

# Implementation of a robot behaviour learning simulator

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April 30, 2021

In our last meeting, we talked about the working of the simulator and the way it should log the data format from the simulation when it is running. I talked about the tools I might use to make the GUI and came to know the format for the log file.

# Today's Agenda

I was not able to work upon the data-log part of the simulation, but worked on

- Deciding the tool for Robot's GUI
- Making the GUI with a small turtlesim robot simulation
- Making the model for Gazebo's board, with boxes in Gazebo simulator

- I did not use JavaFX for making the GUI, after I read about ROS's RQT development kit.
- The way I made the GUI for a turtlesim simulation, I will have to make a plugin for logging the data in our preferred format.
- To make a box in 3D modelling, that entirely covers the box in our gazebo simulation.
- Placing the box in Gazebo, and trying to SLAM (*Simultaneous Localization and Mapping*) the robot around various boxes by giving a final goal point.

# Demonstrations

Let's move forward to see the demonstration.

# A humble suggestion

Due to working at home conditions right now, I find it a bit hard to focus. I chose not to go to Laboratory, due to the risks. I would appreciate if we could have more than one meeting in a week, with either one of you (if there are schedule clashes). It will help me focus more on the work than thinking 'friday is too far' and working loosely.



# Last Slide

Thank you for your time. I hope you have a great day.