"Correct answer" questions

What are the four "quirks" mentioned across the videos?

Whats the difference between a blocking and non-blocking function?

What was wrong/missing from the "setting up spot" video???

What camera sensors does spot have?

Conceptual questions (e.g. “why” not “what”)

When running at full speed, do you think spot's obstacle avoidance will stop it from hitting a wall? Why? (We'll find out Friday!)

What gaits (book terminology) did you see and not see?

Why do you think the designers made the decision(s) to include/exclude those gaits?

Do you think spot uses a central pattern generator? Why or why not?

(more questions on next page)

Do you think the spot controller has some form of innate releasing mechanisms?
Make sure to mention obstacle avoidance and stair traversal when justifying your answer.

Do you think the spot controller has some level of behavior coordination? why or why not?

Do you think spot uses one of the three systems architectures? which (if any) and why?

Code-change questions

For reference here's a copy of the code-task instructions:

- Download this hello_spot.py file
- Change #1: go to the "Robot standing twisted." part
  - Find the `command_client.robot_command(` part
  - 1. Duplicate the whole function call, and edit the one further down
  - 2. Inside of it change `yaw` to be 0 and `pitch` to be 0.4
- Change #2: go to the section that mentions "absolute body control"
  - change the `z` value of the second `math_helpers.Quat(` object to `0.4`
  - within that section there are time durations for each movement
  - double the amount of time between those movements
- Upload the modified code to canvas

Why do you think the second `time.sleep(3)` is in the code? What would removing it probably do?

(more questions on next page)

What do you think change #1 will do?

What do you think change #2 would do?