

Test Results

ID	Status	Description
1	passed	The install script works as it should on the right linux distribution (Debian, MINT Ubuntu). It is really a great help for us and sperses us a lot of time.
2	passed	The software of SimRobot works perfectly if you execute the setup script before.
3	passed	With the upload script from the hulks it is no problem to upload the code. You just have to know which IP-Address the NAO currently has.
4	passed	It is very easy to customize Sim Robot Scenes, because you just need to add the Robots to the file and set their Positions with a X and a Z Coordinate.
5	passed	It is also very easy to customize the team settings because you just need to add the robots and give them a unique player number which defines their start position
6	passed	Everything worked fine with no issues or errors
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8	failed	The robot was gammarayed but with the problem that he has a too slow processor so he had no time for network packages to analyze, which causes that he couldn't react to the Game Controller

		packages
9	passed	It works perfectly fine to customize the team files and the Game Controller recognizes it.
10	passed	The virtual robot is able to follow the sent commands like he should.
11	passed	The real robot is also able to react to the commands which are sent by the game Controller
12	passed	The MATE software works properly, but sometimes we get some Errors which are easy to fix
13	passed	The MATE software works as well as with the real Robots.
14	passed	Once a Robot located itself he can orientate himself pretty well. During the testing we discovered that the robots subjective perception has less weight to where the robot walks compared to the collective perception.
15	passed	The overall collective perception is created in merging the different positions of the individual robots together to increase accuracy.
16	passed	The vision module of the framework is able to recognise the ball pretty good.
17	passed	The nao walks to the ball like he should.
18	passed	The robots know where their start position is. With this information they create a location map which helps them to orientate wether

		they look to their own goal or to the enemy goal.
19	passed	The robots behave like they should. Further they change roles after every goal to optimize cooling performance.
20	passed	The brightness in our cellar is bright enough for the robots, so they see all lines pretty good.
21	failed	The robot doesn't know what to do when the ball is near the edge lines. Because he is not allowed to leave the field. So he doesn't find a possibility to kick the ball into the right direction.
22	passed	The robot knows where the ball is or he is trying to find it. For this there is a map which displays where the ball is most likely. The nao scans the area by turning and looking around.
23	failed	It seems like the robot doesn't change its kicking-velocity by the distance between ball and goal.
24	failed	The only case where we had a penalisation with a robot during the game was Judy but she had some general problems. So the reason for the fail might be a problem with wrong configurations..
25	faild	This Feature is not implemented jet.
26	failed	At the 2 vs 2 game one Robot thought he was at the right location but in reality he was at a completely different position.
27	passed	The framework has

		implemented some methods to prevent fouls like directly running into another robot (pushing).
28	failed	The light of the eyes is for displaying the rolls in the team. It also shows if the robot is looking for the ball or he has found it.
29	passed	The robots changed their behavior when they lost a teammate. After they lost a teammate they played more secure to overpass the time until the robot is back.
30	passed	The game was really good but some robots (Annastasia was to hot after one minute and Judy wasn't able to locate herself in the first half) had hardware problems. Two robots played the whole time without any problems