

# CONCENTRATION

## Epson Manipulator Card Sorting System

Kausthub Krishnamurthy  
312086040

Email: kkri3182@uni.sydney.edu.au

James Ferris  
311220045

Email: jfer6425@uni.ssydney.edu.au

Sachith Gunawardhana  
440623630

Email: sgun5213@uni.sydney.edu.au

**Abstract**—An implementation of an Epson robotic arm as a card sorting mechanism aimed towards mimicing human style situational problem solving regarding the game Concentration (A.K.A. Memory) with the intent on addressing methods to simplify decision making processes for the game Set. By first addressing a simpler problem we can assess the suitability of this system overall in performing complex sorting operations in a way that directly mimics the way a human would perform the task.

### I. INTRODUCTION

The card game Concentration begins with a set of cards placed face down on a table. The player's objective is to pick up one card at a time and match it with another they have already seen before based on a specified criteria. This form of concentration is a building block to the game Set in that the similarity criteria can be modified and be made more complex. Something as simple as having the same card in every way to matching cards that share only some features.

The driving interest in this project was trying to explore the similarities and differences between the series of processes and actions a human would take to complete a job and compare them with those that a robotic manipulator would need to undertake in order to match those actions. Since there is an inherently different way that machines work to humans we wanted to look into those differences and consider how best to make a system come as close to the original human playing style as possible.

Previous efforts from other research students around the world, on card sorting systems, seem to involve a robotic system that sorts cards in a way that is specific to robots but lacks the capacity to PLAY the game.

I wish you the best of success.

mds

January 11, 2007

### II. BACKGROUND

Background: Describe related work that has been published in the literature. What papers, books and other resources have you consulted and how does their work relate to yours? What outcomes and possible innovation are you hoping to achieve?

#### A. Program Control Paradigms

#### B. Vision Detection Principles

The task was to identify the model of the card from the variations on shape, shape count and the filler. Figure shows

the different variables in the used card set.



Fig. 1. Different types of cards

Shape	Shape Count	Filler
Triangle	One	Shaded
Rectangle	two	Non-Shaded
Ellipse	three	Block

Fig. 2. Variables

In the robot arm we had there is a camera mounted on top of the table which can be used to get images of the objects place on the table. This images can be used to identify the object properties using image processing techniques.

There are plenty of approaches to find features in image processing. Following are some of the processing techniques.

- 1) Edge detection
- 2) Binary image processing[2]
- 3) Corner detection
- 4) Hough transformation
- 5) Swift operator
- 6) Histogram comparisons

In this project Edge detection and Binary image processing methods have been used to identify the cards from the table and shapes in the cards.

1) *Edge Detection*: An edge in an image is a significant local change in the image intensity, usually associated with a discontinuity in either the image intensity or the first derivative of the image intensity[2]. Matlab toolbox has an inbuilt function for Edge detection. Canny operator[1] have been used in this project.

2) *Binary image processing*: Using the histogram of the image a threshold can be identified to convert the image to a binary image with areas of interests. This method was feasible to this project as the image of back of the card gives pixel value near to black and a image of the front of the card gives pixel values near to white.

After creating the binary image with interested regions matlab inbuilt functions can be used to identify centroids and

orientations of the interested regions. Local positions can be transferred to world coordinates using a reference point in this case are 3 fiducial boxes at known positions.

### C. Motion

#### Degeneracy and Dexterity

- positions with multiple inverse kinematic solutions - can't select one, so stalls

## III. EXPERIMENTAL DESIGN

Experimental Setup or Design: Describe your experiment or the design of the system you are developing.

### A. Program Control Paradigms

### B. Vision Detection Principles

In order to achieve the vision detection task we had broken down the task into 4 sub tasks as following

- 1) Identify the Cards on the table.
- 2) Coordinates and pose of the cards.
- 3) Match the local coordinates to the world coordinates.
- 4) Identify the features of the cards.

Matlab image processing toolbox has been used for image processing tasks of this project.

#### 1. Identify the cards on the table.

- In the initial sweep after hiding the robot arm the camera will capture an image of the table. Histogram equalisation has been used to equalise the intensity over the image to make the image processing task easier.
- The back of the card gives pixel values near to black colour in gray image. Using this data a logical image has been created by using a threshold of pixel values less than 0.09. After removing pixels areas less than 1000 using function; bwareopen a structured element has been used to morphologically close the founded blobs.
- The same logic has been used to find face up cards as well. In that threshold of 0.91 has been used as face ups are near to white colour.

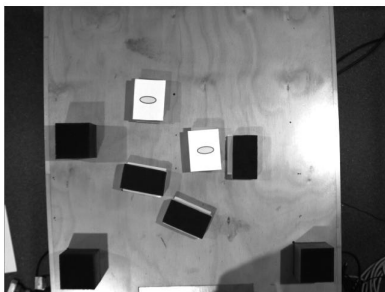


Fig. 3. Initial captured image

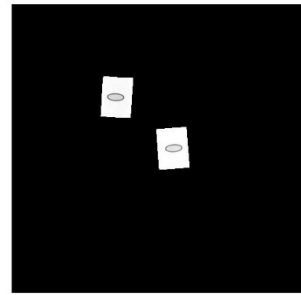


Fig. 4. Isolated Cards

#### 2. Coordinates and Pose of the cards

- Logical image created using above mentioned method has been used to find the local centroids and the orientations of the cards. The function; regionprops has been used to find the centroids and orientation. After finding both, centroids and orientations of the fiducials have been removed. In orientations a redundancy has been added to make sure that the robot arm will always work in the safety limits by checking the value of the angle.

#### 3. Match the local coordinates to the world coordinates

- 3 fiducials have been used to get the relative position of the cards. The method used was the perpendicular distance from two fiducials to the centroid of the card. Following figure will illustrate the method.

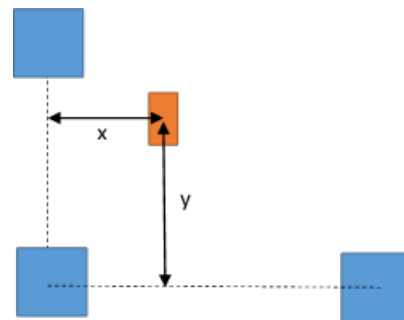


Fig. 5. Method used to match with world coordinates

#### 4. Identify the features of the cards

- The main target was to identify the card itself before trying to extract features. Used the same method as above and identify the card using pixel values as thresholds. Used the found logical image as a mask to isolate only the card face.
- From this image using a bounding box cropped out the card to process to find the features of shape, shape count and filler.
- Edge detection has been used to find the shape. After detecting the edges of the shape unnecessary edges has been removed using clearing edges connected to

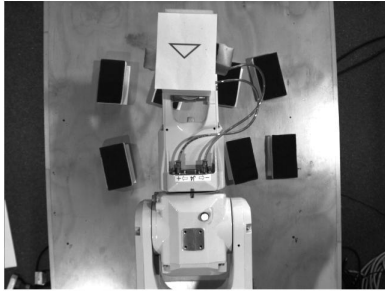


Fig. 6. Initial image of the faceup card

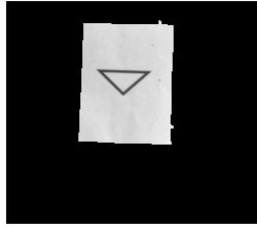


Fig. 7. Isolated Card

border and removing connected regions less than a threshold pixel area.



Fig. 8. Identified Edges

- Perimeter of the founded blob has been used to identify the shape as triangle, rectangle and ellipse had different perimeter values. No of connected components in this stage has been used to identify the shape count. If the shape count is greater than 1, the mean perimeter will be checked for identify the shape. The final logical image with the shape has been used with the original image to identify the filler status. Mean intensity of the blob area of the logical image in original image will have a value greater than 0.72 if the shape is not shaded as pixel value for white is 1. For block status the mean intensity will be lowest and for shaded status the intensity value will be between 0.72 and 0.5.

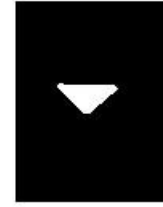


Fig. 9. Identified Shape

### C. Motion

## IV. RESULTS

Results: Show the results you have achieved. Consider how you might present these results in a clear and concise manner. Although you will understand the significance of the results, make sure it is clear to the reader as well.

### A. Vision

The image processing algorithm did able to match cards considering all variables, shape, shape count and filler. Results of the image processing can be summarised as follows.

Task	Completed
Identify & Differentiate Face Ups & Face Downs	100%
Identify the pose of cards & match with world coordinates	100%
Identify different Shapes	100%
Identify no of Shapes	100%
Identify the filler of the shape	100%
Identify the colour of the shape	0%

Fig. 10. Results Table

**Note:** We only did able to get gray images from the camera as there was a problem with white balancing with the camera driver which we didn't able to fix. If we had rgb images for check the color of the shape we should have check the 3 channels separately and found the dominant channel.

## V. DISCUSSION

Discussion: What are the implications of your results? What are the limitations of what you have done and how might the experiment/design be improved in the future?

### A. Vision

As shown in the results section the image processing algorithm developed was able to find matching cards irrespective of changes in card orientations. There were a number of pitfalls to the vision detection algorithm.

**Shadows:** When the lighting condition changes we had to manually change the thresholds we used to make the algorithm

work. Still when darker shadows exist the method we used won't work. If we had rgb images we would have convert the images into the HSV space and subtract the shadow from the image for a certain extent and use that image to further processing.

**Color:** As noted under results section as we didn't able to get RGB images this section was removed from our scope which is achievable easily.

## VI. CONCLUSIONS AND FUTURE WORK

Conclusions and Future Work: Discuss the implications of the results in a broader context, drawing conclusions and providing directions for future research in the area.

## ACKNOWLEDGMENT

The authors would like to thank...

## REFERENCES

- [1] John Canny, *Pattern Analysis and Machine Intelligence* ,6th ed IEEE, 1986/11.
- [2] R.Jain,R Kasturi,B.G.Schucnk *Machine Vision*, 1st ed McGraw-Hill,Inc, 1995.