F20RO Robotics Coursework

(Raymond) Pyra Firkins

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# Introduction

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# Task 1 Methods & Implementation Rationale

The controller for Task 1 heavily relies on the proximity sensors to dictate when the ePuck turns in a specified direction. The direction is specified with the ground sensor detecting a value of less than 500 (half its maximum), which it only reached when driving over the black hint square. The duration it spins for is around 1 in-World second, and not dependant on time, but rather the speed it spins at was manually determined with trial and error by just using basic use of “self.velocity\_left/right = “ statements. This implementation meant that the controller could operate without needing a Supervisor to send/receive information such as location/rotation direction.

A picture containing graphical user interface

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# Task 1 Results & Analysis

The results of the Task1Controller are consistent and predictable, as it is essentially a hard-wired controller to work with this exact scenario. This does mean it only works for this maze and that any other layout will cause the ePuck to not work, even just swapping which side the black square hints at would cause the controller to give the exact reverse-from-desired results.

The largest inefficiency with this implementation is the time delay when turning and when halting the controller, both from the same cause. There seems to be a constant ~2.3 second delay between hitting a wall and stopping, to realising its hit said wall and actually turning or halting operation. The reason for this is unclear, as in other controllers there is no such delay for this long a duration. Depending on the application of this robot, it would either be an insignificant issue or a large one; if time was a key factor in its performance metric, then these two 2.3 second delays combine to around 4.6 seconds, which is almost 37% of the total average runtime of the robot. However, if only consistent results matter, and the time taken is irrelevant, then this is a minor issue that could be generally ignored.

# Task 2 Methods & Implementation Rationale

The fitness functions in the controller specify fitness changes based around moving forward, spinning, moving backwards, and avoiding obstacles. Moving forward with any speed for both motors gives a +2 fitness, to discourage spinning on the spot of slamming backwards into walls, which itself is punished with backwardsFitness. Spinning on the spot in either direction, detected by both wheels moving in opposite directions at any speeds, nets a -2 to the fitness.

An avoidCollisionFitness started was provided in the template, but it was found that at times the black square would be confused with a wall or some other collision obstacle, so an avoidCollision fitness function was not implemented in the final build.

The supervisor is used to provide reward incentives based on the ePuck’s final location, both with a general gradient value for any x/z-value and for specific reward values for being in certain “zones”. The ePuck remaining in the starting “zone” gives a flat -3 fitness, to try to encourage exploration and further discourage spinning or running into a corner, and +3 for being in the top 1/3 of the maze. For the sideways paths, if a hint is detected it’ll reward for being on the right, and vice versa for when no hint detected.

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To tell the supervisor that a hint’s been detected, the emitter was altered to send a hintDetected variable instead of a “fitness:” string. Placing a “t” or “n” to indicate true/false was tested but the supervisor receiver wouldn’t work properly with the extended initial string, so the message had to be sent using the same length of characters before the fitness value itself. These alterations allow a reward based on the square hint to be created inside the supervisor. Otherwise, the ePuck would need to be aware of its own location, using either the GPS module which would modify the template World, or by the supervisor sending the location to the controller, which seemed to be a more difficult task.

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The next issue was resetting the hintDetected value back to false after a given run. Without this function the ePuck will consistently reach an end goal, but which side is not dependant on the hint. Some tests evolved to randomly prefer left or right in a way that coincided with being correct, but this occurred randomly and entirely be chance.

# Task 2 Results & Analysis

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# Discussion & Conclusion

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
|  | Time in minutes | | | |
|  | First run | Second run | Third run | Average time |
| Task 1  T-Maze A | 12.48775 seconds | 12.512437 seconds | 12.4641 seconds | 12.488096 seconds |
| Task 2  T-Maze A | 12.458922 seconds | 12.53051 seconds | 12.473162 seconds | 12.487531 seconds |
| Task 1  T-Maze B |  |  |  |  |
| Task 2  T-Maze B |  |  |  |  |

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Behaviour-Based Robotics (BBR) was found to lead to a robot that was predictable and consistent, yet restricted to only work on this specific set of circumstances, while Evolutionary Robotics (ER) lead to a robot that would work in varying situations, but could either find a bad result to focus on, or take an entirely unknown length of time to reach the desired result. Both have their pros and cons depending on the scenario: for example if BBR code had to be written for multiple maze types or layouts then that method would have become more inefficient, either relying on multiple separate controllers for each maze, or a single controller with an ever-growing number of “if/else if/else” statements, making code hard to read and understand.

# References

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<https://cyberbotics.com/doc/reference/supervisor#wb_supervisor_node_get_field> [Accessed 27/11/2022]

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