UDACITY

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DISCUSS ON STUDENT HUB

Map My World Robot

REVIEW

HISTORY

Meets Specifications

Dear student,
Congratulations on passing this project of the course 👏🏻. It was great to review your submission. I've added some tips that might help you further your learning process. So please go through the comments carefully. Continue on in the course with the same enthusiasm. All the best to gaining more knowledge throughout the course.

Here is an external resource to further your learning.

- This wiki ros page will give more **insight about RTAB map and help you better tune the parameter for better performance.**

Happy learning. Have a great day.

Cheers.

Please don't forget to rate the review which will be helpful to me. Also leave a comment to let me know if I did something good or if you feel there is something that I need to improve in my review strategy to help serve students better as a reviewer.

Basic Requirements

Student submited all required files:

ROS Package: robot and RTABMAP
Db file generated (could be link to file if oversized)

✅ ROS Package: robot and RTABMAP
✅ Db file generated.

Feedback: Well done. You have submitted all the required files.

Simulation Setup

Student's simulation world and robot could properly load in Gazebo.

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Feedback: Great work. The robot is stable in the simulation environment.

The student's environment should have clear features and geometric shapes to perform mapping.

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Feedback: Feature are very important when you map an environment since the algorithm uses uniques features in the world to **create loop closure.** You world has enough. Your world has enough feature to do mapping. Great work👏.

Mapping Package

Student created the following launch files properly:
`mapping.launch`
`teleop.launch`
`localization.launch`
The student's program should be able to launch without errors

Student created the following launch files properly:
✅ mapping.launch
✅ teleop.launch
✅ localization.launch

Feedback: Well done. Keep up the good work.

Pro Tip 💫 **:**
Adding the following line on top before the **launch** tag will make the launch file appear colorful

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```
<?xml version="1.0" ?>
```

```
<?xml version="1.0"?>
<launch>
  <node pkg="teleop_twist_keyboard" type="teleop_twist_keyboard.py" name="teleop">
  </node>
</launch>
```

Mapping Accuracy

Student's map should contain at least 3 loop closures and the occupancy grid is identifiable

✅ Student's map should contain at least 3 loop closures and the occupancy grid is identifiable.

Feedback: The rtab map has sufficient loop closure to pass this rubric.

Student's map should clearly portray the environment. The student should be able to display the characteristics of the landmark features.

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Feedback: Well done. The 3D map is fantastic.

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