

Mblocks Stigmergic Tags and Algorithms

John W. Romanishin, John Mamish, and Daniela Rus

Abstract—This paper presents the work adding stigmergic tags WOO!, Mesh network communications... etc... to the M-Blocks modular robots. The first M-Blocks described in [?] could pivot about one axis of rotation only. In contrast, the 3D M-blocks can exert on demand both forward and backward

I. INTRODUCTION

THIS is the INTRODUCTION !!! Robots Robots Robots Robots are Grand!!

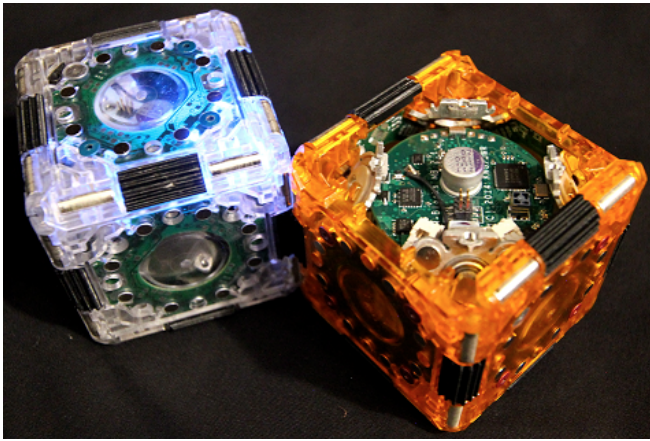


Fig. 1: This is a ROBOT!!

More Text...Organized... as follows. Section ?? gives an overview of related work that pertains to the 3D M-Blocks system. Section ?? presents the mechanical and electrical design of the Modules. Next, Section ?? presents data characterizing the hardware and the results of experiments with the system. Finally, Section ?? concludes with a short discussion and ideas for future work.

II. RELATED WORK

Modular self-reconfigurable robots are often characterized by their system topology: lattice, chain, or hybrid [?]. Most of the systems currently under development including U-Bots [?], Roombots [?], and SMORES [?] utilize a hybrid architecture. The fundamental distinction between hybrid or chain modules and strict lattice systems is that hybrid or chain modules have either fewer connector faces than lattice faces, or these connector faces are located in off-lattice positions. Chain and hybrid systems are typically designed to self-reconfigure using complicated implementations which approximate simpler models, such as the sliding cube model [?] or the pivoting cube model [?].

J. W. Romanishin, D. Rus are with the Computer Science and Artificial Intelligence Lab, MIT, Cambridge, MA, 02139 {johnrom|rus}@csail.mit.edu.

To the best of our knowledge, the 3D M-Blocks are the only self-reconfigurable robots capable of implementing a simple movement model in three dimensions that allows for both independent and lattice-based locomotion.

III. HARDWARE

Text is supposed to go here!!! Tag technologies are shown in Table ??.

TABLE I: Comparison of tagging technologies

	Passive	Size
RFID	0	0
QR Code	-1	-50

A. Magnetic Barcodes Overview

Text goes here!

IV. EXPERIMENTS

A. Tag Characterization Experiments

We did some stuff, wrote it down here...

B. Crystalization Experiments

We did some stuff, wrote it down here...

V. INTRODUCTION

We did things... Things are good. Bye!

ACKNOWLEDGMENTS

This work is supported by the NSF through grants 1240383 and 1138967.

SUPPLEMENTARY MATERIAL

<http://youtu.be/y27gUFO6mTA>

REFERENCES

- [1] J. W. Romanishin, K. Gilpin, and D. Rus, "M-blocks: Momentum-driven, magnetic modular robots," in *Intelligent Robots and Systems (IROS), 2013 IEEE/RSJ International Conference on*. IEEE, 2013, pp. 4288–4295.
- [2] M. Yim, W. Shen, B. Salemi, D. Rus, M. Moll, H. Lipson, E. Klavins, and G. S. Chirikjian, "Modular Self-Reconfigurable Robot Systems: Challenges and Opportunities for the Future," *Robotics and Automation Magazine*, vol. 14, no. 1, pp. 43–52, 2007.
- [3] Y. Zhu, J. Zhao, X. Cui, X. Wang, S. Tang, X. Zhang, and J. Yin, "Design and implementation of ubot: A modular self-reconfigurable robot," in *Mechatronics and Automation (ICMA), 2013 IEEE International Conference on*. IEEE, 2013, pp. 1217–1222.
- [4] M. Vespignani, E. Senft, S. Bonardi, R. Moeckel, and A. J. Ijspeert, "An experimental study on the role of compliant elements on the locomotion of the self-reconfigurable modular robots roombots," in *Intelligent Robots and Systems (IROS), 2013 IEEE/RSJ International Conference on*. Ieee, 2013, pp. 4308–4313.
- [5] R. Fitch, Z. Butler, and D. Rus, "Reconfiguration planning for heterogeneous self-reconfiguring robots," in *Intelligent Robots and Systems*, 2003, pp. 2460–2467.