

Minutes for meeting 22/02/13

Absent-Bartek, Finn

Vision

-Orientation method is good and very accurate but the method for finding the direction the robot is facing is not working efficiently. The error is currently down to 1 in 200.

-Possibly use the grey-circle method. Dale suggested a method that keeps the last 3 or so direction readings in a buffer and if the new reading is completely different to the readings in the buffer and the next few readings after that are the same then this is clearly the new direction the robot is facing else there was an error in reading the direction and it stays as it previously was.

-Sean has made a threshold GUI.

-Grenville will work on the vision test system once direction is fixed.

Strategy

-Sean has a skeleton of the code for planning n actions ahead.

-Mario is working on percepts. Should test them using fake world states or images.

-Bartek is working on a look-up table.

-Decided upon implementing the A* path-finding algorithm and looking into the Pure Pursuit version of the algorithm.

-Need a nice and snappy interface for Strategy, i.e. can the robot be interrupted mid command and issued a new one to follow. Synchronous and asynchronous commands.

Simulator

-It works, no longer flashes.

-But has an error, when you go forward at an angle it doesn't have a perfect accuracy because of rounding some number or something.

-Need to work on simulating steering and robot kick