

The Mobile Manipulation Challenge, Results

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Introduction

- In May, Fetch Robotics held a robotic manipulation competition at ICRA 2019 in Montreal
- 1st place team won a Fetch mobile manipulator robot

Why another robotics competition?

- Industrial application: kit filling, machine tending, bin picking
- Fetch robot eligible for many competitions, but not a perfect fit
 - ERL: Only open to Europeans, rules don't fit our use cases
 - RoboCup@Work: Designed for Kuka YouBot, environment size not ideal
 - RoboCup@Home: Slow moving, focused on general-purpose service robots
 - ACRV Picking Benchmark: Great benchmark, wanted more industrial applications



Win a Fetch!

Competition Overview

Task:

- Pick parts from station/bin
 - 3D printed parts: <u>https://github.com/fetchrobotics/fetchit</u>
- Simulate machining task
 - /schunk_machine/goal
- Place parts in kit
- Place kit at drop-off location
- Trigger camera to inspect kit
 - /sick_camera/goal

Complete as many kits as possible in 45 min



Competition Overview

Gearbox Pick Station

Kit Station





Schunk Machine & **Gear Pick** Station



Screw Bin Pick Station

Items Not Touching

Competition Overview



Schunk Machine (simulated machining task)





Remote Arena

View from an overhead camera



Remote access arena



- VPN access to robot
 - Needs TCP/UDP on all ports for subscribers/service
- Ceiling-mounted cameras

Competition Overview

Action	Points
Full kit delivered (all 6 items and kit at drop-off station)	7
Closing the SCHUNK machine door with Large Gear inside	+3
Delivering the kit to SICK Inspector, and trigger inspection	+1
Dropped Item	-1
Collision with Environment (minor)	-1
Kit delivered with extra item(s)	-1 (per extra item)
Kit delivered with item in incorrect section of kit	-1 (per misplaced item)
Kit delivered with item(s) missing	0

Full rulebook for this year's competition available at:

opensource.fetchrobotics.com/assets/Rulebook2019.pdf

Competition Results



Prizes: Fetch Mobile Manipulation Research Robot

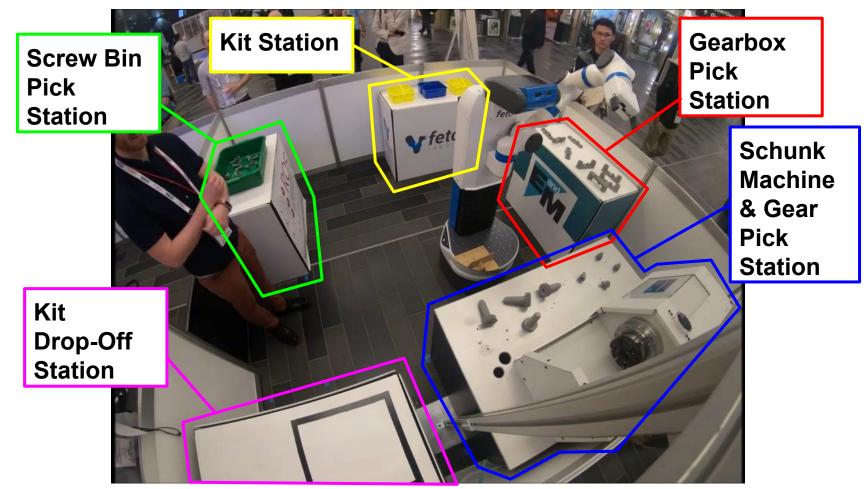
\$7K Schunk Bucks SICK MRS1000 4-layer LiDAR and TiM561 LiDAR



Prizes: \$5K Schunk Bucks SICK MRS1000 4-layer LiDAR and TiM561 LiDAR

Other participants: Columbia, Case Western, Fido

GT Complete Kit Example Video



Manipulation Strategies







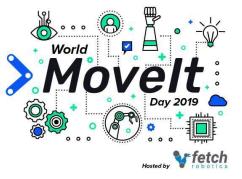
Using the torso lift/lower for faster manipulation

Physically triangulating the chuck

Software Tools

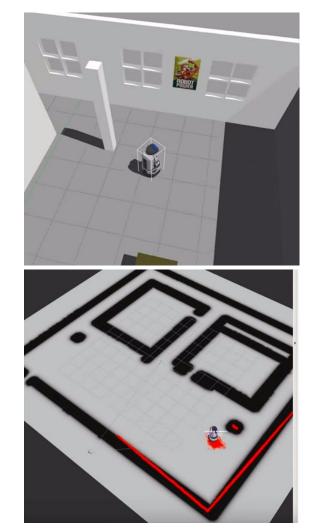
- ROS Melodic:
 - Enforced using Melodic
 - \circ $\,$ $\,$ Forced us to release Melodic for the Fetch
- Gazebo
 - Web-based simulation provided by The Construct
 - Sim code: <u>https://github.com/fetchrobotics/fetch_gazebo</u> -> fetchit_competition
- Movelt
- Supported/Encourage use of Docker
- Teams Open Sourced Code:
 - Georgia Tech: <u>https://github.com/GT-RAIL/derail-fetchit-public</u>
 - UMass Lowell: <u>https://github.com/uml-robotics/fetchit2019</u>





Lessons Learned

- Difficult for teams without robots to participate
- Higher fidelity simulation
 - Fetch Gazebo model needs improvement
 - Gazebo has out-improved our model
- Better remote access
 - Original camera setup had too much latency
 - Final camera setup didn't have enough cameras/viewpoints
 - Better network speeds
- Better internet at venue



FetchIt! 2020

- Potential Locations:
 - IROS 2020: Las Vegas
 - o ICRA 2020: Paris
- Rule Changes
 - Off the shelf items
 - More automation of competition environment, e.g. automatic Schunk Machine door
 - Greater focus on kitting, more realistic kit
 - Real bin-picking
- Improve Experience for Teams Without Robots Already
 - Loaner Robots
 - On-site Hackathons
 - Improvements to the robot in simulation
 - Improvements to remote access

Summary



We gave away a Fetch!

We want to give away another Fetch!

Don't buy a Fetch!

Win a Fetch!

Thanks to FetchIt! Sponsors:





SICK Sensor Intelligence.





Learn and develop for robots with ROS