[Friday 26 April] Scrum Meeting

Attendees

- @Finlay Cross
- @Benjamin Ireland
- @Ronniel Padua
- @Se Hyun Kim

🔗 Links

- *[Link to meeting recording]*
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- *[Link to key resources for easy reference]*

📝 Agenda Items & Notes Overview

Objective

Topic	Description

Next Steps

Network Protocol:

- Migrate to ROS2
- Develop API

Path Planning:

- Port to C++
- Add all identified changes to word doc

Visualisation:

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Application and Integration:

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General

Research ROS-1 to ROS-2. Suggestion to change TCP to UDP - UDP only available on ROS-2

A

MINUTES

- Start with Ros2 migration
  - good is succinct
  - bad - some code does not exist in ros2 that existed in ros1, libraries have been deprecated - specifically network system (ros.h rclcpp.h timers have been swapped for another timer class good change just more work)
  - timing shouldn't be too difficult - about a week
- Raith
  - data base has been setup
- Ben
  - network migration
  - control migration
  - a lot of time is going into understanding why they are doing things
- data dissemination hasn't been integrated, exist but not integrated
  - switch from ros publishers to beaconing protocol
- Controller
  - generated control is interfacing with pixhawk
  - controller interacts with generated controller

- lifecycle
  - drones go through a lifecycle
    - launch
    - formation
    - wait
    - move
    - drone battery die - drone goes back
    - drones react to how (formation continues or all go home)
  - translation
    - trajectory c++
    - lifecycle maybe keep python, focus on the time critical stuff
  - networking
    - uses tcp
    - do we want udp?
    - want to get rid of ros master ros slave
  - Control leadership
    - would like to have
    - each drone behaves as a slave
    - master process that publishes the Di
  - Master down out of scope