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EECS 373
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Assignment P3

Changes to P1/P2

To implement action client/service functionality, the sin_commander was split into two files. The client requested input from the user, which was packaged into an action message and sent to an instantiation of the server class. The client then waited for the result message from the server, timing the delay. The server was written as a class and instantiated. The instance received the action message, recorded the values contained in the message, and commanded a sin wave to the minimal_simulator and minimal_controller as previously seen. Once the goal number of cycles requested by the user was completed, the velocity was reset and a result was returned to the client.

The behavior of the new implementation of sin_commander is shown in the below screenshot. Included are command line outputs of the action server and client, as well as a plot of the resulting commanded velocity.