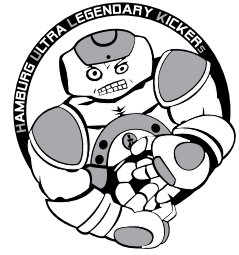


RoboCup 2014

Open Challenge Contribution



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Fallmanager

When watching SPL RoboCup games, one can easily recognize that a fallen robot needs a lot of time for standing up and getting itself ready for playing again. Especially when fighting for the ball, it is of high interest not to fall.

We observed that most of the other teams can recognize when the robot is falling and removing the stiffness from the joints to prevent the robot from being damaged, but most of the teams does not try to prevent the robot from falling.

For that reason, we would like to demonstrate our '*Fallmanager*', which is able to prevent falls in many situations.

The Fallmanager will be demonstrated in the following way:

1. A robot **without** an active Fallmanager will walk against an obstacle placed on the field which will bring the robot to fall.
2. A robot **with** an active Fallmanager will walk against an obstacle placed on the field and the Fallmanager will prevent the robot from falling.

In both scenarios, the time it takes the robots to get back to a standing pose will be measured and compared.

We believe that our development can be of interest for other teams participating in the SPL and therefore would like to demonstrate our achievements.