# Software Survey 2026

**Team name**

KURA

**Which division(s) are you applying for? If your used software differs between divisions, please fill out the survey once per division.**

Large Size (height < 190 cm, weight < 80 kg)

**Is your software fully or partially OpenSource? If so, where can it be found?**

yes we use the github demo provided by booster robotics

**Are you using any software developed by other teams? If so, list every component that you are reusing and the team that originally developed it.**

no

**Are you using any datasets in your research? If you are using your own datasets, are they public?**

no

**Please list the scientific publications your team has made since the last application to RoboCup (or if not applicable in the last 2 years).**

no

**Are there any other contributions you would like to share with the RoboCup community?**

yes we want to introduce midgame passing

**Which approach are you using to generate the robot walking motion?**

we use the github demo provided by booster robotics

**Which approach are you using to generate other motions of the robot (e.g. kicking, standing up)?**

yes we use the github demo provided by booster robotics

**Do you have a kinematic or dynamic model of your robot? If so, how did you create it (e.g. measure physical robot, export from CAD model)?**

no

**What approaches are you using in your robot's visual perception?**

yes we use the github demo provided by booster robotics

**Are you planning with objects in Cartesian or image space? If you are using Cartesian space, how do you transform between the image space and cartesian space?**

no

**Do you have some form of active vision (i.e. moving the robots camera based on information known about the world)?**

yes

**What approach are you using to localize your robot?**

yes we use the github demo provided by booster robotics

**Is your team performing team communication? Which communication protocol are you using?**

yes we use UDP

**What approach are you using for navigation? Are you avoiding obstacles?**

we use potential field path planning

**How is the behavior of your robots structured? (e.g. Behaviour Trees)**

we have a main behavior tree and multiple subtrees

**Are you simulating your robot? If so, which simulator are you using and for what purpose do you use simulations?**

no

**What operating system is running on your robot and which middleware are you using (for example Ubuntu 22.04 and ROS2 Galactic)?**

UBUNTU 22.04

**Is there anything else you would like to share that did not fit any previous question?**

no