

OMID 2014 Team Description

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Abstract. This Paper is a general description of OMID 2014, one of the Robocup Small Size League teams. The description includes hardware of robots and a general overview of software architecture. This time we have some improvement that include a complete new software design, noise avoiding ball detection, new design of robots main board.

1 Introduction

The Omid robotics team is a branch of robotic society of ECE department of Shahed University. Our team started the Small-Size League in summer 2007 with the effort of former member. Now OMID is working with new members and formers are as guiders. Here is an overview on the robots preparation and performances of each part respectively and all together. According to Robocup 2012, we Focus on some special problems :

- Breaking down the MOSFETs of motor driver during the match.
- Breaking down the IGBTs in shooting moments (after some shoots)
- nRF Simultaneously send and receive problems.
- Optimization PI controller Coefficients.
- Optimization Regulators in main board.
- AI plans to solve some weakness.

The Solutions we prefer for each of the problems, described in related part of TDP Briefly.

And According to increase players number in the field we add 3 more robots and rich 10 players.

2 Mechanical Design

2.1 Driving System:

The main plan of robot is made of Aluminum. 4 Omni-directional carry the main body, each wheel is coupled to an EC-45-Flat brushless 30 watt motor via an inverse gear with a transmission ratio of 1:5. These Wheels are fully designed in one piece and no screw has been used in the structure of wheels. This feature causes more efficiency, more wheel life time and simplicity in design.

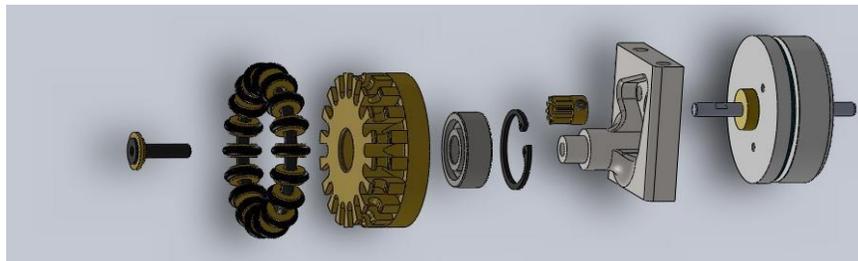


Fig.1. Omni-directional wheel structure.

2.2 Kicking System:

There are two solenoids that help to kick the ball, both for direct and chip kick. A flat plunger is made of steel, 4mm thickness. Direct kick plunger is made of two materials. The first part material is magnet which is steel, and the second part is made of a material with no magnetic property such as Aluminum. This feature causes a powerful kicking system.

2.3 Spin-Back System:

The Spin-Back module is driven by 15 watt Maxon EC16 with a transmission ratio of 2:1. As we have in Small-Size League rolls the robots must have specific dimension, our robots have 178mm of diameter and 148mm of height and also each robot covers less than 20% of ball. The whole robot is about 2.5 kilograms weight. 3D simulation models shown in Fig.2 are created with SolidWorks.



Fig.2. Robot's mechanical plan design

3 Electrical System

The main board consists of FPGA cyclone III [1]. We are using PI controller in order to drive all motors[3]. Each motor is equipped with an encoder to generate the feedback signal for PI controller. Motors are driven by MOSFETs and Driver IC. The nRF24L01+ is wireless communication that used[2]. It occurs in 2.40GHz band. we use two, 2 cell-1500 MH li-polymer batteries for the power and main board. The motor drive circuit, wireless communication part, and main control circuit are designed in a single board rather than the shooting circuit, which connect to the main board by small cables.

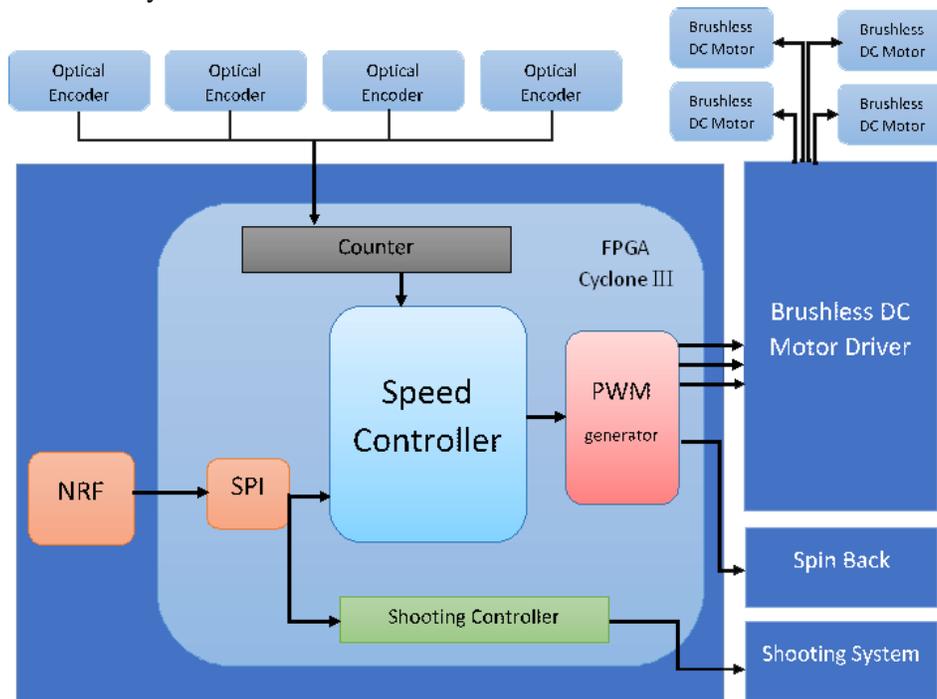


Fig.3. A block diagram of the robot's hardware system.

3.1 Central Control

We use a cyclone III FPGA as the main controller to generate all control signals for motors. The full duplex wireless communication system receives the command packet from the AI and sends the robot status to AI. Once a packet arrives, it has to be decoded and processed with the data of hall sensors and encoders to generate signals to handle motor drivers and shooting system. Also we use buffer for every input to FPGA pins to avoid FPGA damages.

3.2 Motor Driver

This part drives 4 brushless DC motors and 1 brushless DC motor for Spin Back. Motors are driven by Driver IC and MOSFETs. We utilize 3 phase inverter for DC motor drive. One of the Advantages of this motor driving is that the switching speed become faster than the older drivers. We decided to use ACS712 current sensor for current feedback of main board and then reduce motor speed in FPGA to reduce current to solving MOSFETs break down during the matches.

3.3 Shooting System

There are two kickers, a direct kicker and a chip kicker. We developed the flat kick system to kick in maximum velocity, approximately 8 m/s. The kicker board can charge two 2200 μ F capacitors from 0V to 250V in about 5 seconds with 2A average current. In order to avoid IGBTs break down in shooting moment, SNUBBER[5] as secondary Circuit used, that damping extra current.

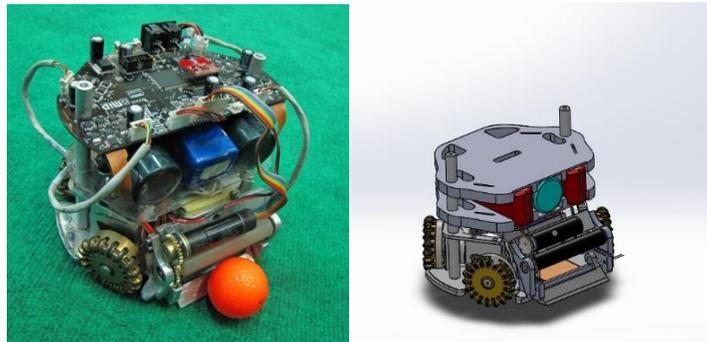


Fig.4. A picture of Omid robots.

3.4 Communication:

The communication between robots and computer performed with nRF24L01+ module. The nRF24L01+ is a single chip 2.4GHz transceiver with an embedded baseband protocol engine, suitable for ultra low power wireless

applications. The nRF24L01+ is designed for operation in the world wide ISM frequency band at 2.400 - 2.4835GHz.

4 Software

The robots software is separated to two main sections. Visioning software and Game play algorithms.

4.1 Vision

For purpose of real time image processing and object recognition, we use two cameras (The Stingray F_046B/C's high resolution) and SSL-vision software [4]. The whole artificial intelligence is on one computer receiving the data of SSL-Vision and Referee in each frame and uses them to make decision.

4.2 Game Play Strategy Algorithms

4.2.1 Operational Functions

Functions of this section are categorized in three levels. Low, Medium and High Level Functions.

- **High Level Functions**

These functions specify the current skill of the robot such as taking a defensive position, Goal kick, corner kick, passing the ball and so on. To do a high level function we need to make it closer to machine language, so we use medium level functions to do this task.

- **Medium Level Functions**

Functions in this level are mostly common robot actions. For example one of these functions is "Moving In Field" so we can move and turn in field with this function. As you can see again we need to get closer to machine languages so we use low level functions.

- **Low Level Functions**

Low Level Functions are the robot basic behaviors including: exactly addressed movements, stop, spin back On/Off, direct kick and chip kick. Functions in higher levels are interpreted to the low levels in order to execute the result of an appropriate command and send to the robot circuit via NRF.

As an example when the Decision Section (4.2.2) chooses the defensive state for a robot, the high level function will be set to "defense", consequently the medium level function will be set to "move in field" and then related low level functions such as gotoXY, stop, spin back,... will be executed so the command packet is ready to be sent to specific robot.

4.2.2 Decision making Section

The most important intellectual section is decision making section. In this section functions use data of SSL-Vision, SSL-Referee-Box and Robot Agents for current status of play and predictions of the next status in order to choose and decide a proper high level function.

4.3 GUI

4.3.1 Game Simulator

To test the Game Play Strategy Algorithms (4.2) without having two full robot teams and a play field, a Game Simulator GUI is prepared. In this way the Algorithm testing and error correction is done much easier regardless any physical and hardware problems and needs. Fig.5. a Screenshot of game simulator program.



Fig.5 a Screenshot of game simulator program

4.3.2 Game Manager

To monitor and control all robots in the game field, Monitoring Software is programmed that will be installed on the off board controlling system. The robots location and ID on the play field is received from the visioning software and simulated. In other word this software manages the game play.

References:

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4. Stefan Zickler, Tim Laue, Oliver Birbach, Mahisorn Wongphati, Manuela Veloso "SSL-Vision: The Shared Vision System for the RoboCup Small Size League"
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