

Our final project demo worked out alright in spite of a couple of unexpected problems that we encountered, mostly a result of Murphy's Law. The biggest one that ate up the most time was that the bluetooth connection seemed to randomly drop about halfway through the demo, meaning our robot was unable to receive messages from the controller, and vice versa. We probably took too much time to solve this problem because we believed it might resolve itself if we left the robot alone, but after getting Shouvik to restart the robot and reset the Bluetooth USB connection, we were able to resume the demo and complete the mission.

Another large problem we had was possibly more of our fault. Early on we ended up close to the Northern wall of the hallway, and mapped towards the Southern wall while going down the hallway. Since we were unable to see the wall as we were moving, looking the other way, we ended up much too close to it and probably spun a little bit without the robot realizing it. This led to us having to waste time getting the robot to rotate and travel its way away from the wall before we could fix and get a good reading on our location, but once that was complete we were back on track and there were no lasting effects of this error, other than a time delay.