

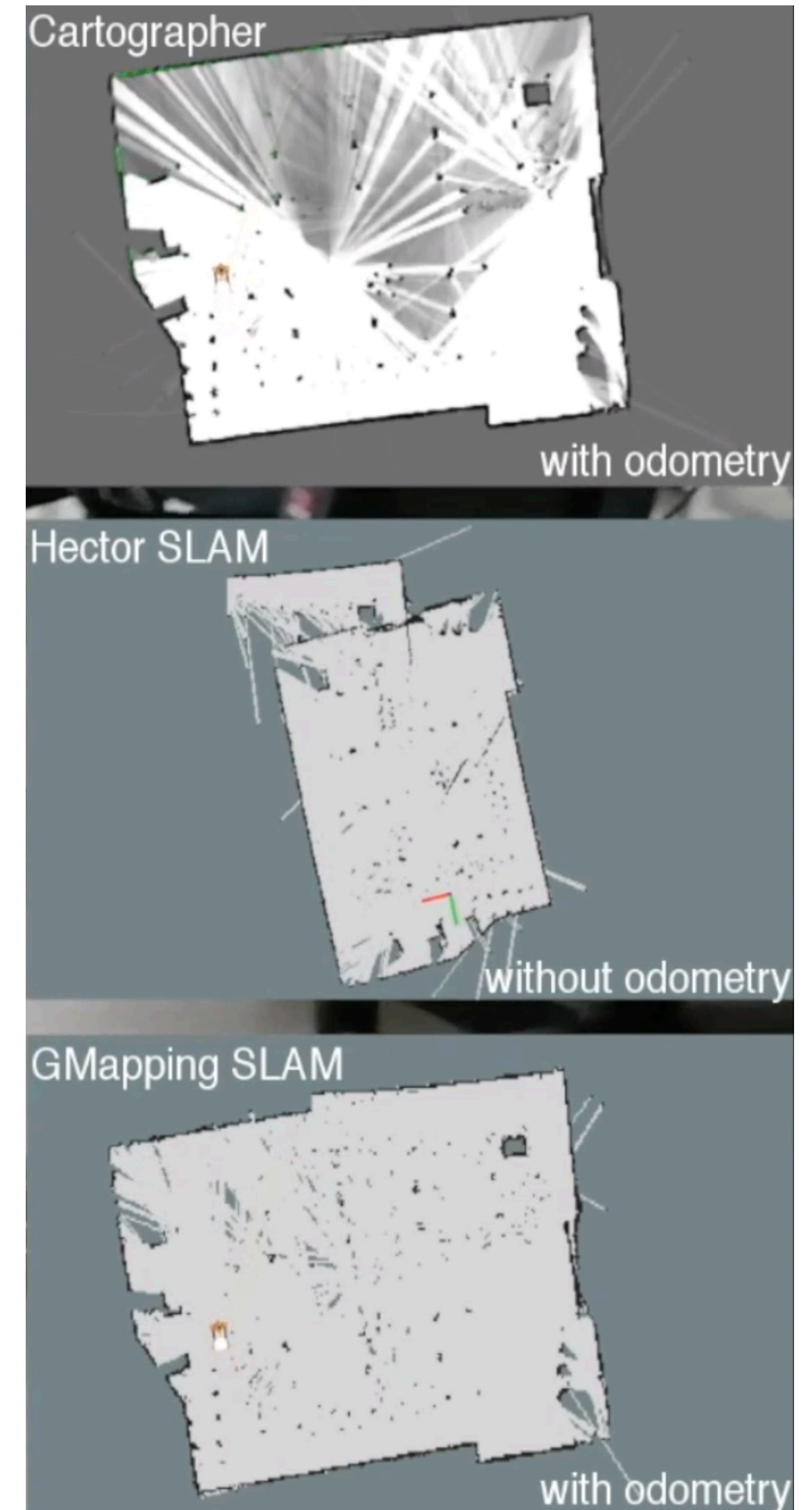
Parking team

Team progress



Roadmap

- Finish data analysis
- Improve the Kalman filter implementation
- Tune PID values in the velocity controller
- Follower follows splines
- Switch SLAM to Cartographer
- Test smooth driving
- Obstacle avoidance
- Demo preparations



Completed tasks



- Implemented Kalman filter
- Aligned IMU and LIDAR frames
- Calibrated steering
- Improved the Follower code
- Created a Launch file to simplify and speed up testing
- Recorded some data
 - LIDAR position, IMU and LIDAR orientation and car's velocity

Pending tasks



- **Figure out why low level driving does not work**
- Testing initialised values of Kalman Filter
- Tune PID values in the velocity controller
- Fully understand transformations in ROS to get Cartographer running
- Obstacle avoidance