Implementation of a Robot Behaviour Learning Simulator

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Recap - Last Meeting

In our last meeting, we wished the Turtlebot to not go diagonally but move in just 4 movements. There was also a discussion regarding what should be considered an obstacle and what should not be.

Today's Agenda

In today's meeting, I will demonstrate the Path Plannning that is done in those 4 movements only, as well as will talk about a method which might help us get the obstacle data as we wish to extract the information from the environment and not the robot itself.

Simulation Demonstration

Let us see the demonstration of the simulation now.

A possible Method for Obstacle Environment Generation

Map files and the related YAML files describe the presence of an obstacle or not, and in that case I will study that method or some other method I might find after asking from Internet Forums to see how we can extract the data from the simulation.

Thank you for your time.