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Professor Newman

Mobile Robotics

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Beta Group Lab 3 Report

The physical robot had some limitations in comparison to the STDR. The maze we solved in simulation represented a significantly larger space than what we had to work with for the physical robot. So, the physical robot was only able to execute a few of the poses from the path_client program before it ran out of space. In terms of code, we only had to change two variables, the speed and the yaw, which we decrease to improve the accuracy of the physical robot. Instead of changing the topic publisher in the code, we use the command line trick Professor Newman showed us in class to make the path_service program publish to the physical robot.

Youtube Link: <https://youtu.be/o1xE1sWpt-4>

Github Link: <https://github.com/RossKasal/EECS476>