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rnk14
Ps3

In this submission you will find a pdf of the write up as well as a zip folder with a copy of the write up, my altered code, and my video.

For this assignment we were tasked with editing the path_client.cpp and path_service2.cpp files. For the path_service2, I added code to get the yaw and distance as well as a few other lines that were related to this function. For the path_client, I created additional poses (for a total of 10 poses) to execute to reach the final goal to drive the robot to the upper-left corner of the maze. In the video you will see my final result.

One interesting thing that I found while testing this program was that the run-times were not consistent. One execution of the robot would lead to the top left corner and another execution (with the exact same code) would produce a different result. After testing and small changes I was able to successfully create a pose sequence to reach the top left corner. Below are links to youtube for another copy of my video and a link to my github repository.

Youtube link:

<https://youtu.be/pMzwISbMuIo>

Github link:

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