The RSS Course Challenge

RSS Lecture 11 Wednesday, 13 March 2013 Prof. Seth Teller

Overview

- Historical context
- RSS Challenge scenario, requirements
- What you are provided
- Schedule through end of term
- Graded challenge milestones
- Q&A





Challenge sub-tasks

- Plan and Navigate:
 - Navigate, starting from known location (team places robot)
 - Optional: handle unknown start location (staff places robot)
 - Form motion plans around mapped, unmapped obstacles
- Identify Construction Site:
- Define site location a priori, or have robot choose it online
- Find Objects:
 - Detect objects of known types at expected locations
 - Detect objects at unknown locations, identify object types
- Gather and (Optionally) Store Objects:
- Collect blocks on, under, or within robot body
- Transport Objects:
 - Convey blocks to construction site (all, serially, in groups)
- Construction:
 - Create a simple structure of your choice (e.g. group, row, open/closed wall, stack, multi-story wall) at construction site
- Optional:
 - Any technical aspect on which your team wishes to focus

What you are provided

- Robot through lab 7 and other parts
- ROS source, staff solution code
- · Map of challenge environment, blocks
- Fiducial locations, color coding
- Rules / constraints

What you are provided

Materials

- Standard RSS microbot, sensors, etc.
- Delrin, Lexan, sheet metal, plywood etc.
- Any parts needed from RSS, EECS stockroom
- \$50 budget for outside components
- (use MIT's tax-free number, save receipts) – Absolutely no cardboard or duct tape
- Absolutely no cardboard or duct tape (decorative or cosmetic cardboard is OK)
- Shop access
- An approximate map of challenge area
- · Fiducial locations, color coding
- Rules / constraints





Block marshalling, servocontrolled release mechanism



Alternative design from another team

Examples from Past Years



Block marshaller



Funneling mechanism

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What you are provided

- Hardware
- An approximate map of challenge area
- · Fiducial locations, color coding
- Rules / constraints
 - Team must be ready to run when called
 - Team has 2 minutes to stage and launch bot
 - Bot must run autonomously for 10 minutes
 - Bot can't make destructive/irreversible changes
 - Walls will not move (much) if bot hits them
 - Each team should narrate its own bot's run
- External sensors, code?







- Come up with several questions
- We'll discuss until end of today's meeting
- Submit remainder to rss-help
 - We'll post responses to wiki (Challenge FAQ)

Questions?