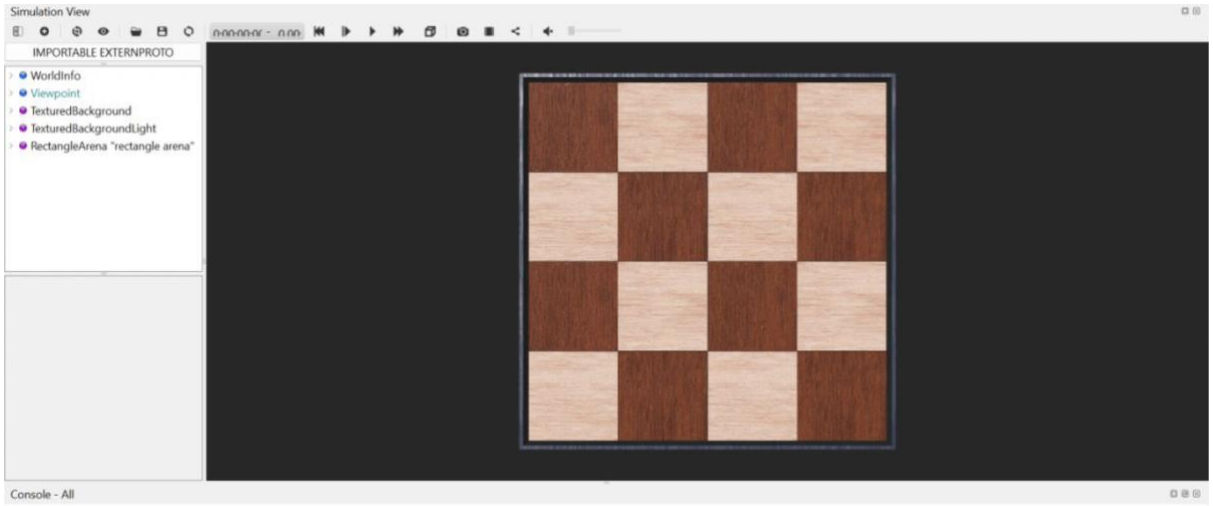
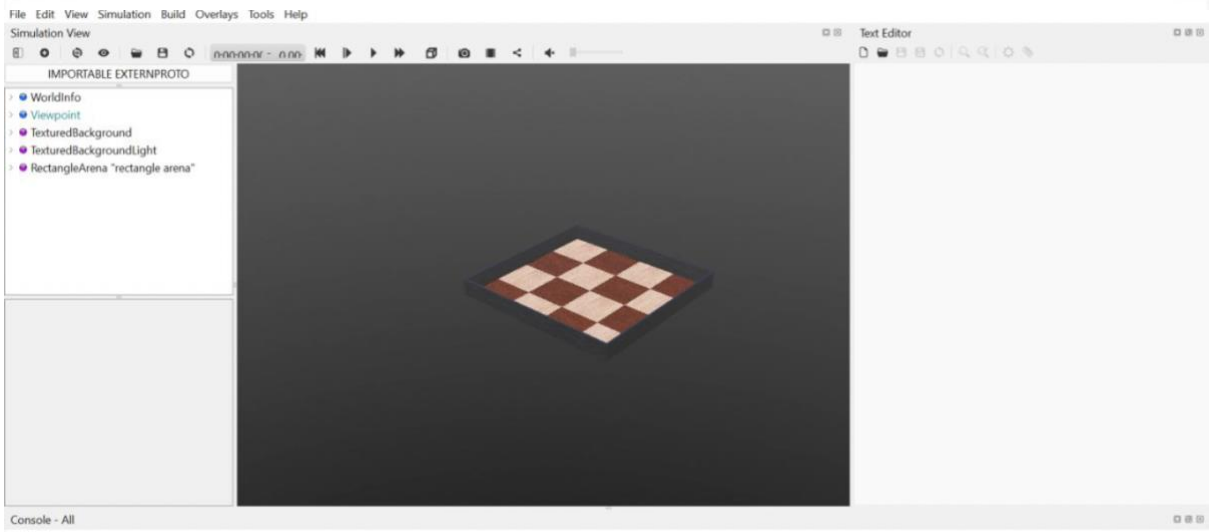
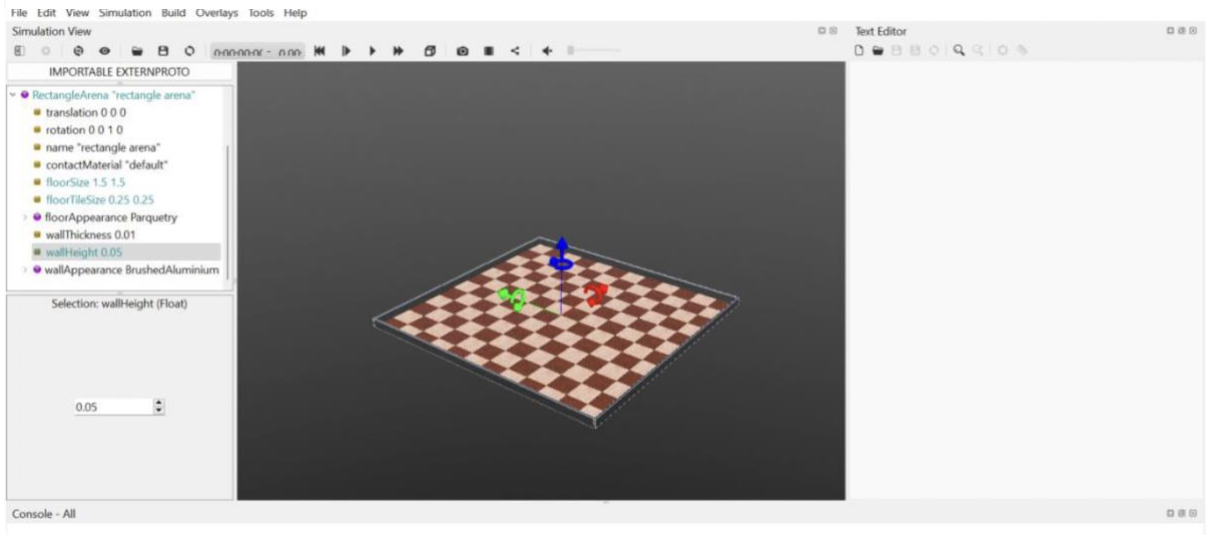
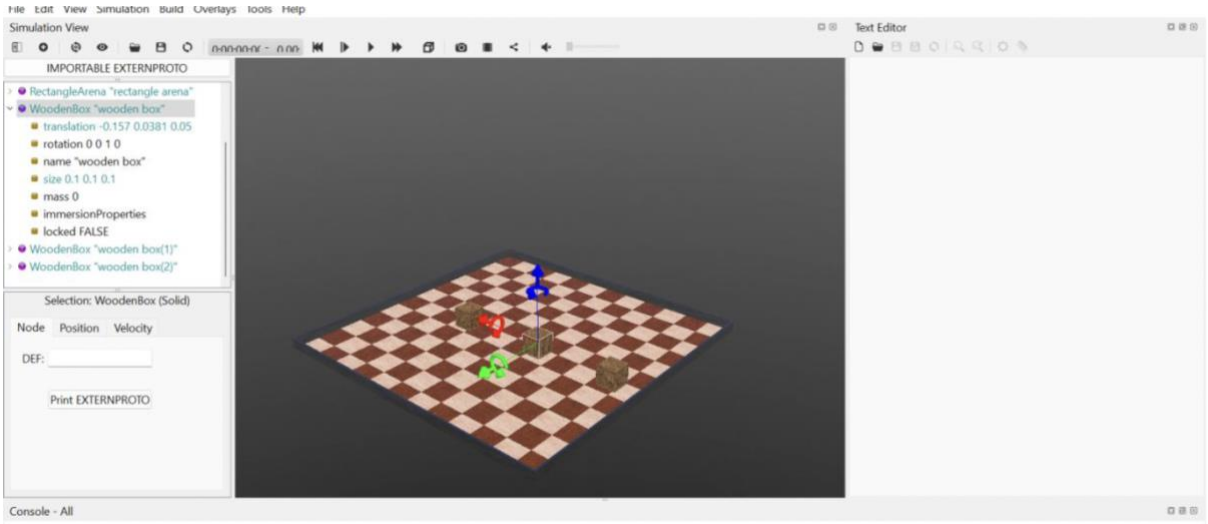
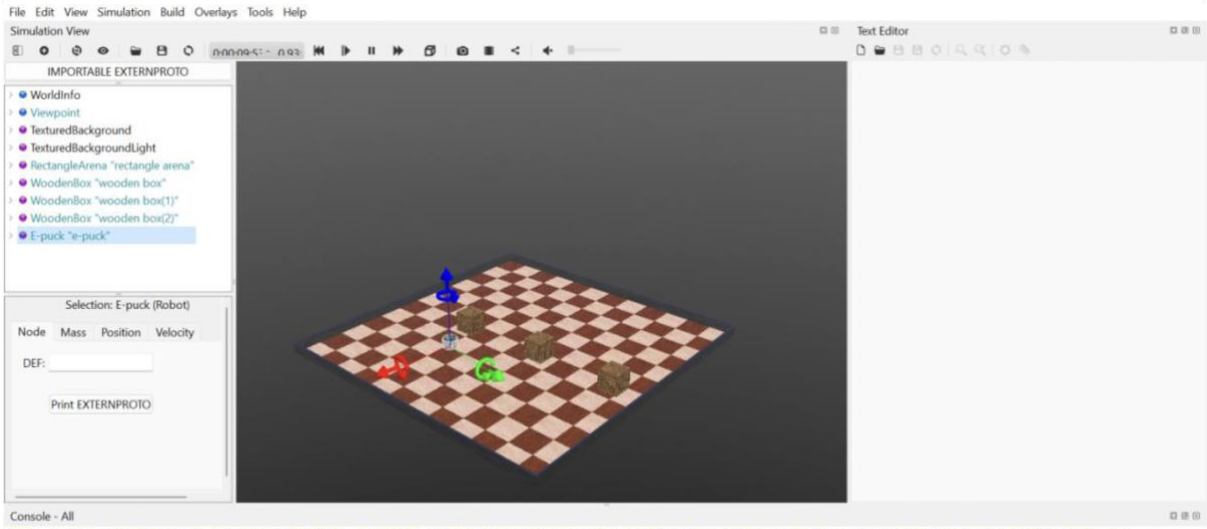
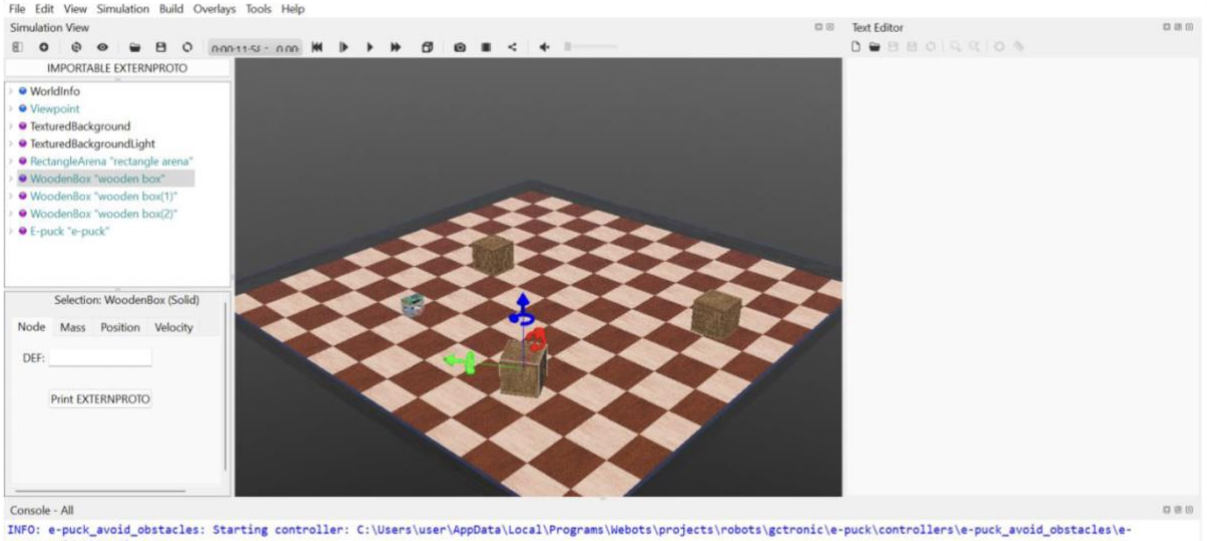

Simulation View
IMPORTABLE EXTERNPROTO
WorldInfo
Viewpoint
TexturedBackground
TexturedBackgroundLight
RectangleArena "rectangle arena"
Console - All

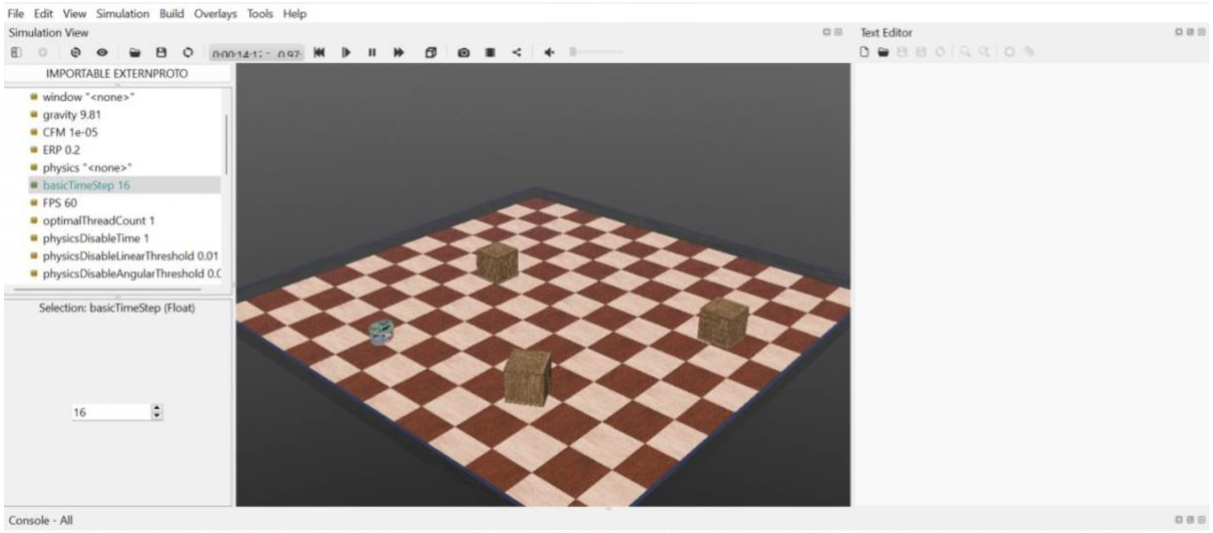

File Edit View Simulation Build Overlays Tools Help
Simulation View
Text Editor
IMPORTABLE EXTERNPROTO
WorldInfo
Viewpoint
TexturedBackground
TexturedBackgroundLight
RectangleArena "rectangle arena"
Console - All

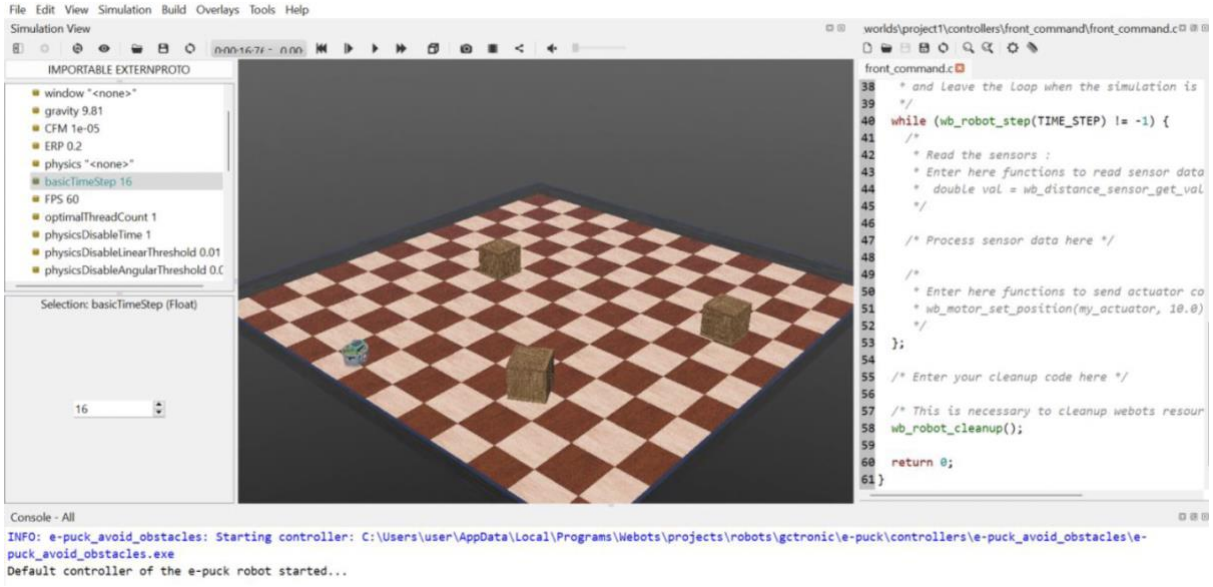

File Edit View Simulation Build Overlays Tools Help
Simulation View
Text Editor
IMPORTABLE EXTERNPROTO
RectangleArena "rectangle arena"
translation 0 0 0
rotation 0 0 1 0
name "rectangle arena"
contactMaterial "default"
floorSize 1.5 1.5
floorTileSize 0.25 0.25
floorAppearance Parquetry
wallThickness 0.01
wallHeight 0.05
wallAppearance BrushedAluminium
Selection: wallHeight (Float)
0.05
Console - All

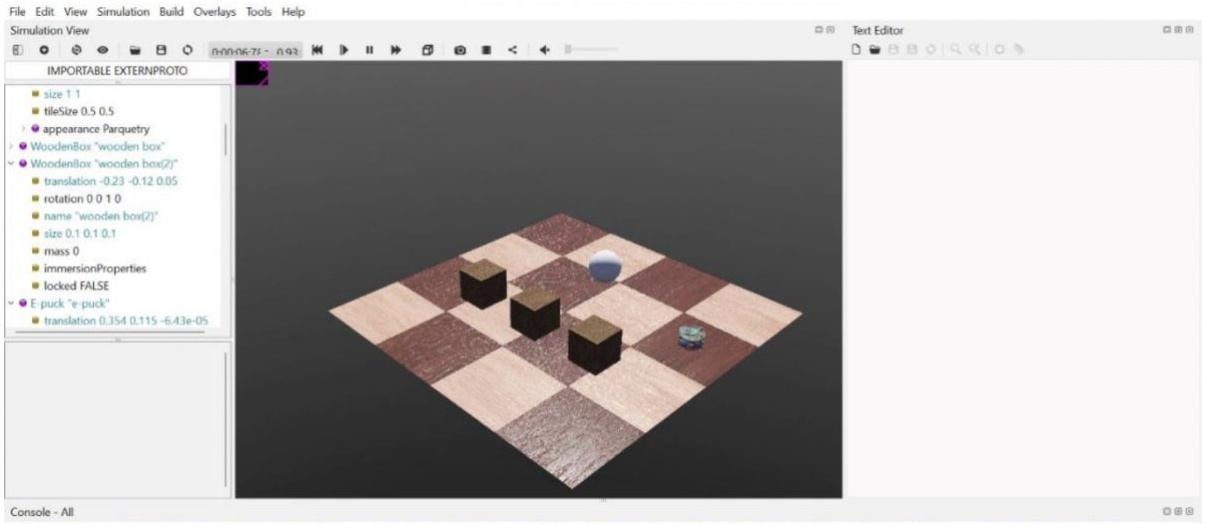

File Edit View Simulation Build Overlays Tools Help
Simulation View
Text Editor
IMPORTABLE EXTERNPROTO
RectangleArena "rectangle arena"
WoodenBox "wooden box"
translation -0.157 0.0381 0.05
rotation 0 0 1 0
name "wooden box"
size 0.1 0.1 0.1
mass 0
immersionProperties
locked FALSE
WoodenBox "wooden box(1)"
WoodenBox "wooden box(2)"
Selection: WoodenBox (Solid)
Node Position Velocity
DEF:
Print EXTERNPROTO
Console - All

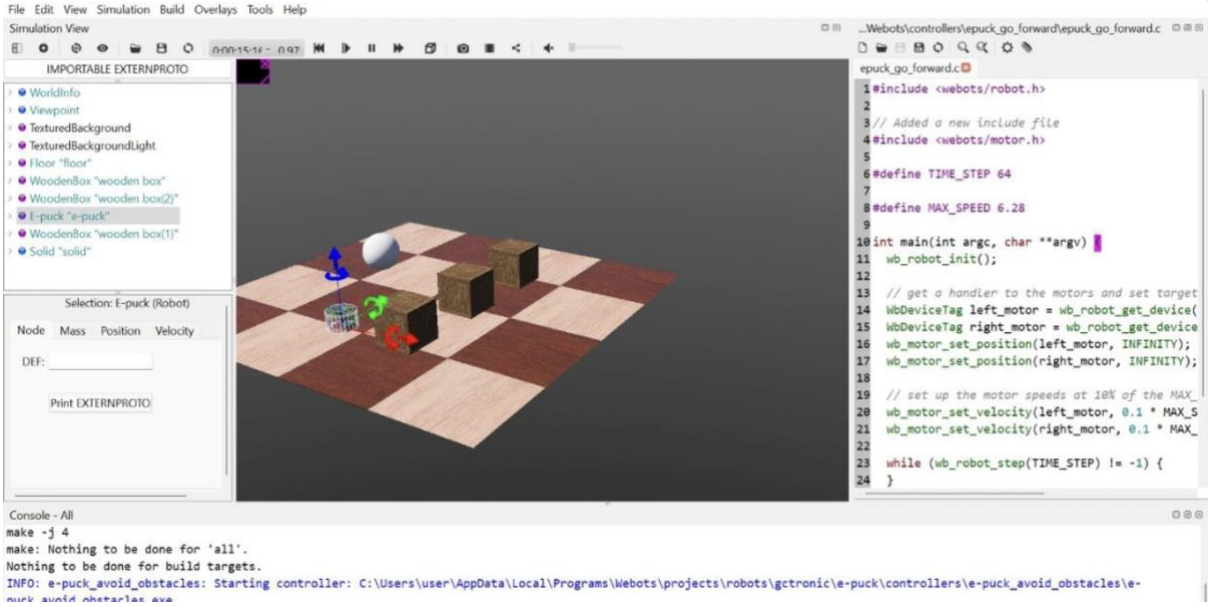

File Edit View Simulation Build Overlays Tools Help
Simulation View
Text Editor
IMPORTABLE EXTERNPROTO
WorldInfo
Viewpoint
TexturedBackground
TexturedBackgroundLight
RectangleArena "rectangle arena"
WoodenBox "wooden box"
WoodenBox "wooden box(1)"
WoodenBox "wooden box(2)"
E-puck "e-puck"
Selection: E-puck (Robot)
Node Mass Position Velocity
DEF:
Print EXTERNPROTO
Console - All
INFO: e-puck_avoid_obstacles: Starting controller: C:\Users\user\AppData\Local\Programs\Webots\projects\robots\gctronic\e-puck\controllers\e-puck_avoid_obstacles\e-puck_avoid_obstacles.exe
Default controller of the e-puck robot started...


File Edit View Simulation Build Overlays Tools Help
Simulation View
Text Editor
IMPORTABLE EXTERNPROTO
WorldInfo
Viewpoint
TexturedBackground
TexturedBackgroundLight
RectangleArena "rectangle arena"
WoodenBox "wooden box"
WoodenBox "wooden box(1)"
WoodenBox "wooden box(2)"
E-puck "e-puck"
Selection: WoodenBox (Solid)
Node Mass Position Velocity
DEF:
Print EXTERNPROTO
Console - All
INFO: e-puck_avoid_obstacles: Starting controller: C:\Users\user\AppData\Local\Programs\Webots\projects\robots\gctronic\e-puck\controllers\e-puck_avoid_obstacles\e-puck_avoid_obstacles.exe
Default controller of the e-puck robot started...


File Edit View Simulation Build Overlays Tools Help
Simulation View
IMPORTABLE EXTERNPROTO
window "<none>"
gravity 9.81
CFM 1e-05
ERP 0.2
physics "<none>"
basicTimeStep 16
FPS 60
optimalThreadCount 1
physicsDisableTime 1
physicsDisableLinearThreshold 0.01
physicsDisableAngularThreshold 0.0
Selection: basicTimeStep (Float)
16
Text Editor
Console - All
INFO: e-puck_avoid_obstacles: Starting controller: C:\Users\user\AppData\Local\Programs\Webots\projects\robots\gctronic\e-puck\controllers\e-puck_avoid_obstacles\e-puck_avoid_obstacles.exe
Default controller of the e-puck robot started...


File Edit View Simulation Build Overlays Tools Help
Simulation View
IMPORTABLE EXTERNPROTO
window "<none>"
gravity 9.81
CFM 1e-05
ERP 0.2
physics "<none>"
basicTimeStep 16
FPS 60
optimalThreadCount 1
physicsDisableTime 1
physicsDisableLinearThreshold 0.01
physicsDisableAngularThreshold 0.0
Selection: basicTimeStep (Float)
16
worlds\project1\controllers\front_command\front_command.c
front_command.c
* and leave the loop when the simulation is
*/
while (wb_robot_step(TIME_STEP) != -1) {
/*
* Read the sensors :
* Enter here functions to read sensor data
* double val = wb_distance_sensor_get_val
*/
/* Process sensor data here */
/*
* Enter here functions to send actuator co
* wb_motor_set_position(my_actuator, 10.0)
*/
};
/* Enter your cleanup code here */
/* This is necessary to cleanup webots resour
wb_robot_cleanup();
return 0;
}
Console - All
INFO: e-puck_avoid_obstacles: Starting controller: C:\Users\user\AppData\Local\Programs\Webots\projects\robots\gctronic\e-puck\controllers\e-puck_avoid_obstacles\e-puck_avoid_obstacles.exe
Default controller of the e-puck robot started...


File Edit View Simulation Build Overlays Tools Help
Simulation View
Text Editor
IMPORTABLE EXTERNPROTO
size 1 1
tileSize 0.5 0.5
appearance Parquetry
WoodenBox "wooden box"
WoodenBox "wooden box(2)"
translation -0.23 -0.12 0.05
rotation 0 0 1 0
name "wooden box(2)"
size 0.1 0.1 0.1
mass 0
immersionProperties
locked FALSE
E-puck "e-puck"
translation 0.354 0.115 -6.43e-05
Console - All
INFO: e-puck_avoid_obstacles: Starting controller: C:\Users\user\AppData\Local\Programs\Webots\projects\robots\gctronic\e-puck\controllers\e-puck_avoid_obstacles\e-puck_avoid_obstacles.exe
Default controller of the e-puck robot started...


File Edit View Simulation Build Overlays Tools Help
Simulation View
...Webots\controllers\epuck_go_forward\epuck_go_forward.c
IMPORTABLE EXTERNPROTO
WorldInfo
Viewpoint
TexturedBackground
TexturedBackgroundLight
Floor "floor"
WoodenBox "wooden box"
WoodenBox "wooden box(2)"
E-puck "e-puck"
WoodenBox "wooden box(1)"
Solid "solid"
Selection: E-puck (Robot)
Node Mass Position Velocity
DEF:
Print EXTERNPROTO
epuck_go_forward.c
#include <webots/robot.h>
// Added a new include file
#include <webots/motor.h>
#define TIME_STEP 64
#define MAX_SPEED 6.28
int main(int argc, char **argv)
wb_robot_init();
// get a handler to the motors and set target
WbDeviceTag left_motor = wb_robot_get_device(
WbDeviceTag right_motor = wb_robot_get_device
wb_motor_set_position(left_motor, INFINITY);
wb_motor_set_position(right_motor, INFINITY);
// set up the motor speeds at 10% of the MAX_
wb_motor_set_velocity(left_motor, 0.1 * MAX_S
wb_motor_set_velocity(right_motor, 0.1 * MAX_
while (wb_robot_step(TIME_STEP) != -1) {
}
Console - All
make -j 4
make: Nothing to be done for 'all'.
Nothing to be done for build targets.
INFO: e-puck_avoid_obstacles: Starting controller: C:\Users\user\AppData\Local\Programs\Webots\projects\robots\gctronic\e-puck\controllers\e-puck_avoid_obstacles\e-puck_avoid_obstacles.exe