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Mobile Robotics

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Lab 4 Report

Unfortunately, this lab was certainly more frustrating than the others, but not due to the task of the lab. We were plagued by non functioning turtlebots, ROS not recognizing our packages, getting Callback functions for the lidar alarm to work, and other frustrations. After trudging through all of these complications we had the turtle bot execute a path command and pay attention to the lidar alarm. If the lidar alarm became true, the robot was commanded by the path action client to halt immediately and then wait for the obstacle to pass. The path action client would wait until lidar alarm became false before having the robot once again. Once the obstacle passed, the robot would continue on with its original path command.

Youtube: https://www.youtube.com/watch?v=JUk7CgN_QOk&feature=youtu.be

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