The CMUnited-99 Champion Simulator Team

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Abstract. The CMUnited-99 simulator team became the 1999 RoboCup simulator league champion by winning all 8 of its games, outscoring opponents by a combined score of 110–0. CMUnited-99 builds upon the successful CMUnited-98 implementation, but also improves upon it in many ways. This paper gives a detailed presentation of CMUnited-99's improvements over CMUnited-98.

1 Introduction

The CMUnited robotic soccer project is an ongoing effort concerned with the creation of collaborative and adversarial intelligent agents operating in real-time, dynamic environments. CMUnited teams have been active and successful participants in the international RoboCup (robot soccer world cup) competitions [1, 2, 15]. In particular, the CMUnited-97 simulator team made it to the semi-finals of the first RoboCup competition in Nagoya, Japan [9], the CMUnited-98 simulator team won the second RoboCup competition in Paris, France [13], and the latest CMUnited-99 simulator team won the third RoboCup competition in Stockholm, Sweden [1].

The CMUnited-99 simulator team is modeled closely after its two predecessors. Like CMUnited-97 and CMUnited-98, it uses layered learning [12] and a flexible team structure [11]. In addition, many of the CMUnited-99 agent skills, such as goaltending, dribbling, kicking, and defending, are closely based upon the CMUnited-98 agent skills. However, CMUnited-99 improves upon CMUnited-98 in many ways. This paper focuses on the research innovations that contribute to CMUnited-99's improvements.

Coupled with the publicly-available CMUnited-99 source code [8], this article is designed to help researchers involved in the RoboCup software challenge [3] build upon our success. Throughout the article, we assume that the reader is familiar with the RoboCup simulator, or "soccer server" [5]. A detailed overview of the soccer server, including agent perception and actuator capabilities, is given in [7].

Section 2 describes the improvements in CMUnited-99's low-level skills, including the introduction of teammate and opponent modeling capabilities. Sec-

[1] The CMUnited small-robot team is also a two-time RoboCup champion [14, 16].

tion 3 presents the improvements in CMUnited-99's ball handling decision. Section 4 focuses on the process by which the low-level skills were improved. Section 5 introduces the concept of layered extrospection, a key advance in our development methodology. Section 6 summarizes CMUnited-99's successful performance at RoboCup-99 and concludes.

2 Agent Skills

CMUnited-99's basic skills are built mostly on CMUnited-98's skills. This section focusses on CMUnited-99's improvements in low-level skills.

2.1 Ball Velocity Estimation

One of the most important part of good ball handling skills is an accurate estimation of the ball's velocity. When a player is facing the ball, an estimate of the ball's velocity is "visible" via the player's sensory perceptions. However, in both CMUnited-98 and CMUnited-99, when an agent is handling the ball, it uses *position based velocity estimation*. That is, if the agent observes the ball on two successive cycles, it knows the actual path which the ball traveled, and therefore its current velocity.

While this is intuitively a fairly simple idea, there are several complications. First, each agent needs to keep track of the kicks it performed in order to accurately estimate the ball velocity. This is for cases where the agent is not receiving sensations every cycle. The server gives information about kicks that it received, and it is important to note when requested kicks are not executed by the server.

The second complication is somewhat of an artifact of our world model. Our agents store the current position of all objects in global coordinates by converting the objects' sensed relative positions to global coordinates based on the agent's estimated current position. When an agent gets new visual information, it re-estimates its current position. Both of the estimates are quite noisy since they are based on usually distant flags. This means that the ball's old position and new position are in essentially different coordinate frames. In Figure 1, objects in the old coordinate frame are represented in dark grey and objects in the new coordinate frame are lighter. As shown, our agents can calculate the disparity between the coordinate frames by taking the difference of the player's predicted position at time t (judged in the coordinate frame from time $t-1$) and the player's observed position at time t. The ball's position at time $t-1$ can then be moved to the new coordinate frame. The ball velocity is then simply the difference between it's position at time t and position at time $t-1$. This gives a good estimate of the ball's velocity because the only error left is the error in the reported ball positions. When the ball is close to the player, this error is quite small.

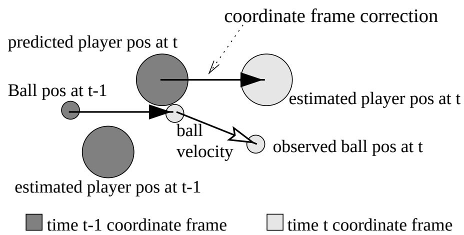


Fig. 1: Correcting for position error in ball velocity estimation.

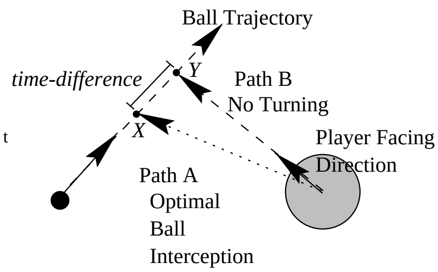


Fig. 2: Deciding whether to turn in ball interception.

2.2 Ball Interception

The basic structure of our ball interception strategy is the same as in CMUnited-98. We successively simulate the ball's positions on future cycles and then determine if the agent can reach a spot that the ball will occupy before the ball does.

An important change to this scheme is an emphasis on dashing instead of turning. In order to execute less turns while in pursuit of the ball, the agents now first calculate how long it would take to intercept the ball with no turning at all. This is just a simple ray-ray intersection as shown in Figure 2, path B. *time-difference* is the distance between the calculated optimal (point X) and the path with no turning (point Y), judged by how long it would take the ball to get from X to Y. If *time-difference* is below a threshold of a few cycles, then the agent will proceed along path B instead of path A. Proceeding along path B will always result in a dash instead of a turn.

2.3 Using Models of Opponents and Teammates

Deciding when to shoot at the goal has a huge impact on the performance of a team. CMUnited-98 made this decision based on several very inaccurate heuristics. CMUnited-99 makes this decision in a more principled way by using a model of an "optimal" goalie. That is, we use a model of a goalie that reacts instantaneously to a kick, moves to exactly the right position to stop the ball, and catches with perfect accuracy.

When deciding whether to shoot, the agent first identifies its best shot target. It generally considers two spots, just inside of the two sides of the goal. The agent then considers the lines from the ball to each of these possible shot targets. *shot-target* is the position whose line is further from the goalie's current position.

The agent then predicts, given a shot at *shot-target*, the ball's position and goalie's reaction using the optimal goalie model. We use the following predicates:

blocking-point The point on the ball's path for which an optimal goalie heads.
ball-to-goalie-cycles The number of cycles for the ball to get to the *blocking-point*
goalie-to-ball-cycles The number of cycles for the goalie to get to the *blocking-point*

shot-margin $=$*ball-to-goalie-cycles*$-$*goalie-to-ball-cycles*

better-shot(k) Whether teammate k has a better shot than the agent with the ball, as judged by *shot-margin*

The value *shot-margin* is a measure of the quality of the shot. The smaller the value of *shot-margin*, the more difficult it will be for the goalie to stop the shot. For example, for a long shot, the ball may reach the *blocking-point* in 20 cycles (*ball-to-goalie-cycles*$=20$), while the goalie can get there in 5 cycles (*goalie-to-ball-cycles*$=5$) This gives a *shot-margin* of 15. This is a much worse shot than if it takes the ball only 12 cycles (*ball-to-goalie-cycles*$=12$) and the goalie 10 cycles to reach the *blocking-point* (*goalie-to-ball-cycles*$=10$). The latter shot has a *shot-margin* of only 2. Further, if *shot-margin*<0, then the "optimal" goalie could not reach the ball in time, and the shot should succeed.

Using a model of opponent behavior gives us a more reliable and adaptive way of making the shooting decision. We can also use it to make better passing decisions. When near the goal, the agent may often be faced with the decision about whether to pass or shoot the ball. The agent with the ball simulates the situation where its teammate is controlling the ball, using the goalie model to determine how good of a shot the teammate has. If the teammate has a much better shot, then the predicate *better-shot*(k) will be true. This will tend to make the agent pass the ball, as described in Section 3.

Note that this analysis of shooting ignores the presence of defenders. Just because the goalie can not stop the shot (as judged by the optimal goalie model) does not mean that a nearby defender can not run in to kick the ball away.

2.4 Breakaway

An important idea in many team ball sports like soccer is the idea of a "breakaway." Intuitively, this is when some number of offensive players get the ball and themselves past the defenders, leaving only perhaps a goalie preventing them from scoring. After looking at logfiles from previous competitions, we saw many opportunities for breakaways which were not taken advantage of.

The first question which has to be answered is "What exactly is a breakaway?" This is built upon several predicates (note that we can naturally reflect these to the other side of the field):

controlling-teammate Which teammate (if any) is currently controlling the ball. "Control" is judged by whether the ball is within the kickable area of a player.

controlling-opponent Which opponent (if any) is currently controlling the ball

opponents-in-breakaway-cone The breakaway cone is shown in Figure 3. The cone has its vertex at the player with the ball and extends to the opponents goal posts.

our-breakaway $=$ (*controlling-teammate*$\neq$ None) $\wedge$ (*controlling-opponent*$=$None) $\wedge$ (*opponents-in-breakaway-cone*≤ 1)

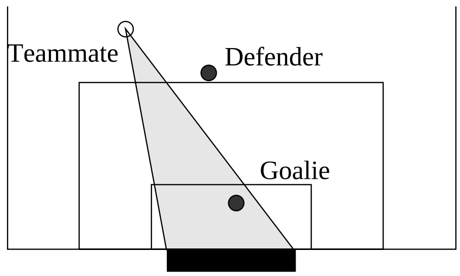


Fig. 3: The Breakaway Cone

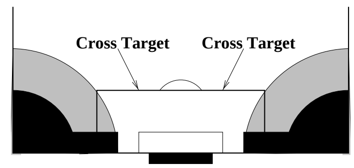


Fig. 4: Important regions for the "cross" behavior

The first new skill we use in breakaways is a generalization of dribbling called "kick and run." When executing the normal dribbling skill, the agent aims to do one kick and then one dash and have the ball end up in its kickable area again. However, this causes a player dribbling the ball to move only half as quickly as a player without the ball since half of its action opportunities are spent kicking rather than moving. Therefore, defenders are able to easily catch up to dribbling players. For kick and run, the agents aim for one kick and n dashes before being in control of the ball again. In effect, they kick the ball harder to allow them to spend more of their time running.

We use the optimal model described in Section 2.3 to help make the decision about when to shoot. During a breakaway, the agent shoots when either one of the following is true:

- *shot-margin* (defined in Section 2.3) gets below a certain threshold (1 cycle in CMUnited-99)
- The time that it would take for the goalie to proceed directly to the ball and steal it gets below a certain threshold (6 cycles in CMUnited-99).

This skill was extremely effective in the competition, with the vast majority of our goals being scored using the specialized breakaway code.

3 Ball Handling Decision

One crucial improvement in CMUnited-99 is the agents' decision-making process when in control of the ball. The decisions made at these times are the most crucial in the robotic soccer domain. Which an agent chooses affects the future options of teammates and opponents.

The agent uses a complex heuristic decision mechanism, incorporating a machine learning module, to choose its action. The most significant changes from CMUnited-98 are that the agents use special-purpose code for breakaways (see Section 2.4); that the pass-evaluation decision tree [10] has been retrained during practice games to capture the agents' improved ball-interception ability (see Section 2.2; that the agents can cross the ball (see below); and that the agents consider whether there is a teammate in a better position than they are to shoot the ball (see Section 2.3).

In presenting the agent decision-making process, we make use of the predicates defined in Section 2 as well as the following:

distance-to-their-goal The distance to the opponent's goal
distance-to-our-goal The distance to own goal
opponents-in-front-of-goal The number of opponents (including the goalie) in the breakaway cone shown in Figure 3
closest-opponent The distance to the closest opponent
closer-to-goal(k) Whether teammate k is closer to the opponent's goal than the agent with the ball
can-shoot Whether *distance-to-their-goal* < 25 and (*opponents-in-front-of-goal* ≤ 1 and *shot-margin* ≤ 6.
can-shoot(k) Same as above but from teammate k's position
congestion $= \sum_{opponents} \frac{1}{(distance-to-opponent)^2})$
congestion(k) Same as above but from teammate k's position
can-dribble-to(x) No defender is nearby or in a cone extending towards the point x

Following is a rough sketch of the decision-making process without all of the parametric details. In all cases, passes are only made to teammates that the decision tree predicts will be able to successfully receive the pass (called *potential receivers* or PR below). If there is more than one potential receiver satisfying the given criteria, then the one predicted with the highest confidence to receive the pass is chosen.

- If $\exists r \in$ PR s.t. *better-shot*(r): pass to r.
- If *our-breakaway*: execute special-purpose breakaway code (see Section 2.4).
- If (*distance-to-their-goal* < 17 and *opponents-in-front-of-goal* ≤ 1) or *shot-margin* ≤ 3: shoot on goal.
- At the other extreme, if *distance-to-our-goal* < 25 or *closest-opponent* < 10: clear the ball (kick it towards a sidelines at midfield and not towards an opponent [13]).
- If $\exists r \in$ PR s.t. *closer-to-goal*(r) and *can-shoot*(r) and *congestion*(r) $\leq$ *congestion*: pass to r.
- If *can-dribble-to*(opponent's goal): dribble towards the goal.
- If $\exists r \in$ PR s.t. *closer-to-goal*(r) and *congestion*(r) $\leq$ *congestion* (even if unable to shoot): pass to r.
- If close to a corner of the field (within a grey or black area in Figure 4) then *cross* the ball as follows.
  - if very near the base line or the corner (in the black area): kick the ball across the field (to "cross target"), even if no teammate is present ("cross it").
  - If able to dribble towards the baseline: dribble towards the baseline (for a later cross).
  - If able to dribble towards the corner: dribble towards the corner.
  - Otherwise, cross it.

Even though the cross doesn't depend on a teammate being present to receive the ball, we observed many goals scored shortly after crosses due to teammates being able to catch up to the ball and shoot on goal.
- If *can-shoot*: shoot.
- *can-dribble-to*(one of the corner flags): dribble towards the corner flag.
- If approaching the line of the last opponent defender (the offsides line): send the ball (clear) past the defender.
- If $\exists r \in$ PR s.t. *closer-to-goal*(r) or *congestion*(r) $\leq$ *congestion*: pass to r.
- no opponent is nearby: hold the ball (i.e. essentially do nothing and wait for one of the above conditions to fire).
- If $\exists r \in$ PR s.t. no opponent is within 10 or r: pass to r.
- Otherwise: Kick the ball away (clear).

Notice that such a ball-handling strategy can potentially lead to players passing the ball backwards, or away from the opponent's goal. Indeed, we observed such passes several times during the course of games. However, the forward passes and shots are further up in the ball-handling decision, and therefore will generally get executed more often.

4 Off-line Training

For the various agent skills described in Section 2 and in [13], there are many parameters affecting the details of the skill execution. For example, in the ball skill of dribbling, there are parameters which affect how quickly the agent dashes, how far ahead it aims the ball, and how opponents affect the location of the ball during dribbling.

The settings for these parameters usually involve a tradeoff, such as speed versus safety, or power versus accuracy. It is important to gain an understanding of what exactly those tradeoffs are before "correct" parameter settings can be made.

We created a trainer client that connects to the server as an omniscient off-line coach client (this is separate from the on-line coach). The trainer is responsible for three things:

1. **Repeatedly setting up a particular training scenario**. In the dribbling skill, for example, the trainer would repeatedly put a single agent and the ball at a particular spot. The agent would then try to dribble the ball to a fixed target point.
2. **Recording the performance of the agent on the task**. Here we use a hand-coded performance metrics, generally with very simple intuitive ideas. In the kicking skill, for example, we record how quickly the ball is moving, how accurate the kicking direction is, and how long it took to kick the ball.
3. **Iterating through different parameter settings**. Using the server's communication mechanism, the trainer can instruct the client on which parameter settings to use. The trainer records the performance of the agent for each set of parameter values.

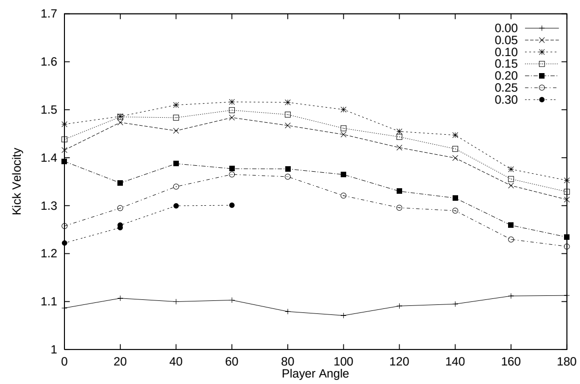


Fig. 5: An example of training data

Once the scenario is set up, the system runs autonomously. Since most skills only involve one or two clients, we could afford to have the trainer iterate over many possible parameter values, taking several hours or days.

Once the trainer has gathered the data, we would depict the results graphically and decide which parameters to use. An example for the hard kicking skill is shown in Figure 5. The two parameters varied for the test shown are the angle the agent is facing relative to the kicking angle (the x-axis), and the buffer around the player out of which the agent tries to keep the ball (the different lines).

Sometimes, the "optimal" parameter selection was fairly clear. For example, in Figure 5, we are trying to maximize the kick velocity. Therefore, we would select a player angle of approximately 60 degrees and a buffer of 0.10. Other times, the data looked much noisier. In those cases we could narrow our search down somewhat and get more data over the relevant parts of the parameter space.

We were sometimes limited by processing power in the breadth or resolution of the parameter space that we could examine. A more adaptive searching strategy, such as might be given by various learning techniques like genetic programming [4], would be a useful addition.

5 Layered Disclosure

A perennial challenge in creating and using complex autonomous agents is following their choice of actions as the world changes dynamically, and understanding why they act as they do. In complex scenarios, even the human computer-agent developer is often unable to identify what exactly caused an agent to act as it did in a given situation. Adding support for human developers and observes to better follow and understand the actions of autonomous agents can be a significant enhancement to processes of development and use of agents.

To this end, we introduce the concept of *layered disclosure* by which autonomous agents include in their architecture the foundations necessary to allow a person to probe into the specific reasons for an agent's action. This probing may be done at any level of detail, and either retroactively or while the agent is acting.

A key component of layered disclosure is that the relevant agent information is organized in *layers*. In general, there is far too much information available to display all of it at all times. The imposed hierarchy allows the user to select at which level of detail he or she would like to probe into the agent in question.

When an agent does something unexpected or undesirable, it is particularly useful to be able to isolate precisely *why* it took such an action. Using layered disclosure, a developer can probe inside the agent at any level of detail to determine precisely what needs to be altered in order to attain the desired agent behavior.

Layered disclosure was a significant part of the development of CMUnited-99, and led to many of the improvements in the team over CMUnited-98. Our development of layered disclosure was inspired in part by our own inability to trace the reasons behind the actions of CMUnited-98. For example, whenever a player kicks the ball towards its own goal, we would wonder whether the agent was mistaken about its own location in the world, whether it was mistaken about the ball's or other agents' locations, or if it "meant" to kick the ball where it did, and why. Due to the dynamic, uncertain nature of the environment, it is usually impossible to recreate the situation exactly in order to retroactively figure out what happened.

Our layered disclosure implementation is publicly available[8]. It can easily be adapted for use with other RoboCup simulator teams.

During the course of a game, our agents store detailed records of selected information in their perceived world states, their determination of their short-term goals, and their selections of which actions will achieve these goals, along with any relevant intermediate decisions that lead to their action selections.

After the game is over, the logfile can be replayed using the standard "log-player" program which comes with the soccer server. Our disclosure module, implemented as an extension to this logplayer, makes it possible to inspect the details of an individual player's decision-making process at any point.

In the remainder of this section we provide two examples illustrating the usefulness of layered disclosure.

5.1 Discovering Agent Beliefs

When observing an agent team performing, it is tempting, especially for a person familiar with the agents' architectures, to infer high level beliefs and intentions from the observed actions. Sometimes, this can be helpful to describe the events in the world, but misinterpretation is a significant danger.

Consider the example in Figure 7. Here, two defenders seem to pass the ball back and forth while quite close to their own goal. In general, this sort of passing back and forth in a short time span is undesirable, and it is exceptionally dangerous near the agents' own goal. Using the layered disclosure tool, we get the information displayed in Figure 6.

```
Action log for CMUnited99 2, level 30, at time 831
-Mode: AM_With_Ball
--Handling the ball
----OurBreakaway() == 0
---handle_ball: need to clear
---clear_ball:  target ang == -93.0
-----starting kick to angle -93.0,
     translated to point (-6.4, -34.0)
```

```
Action log for CMUnited99 2, level 20, at time 845
-Mode: AM_With_Ball
--Handling the ball
---handle_ball: need to clear
---clear_ball:  target ang == 24.0
----starting kick to angle 24.0,
    translated to point (-16.5, -34.0)
----kick_ball: starting kick to angle 24.0
```

```
Action log for CMUnited99 5, level 50, at time 838
-------Invalidating ball vel:0.36 > 0.36
        thought vel was (1.73, -0.70)
-------Position based velocity estimating:
        gpos (-32.1 -23.4), prev_seen_pos (-33.5 -23.1)
---------Sight 838.0:
            B_ team:___________opp:________9__
-Mode: AM_With_Ball
--Handling the ball
----OurBreakaway() == 0
-----CanDribbleTo (-22.05, -20.52):
              TRUE No players in cone
---handle_ball: dribbling to goal (2)
```

```
Action log for CMUnited99 5, level 20, at time 850
-Mode: AM_With_Ball
--Handling the ball
---handle_ball: dribbling to goal (2)
```

Fig. 6: Layered disclosure for the passing example (the boxes have been added for emphasis).

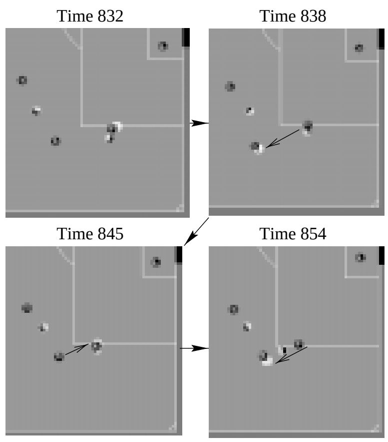
First, we see that in both cases that player number 2 was in control of the ball (time 831 and 845), it was trying to clear it (just kick it away from the goal), not pass to player number 5. Given the proximity of the goal and opponents, clearing is a reasonable behavior here. If a teammate happens to intercept a clear, then our team is still in control of the ball. Therefore, we conclude that this agent's behavior matches what we want and expect.

Next, we can see that player number 5 was trying to dribble towards the opponent's goal in both cases that he controlled the ball (time 838 and 850). There are no opponents immediately around him, and the path on the way to the goal is clear. This agent's intention is certainly reasonable.

However, at time 838, player number 5 does not perform as it intended. Rather than dribbling forward with the ball, it kicked the ball backwards. This points to some problem with the dribbling behavior. As we go down in the layers, we see that the agent invalidated the ball's velocity. This means that it thought the ball's observed position was so far off of its predicted position that the agent's estimate for the ball's velocity could not possibly be right. The agent then computed a new estimate for the ball's velocity based on its past and current positions (see Section 2.1).

Given this estimation of the ball's velocity (which is crucial for accurate ball handling), we are led to look further into how this velocity is estimated. Also, we can compare the estimate of the velocity to the recorded world state. In the end, we find that the ball collided with the player. Therefore, it was invalid to estimate the ball's velocity based on position. In fact, this led us to more careful application of this velocity estimation technique.

In this case, inferring the intentions of the players was extremely challenging given their behaviors. Without layered disclosure, the natural place to look to correct this undesirable behavior would have been in the passing decisions of the players. It would have been difficult or impossible to determine that the problem was with the estimation of the ball's velocity.



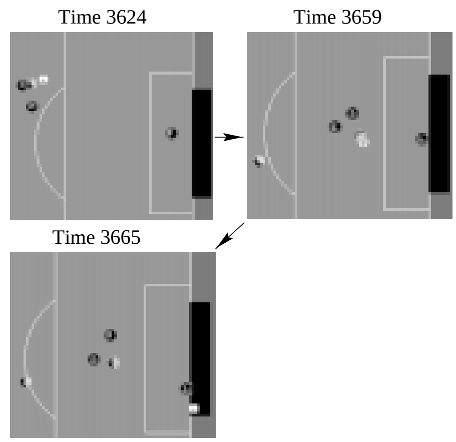


Fig. 7: Undesired passing behavior

Fig. 8: Poorly performing defenders

5.2 The Use of Layers

The fact that the agents' recordings are layered is quite important. One important effect is that the layers allow the observer to look at just higher levels, then explore each case more deeply as required.

Consider the example depicted in Figure 8. Here, two defenders are unable to catch up and stop one offensive player with the ball, even though the defenders were in a good position to begin with.

Since this is a scenario that unfolds over many time steps, we need to be able to understand what happens over that time sequence. The first pass at this is to just look at the highest level decision. The first decision our agents make is in which "action mode" they are [13]. This decision is based on which team is controlling the ball, current location, role in the team structure, etc. Usually the fastest player to the ball is in one mode and the second fastest in another.

By using the layered disclosure tool to look at just the highest level of output, two facts can be learned: the defenders switch modes (between fastest and second fastest) frequently, and are often unsure about which team is controlling the ball. The different modes tell the agent to go to different spots on the field. By switching back and forth, the agents will waste a great deal of time turning to face the direction they want to go instead of actually going. Therefore, the agents do not catch up.

Further, The decision about what mode to go into is sometimes affected by which team the agent believes is controlling the ball. Realizing that this value is often unknown should lead to changes in the way that value is determined, or changes in the manner in which it is used.

In this case, making use of layered disclosure to examine just the high-level reasoning decisions of a pair of agents allows us to focus on a problem that would have otherwise been easily overlooked.

Opponent	Affiliation	Score (CMU–Opp.)
Kasuga-Bitos III	Chubu University, Japan	19 – 0
Karlsruhe Brainstormers	University of Karlsruhe, Germany	1 – 0
Cyberoos	CSIRO, Australia	1 – 0
Essex Wizards	University of Essex, UK	0 – 0
Mainz Rolling Brains	University of Mainz, Germany	0 – 2
Gemini	Tokyo Institute of Technology, Japan	8 – 0
11 Monkeys	Keio University, Japan	0 – 1
TOTAL		29 – 3

Table 1: The scores of CMUnited-98's games in the simulator league of RoboCup-99. CMUnited-98 won 3, lost 2, and tied 1 game.

Note 1. The last game was lost by one goal in overtime.

We envision that layered disclosure will continue to be useful in the RoboCup simulator and in other agent development projects, particularly those with complex agents acting in complex, dynamic environments.

6 Results and Conclusion

The third international RoboCup championship, RoboCup-99, was held on July 28–August 4, 1999 in Stockholm, Sweden in conjunction with the IJCAI-99 conference [15]. As the defending champion team, the CMUnited-98 simulator team was entered in the competition. Its code was left unaltered from that used at RoboCup-98 except for minor changes necessary to update to version 5 of the soccer server. Server parameter changes that reduced player size, speed, and kickable area required adjustments in the CMUnited-98 code. However CMUnited-98 did not take advantage of additions to the players' capabilities such as the ability to look in a direction other than straight ahead (simulation of a neck).

The CMUnited-98 team became publicly available soon after RoboCup-98 so that other people could build upon our research. Thus, we expected there to be several teams at RoboCup-99 that could beat CMUnited-98, and indeed there were. Nonetheless, CMUnited-98 performed respectably, winning 3 games, losing 2, and tying 1 and outscoring its opponents by a combined score of 29–3. Table 1 presents the details of CMUnited-98's matches.

Meanwhile, the CMUnited-99 team was even more successful at the RoboCup-99 competition than was its predecessor at RoboCup-98. It won all 8 of its games by a combined score of 110–0, finishing 1st in a field of 37 teams. Table 2 shows CMUnited-99's game results.

Qualitatively, there were other significant differences between CMUnited-98's and CMUnited-99's performances. In RoboCup-98, several of CMUnited-98's matches were quite close, with many offensive and defensive sequences for both teams. CMUnited-98's goalie performed quite well, stopping many shots. In RoboCup-99, CMUnited-99's goalie only had to touch the ball three times over all 8 games. Only two teams (Zeng99 and Mainz Rolling Brains) were able to

Opponent	Affiliation	Score (CMU–Opp.)
Ulm Sparrows	University of Ulm, Germany	29 – 0
Zeng99	Fukui University, Japan	11 – 0
Headless Chickens III	Linköping University, Sweden	17 – 0
Oulu99	University of Oulu, Finland	25 – 0
11 Monkeys	Keio University, Japan	8 – 0
Mainz Rolling Brains	University of Mainz, Germany	9 – 0
Magma Freiburg	Freiburg University, Germany	7 – 0
Magma Freiburg	Freiburg University, Germany	4 – 0
TOTAL		110 – 0

Table 2: The scores of CMUnited-99's games in the simulator league of RoboCup-99. CMUnited-99 won all 8 games, finishing in 1st place out of 37 teams.

create enough of an offense in order to get shots on our goal. Improvements in ball velocity estimation (Section 2.1), ball interception (Section 2.2), and a myriad of small improvements made possible by layered extrospection (Section 5) greatly improved CMUnited-99's midfield play over CMUnited-98.

Another qualitative accomplishment of CMUnited-99 was how closely its actions matched our ideas of what should be done. When watching games progress, we would often just be starting to say "Pass the ball!" or "Shoot it" when the agents would do exactly that. While this is certainly not a solid criterion on which to judge a team in general, it is a testament to our development techniques that we were able to refine behaviors in such a complex domain to match our high level expectations.

There are certainly many improvements to be made. For example, in CMUnited-99's game against Zeng99, our breakaway behavior (Section 2.4) was much less effective in general. This was because the Zeng99 team put an extra defender behind the goalie. CMUnited-99's agents assumed the defender closest to the goal was the goalie. Therefore, the agents applied the goalie model to that defender instead of to the real goalie. This allowed the real goalie to stop many shots which our agents did not anticipate could be stopped. Creating models of other opponents and using them more intelligently could improve this behavior.

Further, adapting models to opponents during play, as well as changing team strategy is a promising future direction. We have done some experimentation with approaches to quick adaptation in complex domains like robotic soccer[6]. Other researchers associated with RoboCup are also looking in this direction, especially with the newly introduced coach agent.

Various software from the team is available [8]. The binaries for the player and coach agents are available. Full source code for the coach agent, the trainer agent, and the layered extrospection tool are also available. Further, skeleton source code for the player agents, including the low level skills, is also available.

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