Using the Observer/Imitation Model

Initial
1) Move the sourcecode for the Observer/Imitation model into the eCD++ model directory.
2) These models can either be placed in their own subdirectory (Imitate) or in the directory of the model they will imitate.
3) If they are in their own directory, the Makefile and Makefile.common in the eCD++ directory will need to be changed to add that directory to the build path.
4) If they are in another model's directory, the model's Makefile will need to be modified so that it compiles the Observer and Imitator models.

Coupling Models
1. The imitation model should be coupled exactly as the original model was (see imitator_robot.ma as an example for imitating RoboCart robot).
2. The observer model should be coupled so that it is between the model being observed and the hardware (see observer_robot.ma as an example for coupling with RoboCart robot)

Various Scripts
1. robotEvents.py: Generates an event file of 500 random events for the RoboCart obstacle avoidance model
2. armEvents.py: Same as above, but for the robotic arm model
3. robotParse.py: Parses the observation files created by the Observer model and creates a case base file

Sample Data Files
1. observer_robot.txt: Sample observations from the obstacle avoidance robot
2. observer_arm.txt: Sample observations from the robotic arm
3. cases_robot.txt: Sample case base for imitating the obstacle avoidance robot
4. cases_arm.txt: Sample case base for imitating the robotic arm