



E-Puck Behaviour Implementation

ROBOTICS AND INTELLIGENT SYSTEMS

COP518

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February 17, 2016

Contents

1	Introduction	2
2	Background	2
2.1	Behaviours	2
2.2	E-Puck	2
2.3	HSV	2
2.4	Skin Colour	2
3	Design	2
3.1	Task A	3
3.1.1	Flowchart	3
3.2	Task B	3
3.2.1	Flowchart	4
4	Implementation	4
4.1	Main File	4
4.2	Breitenburg Follower	5
4.3	Following Light	7
4.4	Avoiding Light	7
4.5	Breitenburg Shocker	7
4.6	Follow Hand	7
5	Results & Testing	8
6	Conclusion	8

1 Introduction

Within the Robotics and Intelligence systems module groups worked together to implement different behaviours with an E-Puck. Many different behaviours were available for implementation, including attraction, hate and aggression.

This report will explain, in detail, the tasks set out before each group. It will progress by explaining the design established to tackle these objectives, the implementation of the design, testing and results before concluding and evaluation the coursework and the groups achievements.

The tasks given to each group was split into 2 separate parts. The first was to develop a behaviour on a single E-Puck. Such initial ideas proposed by Dr. Meng, included love where the E-Puck would follow close to, but without touching an object, or where the E-Puck would try to avoid objects. More of behaviours will be spoken about throughout this report in greater detail.

The second task included using 2 E-Pucks. One of the E-Pucks was tasked with following a human hand but not other objects, whilst the other was to follow the first E-Puck closely without touching it. This second E-Puck would imitate the love behaviour spoken about previously.

2 Background

Introduce the field of robots and speak about areas which are being researched.

2.1 Behaviours

Love, Hate, aggression and more...

2.2 E-Puck

What is an E-Puck with figure, who was it made by and so on...

2.3 HSV

Describe the HSV colour plane

2.4 Skin Colour

Discuss the finding in multiple research papers on skin colour in the HSV colour plane.

3 Design

This section will explain how both tasks A and B will be completed, giving diagrams and flowcharts of how the E-Pucks will carry out a particular task.

3.1 Task A

To begin designing a solution to the tasks set out in section 1, one must first decide upon the different behaviours to be implemented for the tasks. A relatively simple task to be implemented, which would be beneficial to both the first and second task, would be to implement a love behaviour.

Section 2 discussed how each behaviour would perform, illustrating that the love behaviour would follow but not touch the leading object. A second behaviour to be implemented would be an adaption of the aforementioned love behaviour, although instead of the E-Puck following an object it would instead follow a bright light placed before it. The E-Puck would use both the camera to discover any spots of light that have a much higher intensity than its surroundings.

One third and final possible behaviour to implement, providing time permits the group to do so, would be to implement an obstacle avoidance behaviour. The behaviour which attempts to avoid any nearby objects whilst moving in a particular direction. When it approaches an object it changes its direction to move away from the object.

The first and final behaviours rely heavily on the infrared senses situated around the edge of the E-Puck. The E-Puck will read in from the infrared sensors, each returning a voltage reading to the chip. This reading can then be used within a formula to calculate the distances to a nearby object. When an object is discovered nearby, the E-Puck must either turn to face it or alter its direction to move away from it, for the love and obstacle avoidance behaviours respectively. The E-Puck is then required to move forward at a fixed speed until either the object is very close, but not touching for the love behaviour or no longer detected for the hate behaviour.

To create the second behaviour of an attraction to light the E-Puck must be implemented in a similar way to the previously mentioned behaviours, although instead of reading the infrared sensor value for distance one will measure the amount of ambient light falling onto the device.

3.1.1 Flowchart

3.2 Task B

Task B requires the group to implement 2 different E-Pucks and cause each to do their own tasks. One E-Puck will be required to follow a hand whilst the other E-Puck will be required to follow the first E-Puck. This may seem similar after implementing the behaviours from task A, although many issues could arise with this task. These issues will be discussed toward the end of this section.

Since the love behaviour will have already been implemented once the implementation of task B begins it would be logical to make use of these behaviours to save time. Therefore to obtain the the desired output of the second E-Puck (the following of the first E-Puck), one may use this behaviour and achieve the required result.

For the first E-Puck, the E-Puck which will be following a human hand, the

Selector	Function
0	run_breitenberg_follower
1	finding_light
2	avoid_light
3	run_breitenberg_shocker
4	followHand

Table 1: A table to show what function is ran for each selector.

group will have to use both the camera and infrared sensors on the E-Puck and consult the research performed within section 2 surrounding the colour of human skin.

The E-Puck will begin by discovering any near-by objects using the infra-red sensors before turning the front camera towards any discovered objects. The front camera will then read in the image of the object. Removing a few rows of pixels from the image, for fast processing, the pixels will then be processed to find any required colour that the E-Puck is looking for, the colour of a hand. This processing will be done in the HSV colour plane as to reduce the impact lighting has on the colour of an image.

3.2.1 Flowchart

4 Implementation

This section will describe how each of the tasks mentioned in section 3 have been implemented, explaining the functions within the code, and any discrepancies between the design and final implementation.

The design was gradually implemented in stages, building up to the final completed solution to each task. To make the project easier to implement the demo project provided on the E-Puck[1] website was used as a template.

4.1 Main File

Within the demo project one can find the main file. This main file starts by finding the position of the selection, a single hexadecimal digit. This selector then decides which function will be called. This becomes very useful to the groups project as then each behaviour needed to be implemented can be ran when a unique selector is selected. Table 4.1 clearly shows the possible choices to the user with the code being displayed in the code snippet 1.

The functions shown in table 4.1 will each be discussed in detail throughout this section.

```

selector=getselector();
if (selector==0) {
    run_breitenberg_follower();
} else if (selector==1) {
    finding_light();
} else if (selector==2) {
    avoid_light();
} else if (selector==3) {
    run_breitenberg_shocker();
} else if (selector==4) {
    followHand();
} else{
}

```

Code Snippet 1: Processes for selecting which function to run

4.2 Breitenburg Follower

The ‘run_breitenburg_follower’ function is a function that was taken from the demo project mentioned previously. The function can be found in the ‘runBreitenberg_adv.c’ file along with it’s dependencies.

The function uses the front 4 infrared sensors to attempt to follow an object, reading in the distance to the object and calculating the linear and angle speeds using the functions shown in code snippets 3 and 2.

```

int angle_speed_calc(int pos, int gain)
{
    int consigne = 0;
    int angle_speed = 0;
    int ecart = consigne - pos;

    angle_speed = ecart*gain;

    if(angle_speed >= 1000)
        angle_speed = 999;
    else if(angle_speed <= -1000)
        angle_speed = -999;

    return angle_speed;
}

```

Code Snippet 2: Functions for calculating the angular speed of the E-Puck

The angular speed is calculated by passing the function the difference in the readings between the 2 front left infrared sensors and the 2 front right infrared sensors. The magnitude of this value then decides how quickly the robot must

```

int lin_speed_calc(int distance, int gain)
{
    int consigne = 100;
    float h = 0.05;
    int ti = 3;
    int ecart = consigne - distance;
    int lin_speed;

    ui_lin = ui_lin + h * ecart / ti;
    lin_speed = (ecart + ui_lin) * gain;

    if(lin_speed >= 1000)
    {
        ui_lin = 999/gain - ecart;
        if(ui_lin > 60)
            ui_lin = 60.0;
        lin_speed = 999;
    }
    else if(lin_speed <= -1000)
    {
        ui_lin = -999/gain + ecart;
        if(ui_lin < -10)
            ui_lin = -10.0;
        lin_speed = -999;
    }
    return lin_speed;
}

```

Code Snippet 3: Functions for calculating the linear speed of the E-Puck

turn left or right, whilst whether the value is positive or negative decides which way the robot should turn.

The linear speed calculator works in a similar way where the average of the front 2 middle infrared sensors are passed into the function and dependent upon the magnitude of this value the linear speed can then be calculated.

These values are then added together for the speed of the right wheel and the angular speed is subtracted from the linear speed for the left wheel causing the E-Puck to move in the desired way.

4.3 Following Light

The ‘finding_light’ function finds light using the infrared sensors once again, although instead of detected the emitted infrared light the sensors detect the ambient light.

One anticipated obstacle for this function would be for different environments the E-Puck would behave very differently. For example, in very dark environments the E-Puck will find it very easy to find a light source. Although, in brighter environments the E-Puck will find it much more difficult to find the light source being shone onto it. To attempt to overcome this problem a baseline reading of the environment is taken before the E-Puck begins to look for any light source. From here the E-Puck can compare any future readings with the baseline readings and thus find any increases in light, being any newly introduced light sources.

4.4 Avoiding Light

The ‘avoid_light’ function works in a very similar way to the ‘finding_light’ function although instead of being attracted to the light source it moves in the opposite direction.

4.5 Breitenburg Shocker

Once again, the ‘run_breitenberg_shocker’ function runs in a very similar way to the ‘run_breitenberg_follower’ but instead of moving towards an object when one is discovered on the front infrared sensors the E-Puck turns and moves away from it.

4.6 Follow Hand

As one may realise the ‘followhand’ function is more complex and therefore contains more problems to solve. The idea behind the function is to check whether there is object nearby the front 2 infrared sensors, if so the camera takes an image and checks whether or no the image is a hand. The camera does this by checking the colour of the image and recognising whether it is the range of the hue of a hand.

The first stage of this function is very simple and can be done easily, in the same way as previously seen functions by just reading the distance from an infrared sensor on the E-Puck.

These sensors then trigger whether an image should be taken. If the image is to be taken then it is done so by calling the 'hgetImage' function which has been taken from the aforementioned demo project and renamed. The following 'hImage' function then begins to process the image, firstly converting the RGB image to HSV. The code and algorithm for this can be seen in code snippet 4. One may notice that only the hue has been calculated and this is because only the hue is needed as the saturation and value intensity are both environment dependent. Therefore finding a hand in a brightly light room or a poorly light room should obtain similar results.

```
//RGB turned into an integer value for comparison
red = (hbuffer[2*i] & 0xF8);
green = (((hbuffer[2*i] & 0x07) << 5) | ((hbuffer[2*i+1]
    & 0xE0) >> 3));
blue = ((hbuffer[2*i+1] & 0x1F) << 3);
// convert to RGB to Hue
double hue = RGB2Hue(red, green, blue);
if(hue> 6 && hue<38){
    hnumbuffer[i] = 1;
    vis +=1;
}else{
    hnumbuffer[i] = 0;
}
```

Code Snippet 4: Converting RGB pixels to HSV

Once the hue has been calculated the function proceeds to categorise each pixel as a 1 if the hue lies within the range of a human hand or a 0 otherwise. The range the hue must lie within starts at 6° through to 38°. These values have been calculated after careful research was carried out on human skin colour, referred to in section 2.

The final stage of the function is to check the amount of times this hue has been seen and calculate a threshold where the E-Puck decides whether human skin is visible or not. This threshold was discovered after testing various threshold values which will be analysed in more detail throughout section 5.

5 Results & Testing

6 Conclusion

References

- [1] Pugh J., Cianci C., Klaptoch A., Magnenat S., Zufferey J.-C., Floreano D. Mondada F., Bonani M., Raemy X. and A Martinoli. The e-puck, a robot designed for education in engineering, 2016.