

WRSC 2013 rules

(Preliminary version in English)

(Version française : http://www.ensta-bretagne.fr/lebars/wrsc2013/Rules_2012-12-17_FR.pdf)

Categories of robots

- Autonomous small sailboats up to 1 m long, 2 m high, 100 kg, referred to **Microsailboats category (MS code)**.
- Autonomous sailboats up to 4 m long, 10 m high, 500 kg, referred to **Sailboats category (S code)**.
- Any type of autonomous boat up to 4 m long, 10 m high, 500 kg, referred to **Motorboats category (M code)**.

Organizers might refuse any dangerous or inappropriate robot... Ask the organizers before if necessary. All the robots should have all the necessary things to ease the process of getting them into the water, start, stop, recovery and work safely. Robots that can go at more than a speed of 5 kn should have the ability to be remotely controlled (for safety reasons). However, it is strongly recommended that all robots can be remote controlled.

Ranked robots

There will be **distinct rankings for each category**. Each robot will need a unique name and get at least 1 point during the tasks to be ranked. A ranked robot might be weighed or measured several times (and maximum values will be used) if it has significant changes during the competition (important parts changed, use of a backup robot...). A journal paper (around 10 pages) and a video (to describe the robot, its building process, its algorithms, its philosophy...) should be provided 15 days before the competition. Moreover, a short presentation should be done during the competition. All these documents will be published on the WRSC website and YouTube after the competition. Their quality will be evaluated (100 points max).

A GPS tracker should be provided by organizers for each robot during the competition. It should store the robot positions in a log file each second. Time will be in UTC. However, it is strongly recommended that competitors store the same type of data as well as a maximum of information on their state themselves in case of a problem (for example an Excel-compatible log file t;x;y;theta;...;actions;detections;...).

Teams

There will be 2 types of teams:

- **Students teams:** at least 50% of students (including PhD students as students), one of the student being the Team Leader, max of 10 people and have at least 1 robot. Their robots will be ranked in the **student ranking** if they comply with the ranked robot rules.

- **Open teams:** the only requirements are a max of 10 people and have at least 1 robot. Their robots will be ranked in the open ranking if they comply with the ranked robot rules.

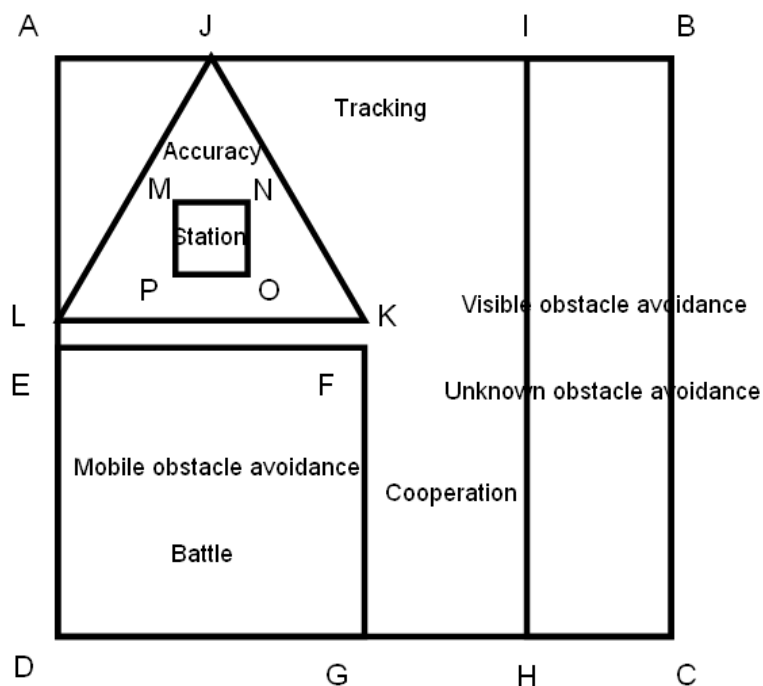
There will be **priority rules** for the attribution of time and space slots, chase boats, GPS trackers, judges... necessary to validate points for a task:

- Ranked robots from student teams (highest priority).
- Ranked robots from open teams.
- Other robots from students teams.
- Other robots from open teams.

A zodiac (or other type of small motorboat) should be provided to each team when possible. During the competition, at least 1 judge will be onboard and might take control of the zodiac at any time. 2-3 tables around 10 chairs should be given to each team, as well as Internet and electricity (bring your own international adapters if needed). Teams can have several robots. There should not be registration fees for all students (including PhD students), teams and robots, only registration fees of around 50€ for non-student conference participants. Organizers will limit the number of teams, people and robots if necessary.

Competition tasks

Unless differently specified (endurance task...) or particular conditions (avoiding a collision with other robots...), no point for a task will be given if a manual or remote human intervention is done on a robot during a task where the robot should be autonomous. Moreover, only 1 attempt will be possible for tasks with all the competitors in the same time (due to organisation issues). Otherwise, the points earned for the best attempt should be used.



Station keeping task

Go autonomously inside the MNOP square (side of 50 m), stay in the middle during 5 min and leave it. The competitors will be allowed to choose the starting point, which will be outside the square. The robot will be considered as regulated in the middle of the square 5 min after the beginning of the attempt. The robot will be required to be outside the square max 15 min after the beginning of the attempt. No point will be given if the robot never comes inside the square or is not outside at the end of the attempt. The GPS tracker log file will be used to compute automatically the time spent inside the square as well as the maximum and average distance to the center between the 5th and 10th minute after the beginning of the attempt, and check validation conditions. The points will be given using the following formula: $\max(30,6*\text{nb_min_inside_square})+\max(20,500/\text{max_dist})+\max(50,250/\text{avg_dist})$. Buoys will be installed to indicate visually the square position, but they will not be used to compute the points.

Max time of an attempt: 15 min

Max points: 100

MS+S+M

Accuracy task

Follow autonomously an JKL triangle (side of 50 m for category MS, 200 m for others). The competitors will be allowed to choose the starting point, but the triangle will have to be followed in the JKLJ order. The triangle will be considered as begun when the robot will have reached the perpendicular to JK in J and finished when the perpendicular to LJ in J will be reached. No point will be given if the first perpendicular is never reached or the last perpendicular is not reached max 50 min (25 min for category MS) after the first perpendicular. The GPS tracker log file will be used to compute automatically the maximum and average distance to the triangle, and check validation conditions. The points will be given using the following formula: $\max(50,50/\text{ecartmax})+\max(50,50/\text{ecartmoy})$. Buoys will be installed to indicate visually the square position, but they will not be used to compute the points.

Max time of an attempt: 50 min (25 min for category MS)

Max points: 100

MS+S+M

Downwind speed task

Cover autonomously as fast as possible a distance of 400 m (100 m for category MS). All the robots will start in the same time from an AB line and will have to reach a CD line (lines of 400 m (100 m for category MS) width, making an ABCD square with a side of 400 m (100 m for category MS)). No point will be given if the CD line is not reached max 30 min after the beginning. The GPS tracker log file will be used to compute automatically the max and average speed, and check validation conditions. The points will be given using the following formula: $\max(50,v_{\text{max}})+\max(50,v_{\text{moy}})$, v in m/s. These points will be adapted to take into account the size differences between robots using the formula: multiplication by $\sqrt{\text{overall hull length}}$ (for microsailboats and sailboats). Buoys will be installed to indicate visually the lines positions, but they will not be used to compute the points.

Max time: 30 min

Max points:100

MS+S+M

Upwind speed task

Same as above except the placement with respect to the wind.
MS+S

Sidewind speed task

Same as above except the placement with respect to the wind.
MS+S

Swarm behaviour task (sponsored by CGGVeritas ?)

TBD

Mobile obstacle of known position avoidance task

Navigate autonomously in a square DEFG with a side of 200 m and leave it when a perturbing boat enters in the square. The competitors will be allowed to choose the starting point, which will be inside the square. The perturbing boat will keep a constant speed and heading during its crossing of the square, which will be in the 45 min after the beginning of the attempt. The perturbing boat (probably a zodiac) will be made visible on radar and will send by Wifi, XBee its position, heading, speed (the competitors will be allowed to use their own emitting box). No point will be given if the robot comes at less than 5 m of the perturbing boat, if the robot leaves the square before the perturbing boats enters it or if the robot has not left the square 15 min after the entrance of the perturbing boat in the square. The GPS tracker log files from the perturbing boat and the robot will be used to check automatically these conditions. Buoys will be installed to indicate visually the square position, but they will not be used to compute the points.

Max time of an attempt: 60 min

Max points: 100

MS+S+M

Immobile and visually particular obstacle avoidance in straight line and favourable wind

Go and come back (possibly several times) autonomously on 400 m (100 m for MS category) from a starting line HC to an arrival line IB (lines of 50 m (20 m for MS category) width, forming a HIBC rectangle of 400 m * 50 m (100 m * 20 m for MS category)) avoiding a big immobile obstacle (probably 5 zodiacs stopped and chained, of distinct colour (probably orange, red or yellow) from other boats (but the 5 will have the same colour), visible on radar but not emitting any particular message). The big obstacle will be placed after the departure of the robot and in its trajectory, at least at 50 m (20 m for MS category) in front of the robot and 50 m (20 m for MS category) before the arrival line. No point will be given if the robot comes at less than 5 m of the big obstacle, if the arrival line IB is not reached at least 1 time 45 min after the departure or if the robot leaves the HIBC rectangle before the big obstacle entered it. The GPS tracker log files from the big obstacle and the robot will be used to check automatically these conditions. Buoys will be installed to indicate visually the position of the lines, but they will not be used to compute the points.

Max time of an attempt : 45 min

Max points : 100

MS+S+M

Unknown and immobile obstacle avoidance in straight line and favourable wind

Same as above but with an obstacle without distinct color.

Max time of an attempt: 45 min

Max points: 200

M

Tracking task

Follow autonomously a zodiac equipped with a buoy of a diameter of 50 cm and of a particular colour (probably orange, red or yellow) on a distance of 100 m and by staying at less than 10 m from it. The zodiac will have a speed close to 0.25 m/s and will follow an unknown and not straight trajectory. The starting point will be at 5 m from the buoy. Points = consecutive number of m covered by the zodiac with the robot at less than 10 m. The GPS tracker log files from the zodiac buoy and the robot will be used to check automatically these conditions.

Max time of an attempt: 10 min

Max points: 100

M

Tow and cooperation task

A 1st robot tows a 2nd robot on at least 100 m and then frees the 2nd robot and stop. The 2nd robot starts and then covers additionally at least 100 m, with all that steps in less than 45 min. 30 points if the 1st robot managed to tow the 2nd robot on 100 m, 30 points if the robots managed to separate without subsequent collision, 40 points if the 2nd robot covered the additional 100 m. Points will be multiplied by 2 if one of the robot is a sailboat. Points will be multiplied by 3 if one of the robot is a microsailboat. The 2nd robot will be considered as correctly towed if it stays at less than 10 m of the 1st robot. They will be considered as separated as soon as this distance is reached. Les logs des GPS trackers des 2 robots seront utilisés pour vérifier de manière automatique ces conditions. Comme cette épreuve met en jeu 2 robots, tous les points gagnés seront donnés à chaque robot.

Max time of an attempt: 45 min

Max points: 300

MS+S+M

Chase/naval battle task (sponsored by MBDA ?)

TBD

Endurance and measurements task (sponsored by Ifremer ?)

Cover autonomously an area (making measurements) of a side of 500 m or make another type of trajectory during at least 8 h, (2 h for M category). All the robots will be launched in the same time. Possible measurements : various water parameters (temperature, salinity, oxygen, chlorophyl, depth, quality, waves...), air parameters (speed, wind angle, temperature...), sounds, pictures, videos, sonar, radar, lidar..., estimation of energy consumption, forces and torques on actuators... The competitors should announce in advance the trajectory and measurements planned to be able to get points. 300 points will be given by judges. Points will be given according to the following criterias : covering quality of the area, measurements quality, number and nature of potential physical or remote manual interventions during the task...

Max time of an attempt: 10 h

Max points: 300
MS+S+M

Travelling salesman special task (sponsored by ENSTA Bretagne and Ifremer)

http://en.wikipedia.org/wiki/Travelling_salesman_problem

TBT

Planning

- 2013-09-02 : Conferences and installation of teams, robots setup, visit of ENSTA Bretagne in the evening+welcome buffet/dinner/barbecue.
- 2013-09-03 : Continuation of conferences, beginning of tasks at Moulin-Blanc.
14h00 – 15h30 : Downwind speed task
- 2013-09-04 : Tasks at Moulin-Blanc.
17h00 – 18h00 : Upwind speed task
- 2013-09-05 : Tasks at Moulin-Blanc.
16h00 – 17h00 : Sidewind speed task
17h00 – 18h00 : Swarm behaviour task
- 2013-09-06 : Endurance task and presentations, demos of invited robots (VAIMOS autonomous sailboat from Ifremer, ASV MOBESENS of Ifremer, ASV GESMA, ASV OCARINA LATMOS...) and awards ceremony followed by buffet (Oceanopolis ?).

Awards

There will be awards based on points gathered by each robot for the **3 categories** (Microsailboats category, Sailboats category and Motorboats category), **each divided in a student ranking and an open ranking:**

- Student Microsailboat
- Student Sailboat
- Student Motorboat
- Open Microsailboat
- Open Sailboat
- Open Motorboat

Special awards will be given also (e.g. Best MicroMagic, Best SailBot, Best Gas Motorboat, Best Electric Motorboat, Most Innovative, Best First Year Team...).