

TABLE OF CONTENTS

	pages
HALAMAN JUDUL	
PERNYATAAN KEASLIAN KARYA TUGAS AKHIR	
PERSETUJUAN DOSEN PEMBIMBING TUGAS AKHIR	
PERSETUJUAN TIM PENGUJI TUGAS AKHIR	
ABSTRACT	iv
ABSTRAK	v
ACKNOWLEDGEMENTS	vi
TABLE OF CONTENTS	viii
LIST OF FIGURES	xi
LIST OF TABLES	xvi
LIST OF EQUATIONS	xviii
CHAPTER I INTRODUCTION.....	1
1.1 Background	1
1.2 Problem Formulation	3
1.3 Application Boundaries	5
1.4 Objectives	6
1.5 Methodology.....	6
1.6 Writing Structure	7
CHAPTER II THEORETICAL FOUNDATION	9
2.1 Robot Soccer.....	9

2.2 Computer Vision.....	12
2.3 Centralized Vision System in Robot Soccer	12
2.4 Object Detection in Robot Soccer	13
2.5 Digital Image Processing.....	15
2.5.1 Image Acquisition.....	17
2.5.2 Image Enhancement	18
2.5.3 Color Image Processing.....	20
2.5.4 Morphological Processing	24
2.5.5 Segmentation	27
2.5.6 Representation and Description	36
2.5.7 Image Cropping.....	39
2.5.8 Geometric Image Transformation	40
2.6 Line-Line Intersection	42
2.7 Two Dimensional Matrix.....	43
2.8 Perspective Transformation.....	43
2.9 Angle Of View.....	45
2.10 OpenCV	46
2.11 Visual Studio 2010	46
2.12 Software Testing.....	47
2.10.1 White-Box Testing	47
2.10.2 Black-Box Testing	47
2.10.3 Testing Phases.....	48
CHAPTER III SYSTEM ANALYSIS AND DESIGN	50

3.1 System Analysis	50
3.1.1 Problem Analysis	50
3.1.2 Requirements.....	51
3.2 System Design.....	52
3.2.1 Physical Setup Design	52
3.2.1.1 Camera	52
3.2.1.2 Arena	53
3.2.1.3 Robots	53
3.2.1.4 Camera and Arena Positioning.....	54
3.2.2 Application Design	55
3.2.2 Arena Detection	57
3.2.2 Robot Detection	69
3.2.2 Ball Detection	78
3.2.2 Class Setup	80
3.2.2 Movement Simulation	82
3.3 Testing Scheme	88
CHAPTER IV IMPLEMENTATION AND TESTING	91
4.1 Physical Setup Implementation	92
4.2 Application Impelementation	93
4.2.1 Arena Detection Implementation	93
4.2.2 Robot Detection Implementation.....	97
4.2.3 Ball Detection Implementation.....	107
4.2.4 Movement Simulation.....	111

4.3 Software Testing	119
4.3.1 Unit Testing	120
4.3.1.1 Arena Detection Testing	120
4.3.1.2 Robot Detection Testing.....	122
4.3.1.3 Ball Detection Testing	125
4.3.2 Integration Testing	126
4.3.3 System Testing	128
4.3.3.1 The Effect of Different Camera Resolutions.....	128
4.3.3.2 The Effect of Different Rooms.....	132
4.3.3.3 The Effect of Different Lighting Conditions.....	139
4.3.3.4 The Effect of Different Camera Positions.....	144
4.3.4 Regression Testing	149
4.4 Review and Discussion.....	149
CHAPTER V CONCLUSION & FUTURE DEVELOPMENT	150
5.1 Conclusion	153
5.2 Future Development	155
BIBLIOGRAPHY	158
APPENDICES	A-1
APPENDIX A	A-1
APPENDIX B	B-1
APPENDIX C	C-1
APPENDIX D	D-1
APPENDIX E	E-1

LIST OF FIGURES

	pages
Figure 2.1 Overall centralized control approach system and subsystems	10
Figure 2.2 Detailed overall system of centralized approach.....	13
Figure 2.3 Edge detection	14
Figure 2.4 Background substraction	14
Figure 2.5 Color segmentation	15
Figure 2.6 Sampling and quantization concept	18
Figure 2.7 Image post-sampling and quantization	18
Figure 2.8 Gaussian Kernel	20
Figure 2.9 Image before and after applied by Gaussian Kernel.....	20
Figure 2.10 RGB Color model	22
Figure 2.11 HSV Color model	24
Figure 2.12 Dilation example.....	25
Figure 2.13 Erosion example.....	25
Figure 2.14 Opening example	27
Figure 2.15 Closing example.....	27
Figure 2.16 a general 3x3 mask	28
Figure 2.17 Mask for detecting isolated points.....	29
Figure 2.18 Mask for detecting lines.....	29
Figure 2.19 Sobel Mask for horizontal and vertical edge.....	31
Figure 2.20 application of sobel mask on an image.....	32

Figure 2.21 Result of canny on an image	33
Figure 2.22 Example of plotting point on parameter space	34
Figure 2.23 Example of single and multiple threshold.....	35
Figure 2.24 Border tracing example.....	37
Figure 2.25 Splitting a curve for polygon approximation.....	38
Figure 2.26 Douglas-Peucker pseudocode	39
Figure 2.27 Translation and rotation example on an image.....	41
Figure 2.28 example of perspective transformation.....	45
Figure 2.32 Field of view example	46
Figure 3.1 Problem analysis overview	51
Figure 3.2 Patterns of robots	54
Figure 3.3 Illustration of physical setup	55
Figure 3.4 Application overview flowchart.....	56
Figure 3.5 Pipeline of the application	57
Figure 3.6 Arena detection process	58
Figure 3.7 Alternate arena detection process.....	58
Figure 3.8 Flowchart of storing image into MatrixA[x,y]	60
Figure 3.9 Cropping example	61
Figure 3.10 Image cropping flowchart	61
Figure 3.11 Flowchart of finding the arena contour	63
Figure 3.12 Illustration of finding the arena contour	64
Figure 3.13 Flowchart of hough transform	65
Figure 3.14 Flowchart of line-line intersection	66

Figure 3.15 Line detection and corner acquisition	67
Figure 3.16 Perspective transformation illustration	68
Figure 3.17 Robot detection process illustration	71
Figure 3.18 Flowchart of robot shape detection	72
Figure 3.19 Robot shape detection process illustration	72
Figure 3.20 Role marker flowchart	74
Figure 3.21 Role marker checking process illustration	75
Figure 3.22 Heading marker checking flowchart	77
Figure 3.23 Heading marker checking process illustration	78
Figure 3.24 Flowchart of ball detection	79
Figure 3.25 ball detection process illustration	80
Figure 3.26 UML class diagram for robot class and ball class	81
Figure 3.27 Attack and defense formation	84
Figure 3.28 Angle of orientation	85
Figure 3.29 Angle calculation	86
Figure 3.30 Segmenting path line	87
Figure 4.1 Implementation of physical setup.....	92
Figure 4.2 The process of detecting the arena	96
Figure 4.3 The screenshots the implementation of robot shape detection	99
Figure 4.4 Detected role markers	102
Figure 4.5 Heading marker checking process	105
Figure 4.6 Heading checker area	106
Figure 4.7 The steps of the implementation of ball detection	109

Figure 4.8 Gathered data after the implementation	111
Figure 4.9 Created trajectory paths	113
Figure 4.10 Rotation path	115
Figure 4.11 Assigned coordinate for each robot IDs	116
Figure 4.12 Movement path of the robots	117
Figure 4.13 The reaction in attack formation	118
Figure 4.14 The reaction in defense formation	119
Figure 4.15 Testing arena detection using hough transform	121
Figure 4.16 Testing arena detection using polygon approximation	122
Figure 4.17 Image to be tested and the result of robot detection	123
Figure 4.18 tested image and the result of ball detection	125
Figure 4.19 Result of the detection in different resolutions	129
Figure 4.20 Different rooms to be tested	133
Figure 4.21 Result of robot detection in different rooms	139
Figure 4.22 Four different lighting condition	140
Figure 4.23 Result of detection in different lighting condition	143
Figure 4.24 No edge detected in fourth lighting condition	143
Figure 4.25 Camera positioning schematic	144
Figure 4.26 Different arena images from different camera positions	145
Figure 4.27 Result of detection with different camera positions	148

LIST OF TABLES

	pages
Table 3.1 Technical specification of Logitech C525.....	53
Table 4.1 Coordinates of detected squares	99
Table 4.2 List of coordinates with bounded ID	103
Table 4.3 List of heading markers with their IDs	107
Table 4.4 List of global orientations with their IDs	107
Table 4.5 List of robot ids and rotation angle	110
Table 4.6 List of gathered data	110
Table 4.7 Generated trajectory path	114
Table 4.8 Comparison of detected robot coordinates with real coordinates	124
Table 4.9 Comparison of detected robot heading with real heading	124
Table 4.10 Comparison of detected ID with real world ID	124
Table 4.11 Detected ball coordinate with real ball coordinate	126
Table 4.12 Comparison of detected global orientation	127
Table 4.13 Comparison of rotation angle	127
Table 4.14 Comparison of detected ball distance	127
Table 4.15 List of time taken with different resolutions	130
Table 4.16 comparison of robot position in 360p	130
Table 4.17 comparison of robot position in 480p	131
Table 4.18 comparison of robot position in 720p	131
Table 4.19 comparison of global orientations in 360p	131

Table 4.20 comparison of global orientations in 480p	132
Table 4.21 comparison of global orientations in 720p	132
Table 4.22 List of detected robot position in first room	134
Table 4.23 List of detected global orientation in first room	135
Table 4.24 List of detected robot position in second room	135
Table 4.25 List of detected global orientation in second room	136
Table 4.26 List of detected robot position in third room	136
Table 4.27List of detected global orientation in third room	137
Table 4.28 List of detected robot position in fourth room	138
Table 4.29 List of detected global orientation in fourth room	138
Table 4.30 List of robot positions in second lighting condition	141
Table 4.31 List of global orientations in second lighting condition	141
Table 4.32 List of detected robot positions in third lighting condition	142
Table 4.33 List of robot positions from second camera position	146
Table 4.34 List of global orientations from second camera position	146
Table 4.35 List of robot positions from third camera position	147
Table 4.36 List of global orientations from third camera position	147
Table 4.37 List of robot positions form fourth camera position	147
Table 4.38 List of global orientation form fourth camera position	148

LIST OF EQUATIONS

	pages
Equation 2.1 Spatial domain transform	19
Equation 2.2 2-D isotropic Gaussian distribution	19
Equation 2.3 – 2.9 Part of HSV Conversion formula.....	23
Equation 2.10 Grayscale conversion formula.....	24
Equation 2.11 Dilation.....	25
Equation 2.12 Erosion.....	26
Equation 2.13 Complemen of erosion	26
Equation 2.14 Opening.....	26
Equation 2.15 Closing	26
Equation 2.16 Convolution	28
Equation 2.17 Threshold for convolution.....	29
Equation 2.18 Gradient in vector analysis.....	30
Equation 2.19 Magnitude of Gradient.....	30
Equation 2.20 Direction of Gradient vector	30
Equation 2.21 X Derivatives of sobel operator.....	31
Equation 2.22 Y Derivatives of sobel operator	31
Equation 2.23 Alternate representation of a line	34
Equation 2.24 Threshold test	36
Equation 2.25 Value of gray level with threshold conditioning.....	36

Equation 2.26 Forward Mapping.....	40
Equation 2.27 Inverse Mapping.....	40
Equation 2.28 Translate operation.....	41
Equation 2.29 Rotate operation.....	41
Equation 2.30 Scaling operation.....	41
Equation 2.31 Determinant for the x-axis of the interserction.....	42
Equation 2.32 Determinant for the y-axis of the interserction.....	42
Equation 2.33 Equation form of the interserction determinant.....	42
Equation 2.34 two dimentional matrix.....	43
Equation 2.35 General form of perspective transformation.....	43
Equation 2.36 Forward maping of perspective transformation for x axis.....	43
Equation 2.37 Forward maping of perspective transformation for y axis.....	44
Equation 2.38 Forward maping of perspective transformation for x axis.....	44
Equation 2.39 Forward maping of perspective transformation for y axis.....	44
Equation 2.40 Perspective transformation equation system.....	44
Equation 2.41 Angle of view.....	45
Equation 2.42 Aspect Ratio.....	46
Equation 4.1 Error rate calculation for x axis.....	123
Equation 4.2 Error rate calculation for y axis.....	123