Lab 4: Trajectory Optimization

VNAV 2020

https://mit-spark.github.io/VNAV2020-handouts/lab4/

Unity Simulator

tesse_core

Sensors + Networking

tesse_ros_bridge

Python ROS node that connects with Unity

controller_pkg (from lab 3)

/desired_state

traj_vertices_publisher

waypoints

trajectory_generation_node
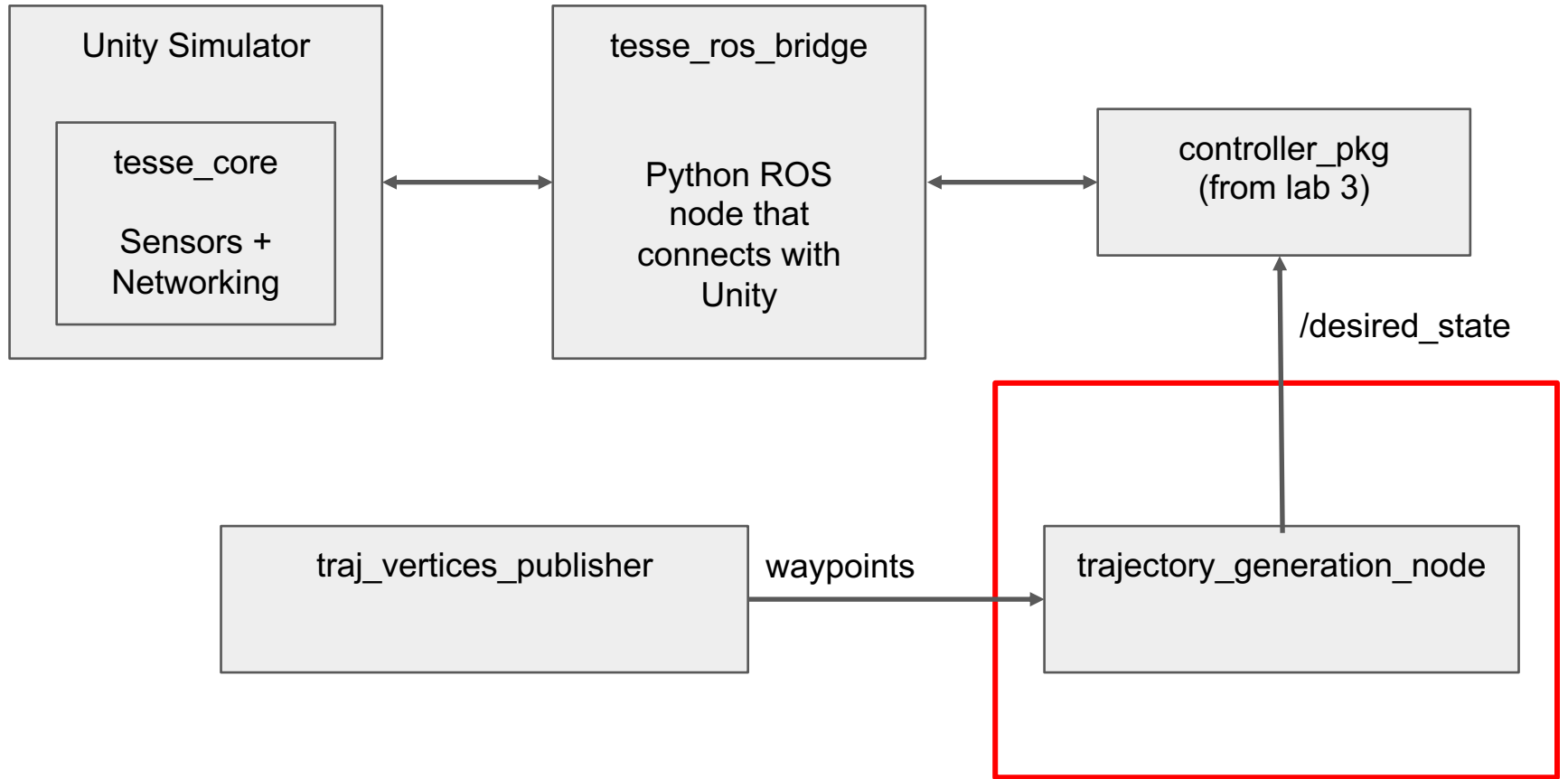
Your code goes here![3]

Racing Tips

1. Change trajectory segment times -- adjust v_max and a_max, or set your own times manually
2. Tune controller parameters in controller_pkg
3. Play with mav_trajectory_generation parameters

16.485 Visual Navigation for Autonomous Vehicles (VNAV)
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