**Questionnaire**

1. [C++] What is the mean of the number "15" used in the pthread\_kill inside the destructor method?
2. [C++] Why are we using UniquePointer instead of SharedPointers to publish a ROS2 message?
3. [Logic] Why are we using an m\_multi\_sound variable? Explain ...
4. [C++] Why are we freeing the memory allocated by raw pointer "buff" variable and not freeing the memory allocated by the Shared and Unique Pointers? (HARD)
5. [C++] Why should we use a "member variable" (persistent over the class) to storage the integral error? m\_vx\_int\_error
6. [Control] What is the function of the FeedForward controller?
7. [ROS2] What is the purpose of CascadeLifecycleNode type nodes?
8. [Robotics] Why is a global and a local Odometry calculated?
9. [Robotics] If the robot has 4 differential wheels, what type of chassis is it?
10. [Docker] Explain with your own words what is the instructions apt-get autoremove && apt-get clean -y for?
11. [Docker] If you modify a layer what happen with the previous and the next ones?
12. [Docker] Can we change the basic image (FROM ubuntu:20.04) from the docker file to another?
13. [C++] What is the [libsoft\_speed.a](https://github.com/hugoceledon/Robotics-Test-Integration-Engineer/blob/develop/robotics/ros2/src/motion_control/lib) file and what is it for?
14. [Python] Why should we use a thread to spin the node?
15. [Python] Why is the limit on the Y-RPM graph 170?
16. What do you think about this project?
17. Is it hard or enough? Is it to complicated, is it well structure, explanations and instructions are clear?