0-5} are the polynomial coefficients, and K and L the shooting duty cycle and lever height settings respectively; the inputs of the shooting mechanism. Using the 3D Kinect camera mounted on the robot, the realised initial ball velocity v_0 and angle α_0 can be estimated in order to update the mapping.

5 Artificial Intelligence

This section describes our efforts to arbitrary ball detection, subsection 5.1, and efforts towards learning opponent behavior, subsection 5.2. The latter is a continuation of our work on recognizing robots in camera images [7] and predicting robot behavior [8] as described in [3,4].

5.1 Arbitrary Ball Detection

Ball detection is currently based on the upper and lower bounds of the YUV values of the ball its color. This detection method works fluently in most cases, however it comes with limitations. For example, changes in the brightness make the calibration of the upper- and lower bounds less accurate, the algorithm is more likely to make false predictions if the color of the ball is similar to its environment, and the algorithm is only capable of detecting one-colored balls.

To solve these inaccuracies and make the detection more humanlike, an approach using a machine learning algorithm is proposed. The new ball detection algorithm uses multiple convolutional layers to create feature mappings of the camera frame. These feature maps are then used to localize potential ball locations. Finally, the potential ball locations are classified through a neural network providing the probability-rate of the location actually holding a ball. Figure 5 visually represents the algorithm.

A speed of 13 frames per second using only one CPU core with an accuracy of 80% on images with different balls with variable brightness and colors was achieved. In further research, the focus will be on implementation. The achievable speed on a Jetson board will be researched, if needed different ways of integration will be explored.

5.2 Analysis

The arbitrary ball recognition may be combined with previous work on recognizing robots [7] and forms the basis for a new method of building a shared world model. Currently the world model is based on conventional image processing

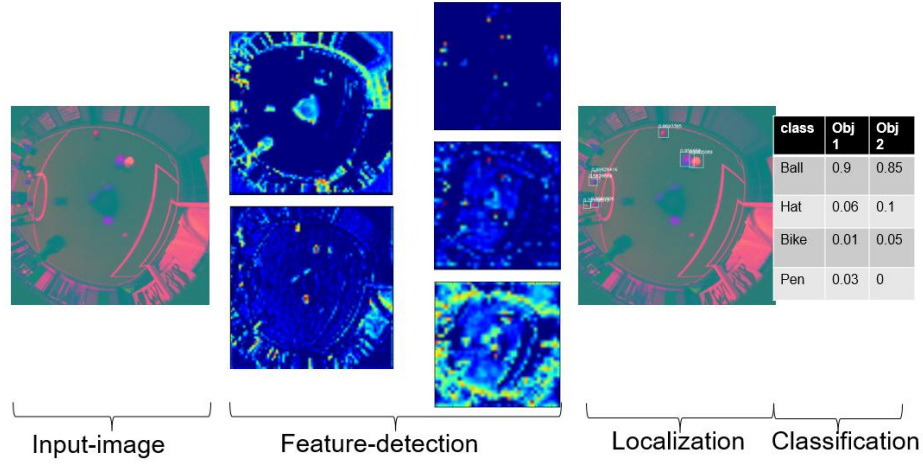


Fig. 5. Object detection algorithm

technology and kept as a logfile by all robots of the team. The aim is to use this information to learn the behavior of competing teams and use this in our simulator. The world model information from the TURTLES during a game is obtained with a frequency of about 10-30 Hz. In that data Game Turning Points (GTP) are identified. GTP's are points where a switch is made between attacking and defending. Such situations occur typically when the ball is lost or regained, or shot at the goal. Using these GTP's all successful or failing episodes during a game are found. Episodes describe a game moment as a series of successive steps. The number of steps of an episode varies between just a few to sometimes several hundreds of steps. Our analysis is limited to the last 100 steps of an episode.

5.3 Classification

Having collected these episodes, two functions are performed. First a Game Situation Image (GSI) is created for each step of an episode, analogous to the work of van 't Klooster [8]. Then all episodes are classified according to its status as being one of the following: Attack or Defend, Own Half or Opponent Half, Our Ball or Opponent Ball and the starting situation, like Kickoff, ThrowIn etc. For each step in an Episode, the movements of the four field players of a team are calculated as single steps in the X and Y direction as Quantized Team Moves (QTM). The GSI and its QTM steps are fed into a neural network and let the network learn the relationships between the world model and moves. Because each Episode leads to a desirable or undesirable situation, a reward or punishment is assigned to the episode. This network then learns how a team responds to the various game situations. Two different approaches will be tested: a Deep Recurrent Q-Learning Network (DRQN) and a Deep Residual Network (DRN) to find out which of these two approaches best captures the team behavior.

6 Conclusions

In this paper we have described the major scientific improvements of our soccer robots over the past year. Our developments in the control of the eight-wheeled platform expand to the platform and strategy level, bringing the introduction of the eight-wheeled platform closer. By integrating magnets into the solenoid assembly, we have reduced the standard deviation of our shots, increasing reproducibility. For arbitrary ball detection we have verified the feasibility of a neural network on the TURTLE's computational units. The research to modelling opponents continues, currently the classification process is revisited.

Altogether we hope our progress contributes to an even higher level of dynamic and scientifically challenging robot soccer during RoboCup 2019 in Sydney, Australia. The latter, of course, while maintaining the attractiveness of our competition for a general audience. In this way we hope to go with the top in Middle-size league for some more years and contribute to our goal in 2050!

References

1. Lopez Martinez, C., Schoenmakers, F., Naus, G., Meessen, K., Douven, Y., Van De Loo, H., Bruijnen, D., Aangenent, W., Groenen, J., Van Nindhuijs, B., Briegel, M., Hoogendijk, R., Van Brakel, P., Van Den Berg, R., Hendriks, O., Arts, R., Botden, F., Houtman, W., Van 't Klooster, M., Van Der Velden, J., Beeren, C., De Koning, L., Klooster, O., Soetens, R., Van De Molengraft, R.: Tech United Eindhoven Team Description 2014. (2014)
2. Almeida Luis, , Santos, F., and Facchinetti Tullio, and Pedreiras Paulo, and Silva Valter, and Lopes L Seabra: Coordinating Distributed Autonomous Agents with a Real-Time Database: The CAMBADA Project. In Aykanat C., Dayar, T., Körpeoğlu I., eds.: Computer and Information Sciences - ISCIS 2004, Berlin, Heidelberg, Springer Berlin Heidelberg (2004) 876–886
3. Schoenmakers, F., Meessen, K., Douven, Y., Van De Loo, H., Bruijnen, D., Aangenent, W., Van Nindhuijs, B., Briegel, M., Van Brakel, P., Senden, J., Soetens, R., Kuijpers, W., Olthuis, J., Van Lith, P., Van 't Klooster, M., De Koning, L., Van De Molengraft, R.: Tech United Eindhoven Team Description 2017. (2017)
4. Schoenmakers, F., Meessen, K., Douven, Y., Loo, H.V.D., Groot, C.D., Farahani, M.D., Lith, P.V., Scheers, P., Sommer, R., Nindhuijs, B.V., Brakel, P.V., Senden, J.: Tech United Eindhoven Team Description 2018. (2018)
5. Kengen, C.M., Douven, Y.G.M., Van De Molengraft, M.J.G.: Towards a More Reproducible Shot with the Tech United Soccer Robots. Technical report, Eindhoven University of Technology, Eindhoven (2018)
6. Senden, J., Douven, Y., van de Molengraft, R.: A Model-Based Approach to Reach a 3D Target with a Soccer Ball , Kicked by a Soccer Robot. PhD thesis, Eindhoven University of Technology (2016)
7. Van Lith, P., van de Molengraft, M., Dubbelman, G., Plantinga, M.: A Minimalistic Approach to Identify and Localize Robots in RoboCup MSL Soccer Competitions in Real-time. Technical report
8. van 't Klooster, M., Nijmeijer, H., Dubbelman, G.: Deep Learning for Opponent Action Prediction in Robot Soccer Middle Size League. Technical report, Eindhoven University of Technology, Eindhoven (2018)