

## **CS 69.13, Fall 2022, Elliot Potter**

### **Method Description**

This program is a modified version of the `simple_motion` program that you provided to us. I decided to import that program as a library, and then write a separate class to handle subscribing to odometry and publishing error messages. My program essentially is a for-loop where the robot drives forward, then rotates by  $360 \text{ deg} / \text{num\_sides}$ . It accepts parameters from the launch file, and these determine the size of polygon, number of sides, and direction of travel.

### **Evaluation**

This program worked fine. I essentially wrote it without testing it, and it pretty much worked as soon as I was able to get the file to run. I had the most difficulty figuring out the configuration of the package – I ended up iteratively converting `simple_motion` into the final package so that I knew exactly what was preventing the build. I ended up with a set of rules around creating ROS packages. You can find them in