The RoboCup 2013 Drop-In Player Challenges: Experiments in Ad Hoc Teamwork

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September 15, 2014

















- Pre-coordination may not be possible
- Agents should be robust to various teammates
- Agents need to adapt quickly!

Ad Hoc Teamwork

- Not in control of all agents on team
- Unknown teammates
- Shared goals
- No pre-coordination

Example in humans: Pick up soccer



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Research Question:

How can an agent cooperate with unknown teammates?

RoboCup Drop-In Player Challenges

- RoboCup is an international robotics competition where autonomous robots play soccer
- Games between teams consisting of different randomly chosen players from participants in the competition
- No pre-coordination between teammates, teammates/opponents unknown before start of a game
- Teams provided standard communication protocol for use during games
- Testbed for ad hoc teamwork
- Challenge held across three leagues at the 2013 RoboCup competition
 - Standard Platform League (SPL)
 - 2D Simulation League
 - 3D Simulation League



Standard Platform League (SPL)

- Use Nao robots
- Teams of 5 vs 5 autonomous robots play soccer
- Robots can communicate over wifi



2D Simulation League

- Teams of 7 vs 7 autonomous agents play soccer
- Agents use primitives of "dash", "kick", and "turn" to interact with environment
- Agents receives noisy visual information about environment
- Agents can communicate over limited bandwidth channel



3D Simulation League

- Teams of 10 vs 10 autonomous agents play soccer
- Agents modeled after Aldebaran Nao robot
- Realistic physics using Open Dynamics Engine (ODE)
- Agents receives noisy visual information about environment
- Agents can communicate over limited bandwidth channel



Topics Covered in Paper

How to create a testbed for ad hoc teamwork

How to select/assign agents to different teams

 How to measure/evaluate/score performance of individual agents in an ad hoc teamwork setting

Strategies for ad hoc teamwork

More Information

More information and vidoes at: http://tinyurl.com/iros14dropin Email: patmac@cs.utexas.edu



This work has taken place in the Learning Agents Research Group (LARG) at UT Austin. LARG research is supported in part by grants from the National Science Foundation (CNS-1330072, CNS- 1305287) and ONR (21C184-01).