← Project review - ROS. Day03

Type of project	Individual
Duration	30 min
Passed Peer Reviews	1/2

Git project

ssh://git@repos-ssh.21-school.ru:2289/students/ROS._Day03.ID_568830/utygett_python_d...

Copy link Open

Student

utygett-python-ds level 0

About

Introduction

The methodology of School 21 makes sense only if peer-to-peer reviews are done seriously.
Please read all guidelines carefully before starting the review.
- Please, stay courteous, polite, respectful and constructive in all communications during t
his review.
- Highlight possible malfunctions of the work done by the person and take the time to disc
uss and debate it.

- Keep in mind that sometimes there can be differences in interpretation of the tasks and t he scope of features. Please, stay open-minded to the vision of the other.
- If you have not finished the project yet, it is compulsory to read the entire instruction bef ore starting the review.

Guidelines

- Evaluate only the files that are in src folder on the GIT repository of the student or group.
- Ensure to start reviewing a group project only when the team is present in full.
- Use special flags in the checklist to report, for example, an “empty work” if repository do es not contain the work of the student (or group) in the src folder of the develop branch, or “cheat” in case of cheating or if the student (or group) are unable to explain their work at a ny time during review as well as if one of the points below is not met. However, except for cheating cases, you are encouraged to continue reviewing the project to identify the probl ems that caused the situation in order to avoid them at the next review.
- Doublecheck that the GIT repository is the one corresponding to the student or the grou p.
- Meticulously check that nothing malicious has been used to mislead you.
- In controversial cases, remember that the checklist determines only the general order of t he check. The final decision on project evaluation remains with the reviewer.

Main part

Exercise 00 - Learning URDF.

- Does the package contain robot.urdf, robot_dysplay.launch?
- After launching robot_dysplay.launch, does RVIZ start with the robot model?
- Look at the contents of the robot.urdf file, does the size of the robot meet the requireme nts?
- Wheels turning through GUI joint state publisher?
- Does the robot have Physical and Collision Properties set to a URDF Model?

No ✓ Yes

Exercise 01 - Using Xacro to Clean Up a URDF File.

- The package contains robot.urdf.xacro, robot_dysplay.launch?
- Does robot_dysplay.launch launch robot.urdf.xacro?
- After launching robot_dysplay.launch, does RVIZ start with the robot model?
- Look at the contents of the robot.urdf.xacro file, does the size of the robot meet the requ irements?
- Wheels turning through GUI joint state publisher?
- Does the robot have Physical and Collision Properties set to a URDF Model?

No ✓ Yes

Exercise 02 - Using a URDF in Gazebo.

- The package contains robot_gazebo.launch, robot.urdf.xacro, robot.gazebo.xacro?
- After launching robot_gazebo.launch, does RVIZ and Gazebo start with the robot model?- Look at the contents of the robot.urdf.xacro file, does the size of the robot meet the requirements?
- Wheels turning through GUI joint state publisher?
- Does the robot have Physical and Collision Properties set to a URDF Model?
- For the differential drive of the robot, gazebo_plugins libgazebo_ros_diff_drive.so is used in the file robot.gazebo.xacro?
- The robot rides in Gazebo controlled through the RobotSteering panel and topic / cmd_vel using rostopic pub commands.
- Robot moves in gazebo and rviz using keyboard via rosrun teleop_twist_keyboard teleop_twist_keyboard.py?

No ✓ Yes

Exercise 03 - Robot control program in Gazebo.

- The package contains files circle_movement.cpp, circle_movement.launch?
- After starting circle_movement.launch, does RVIZ and Gazebo start with the robot model?
- After starting circle_movement.launch, does RVIZ and Gazebo start with the robot moving in a circle?
- Run rqt_graph. The movement of the robot is carried out through the topic cmd_vel?
- In RVIZ, add Tf visualization. When the robot moves, do the odom frames change and the wheels rotate?

No ✓ Yes

Feedback

Fails

Crash | Forbidden functions | Empty work | Invalid compilation | Cheat

Comment

Leave a comment...

Review