

# AAMR FINAL PROJECT

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## TEAM JIMAKI

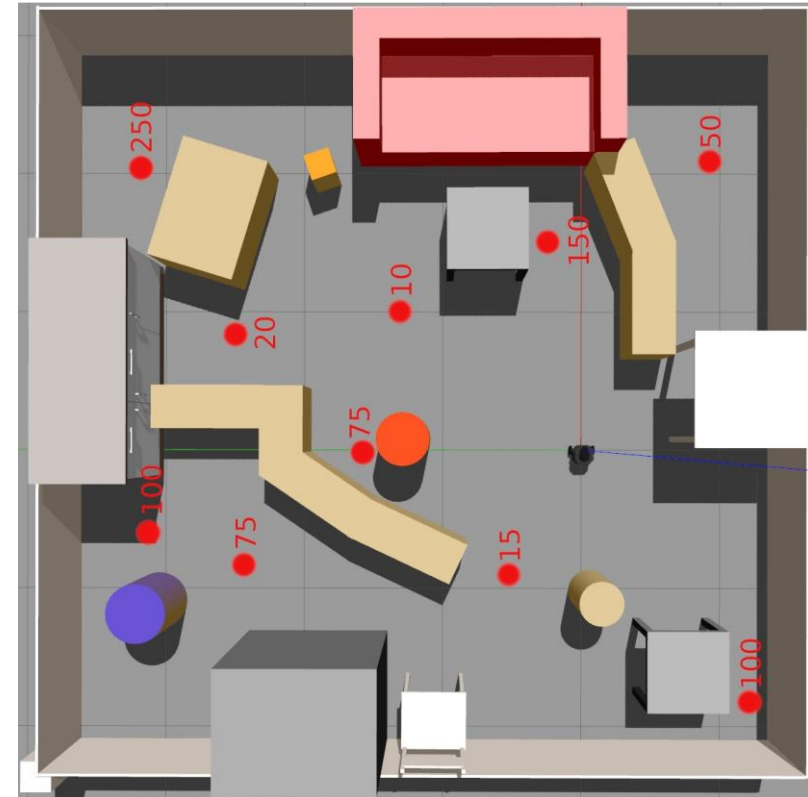
JIBIN THOMAS MATHEW - 32945

KISHORE GOVINDA REDDY - 32917

MANJUNATH KRISTAPPA BADAMI - 33053

# Tasks to accomplish

- Collect as many reward points as possible in the stipulated time whilst avoiding collisions with obstacles or other bots.



# Things that everyone knows

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- move\_base
- AMCL
- Global planner – Navfn
- Local planner – DWAlocalplanner

# Things exclusive to JiMaKi (hopefully)

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Which parameters did we tune?

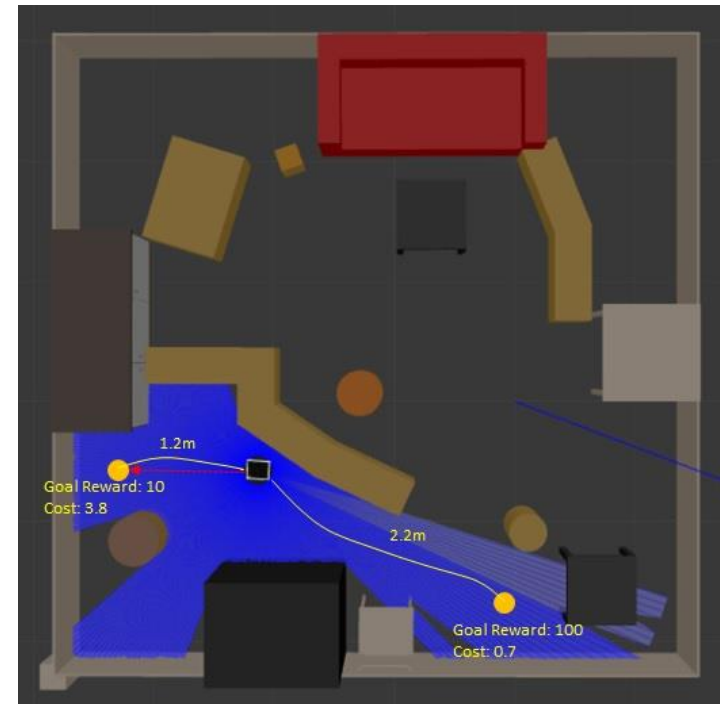
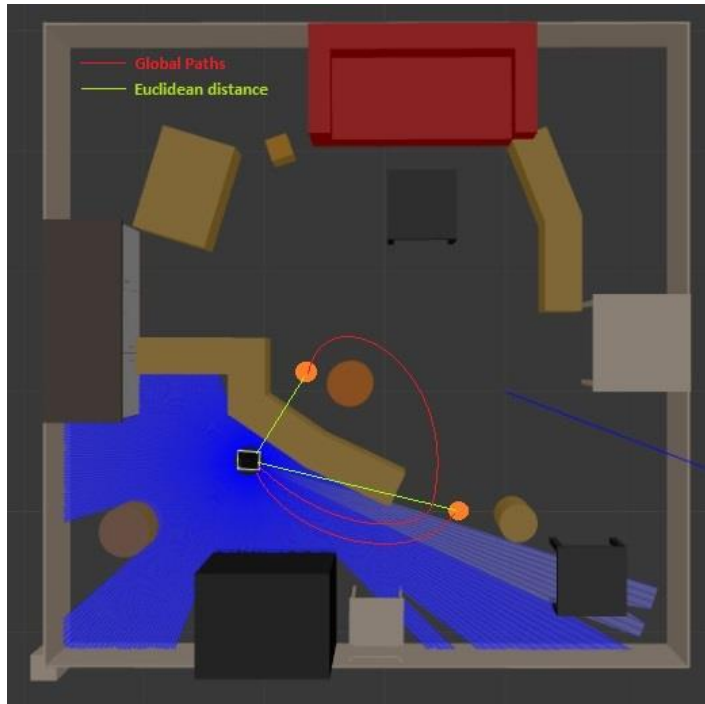
Goal tolerance

- `xy_goal_tolerance` = 0.175 meters
- `yaw_tolerance` = 6.28 ( $\approx 2\pi$  radians)



# Things exclusive to JiMaKi (hopefully)

How do we sort the goals?

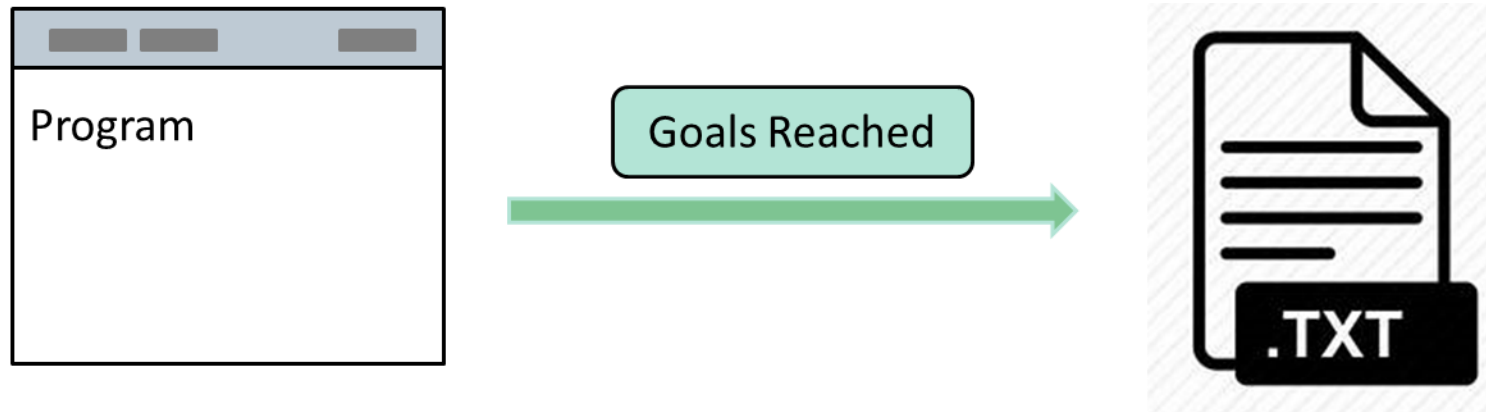


# Things exclusive to JiMaKi (hopefully)

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How do we deal with restarts?

After the turtlebot reaches a goal, we write the goal information to a file and this file is read whenever the turtlebot gets stuck and the program is restarted helping us avoid visiting the goals already reached.

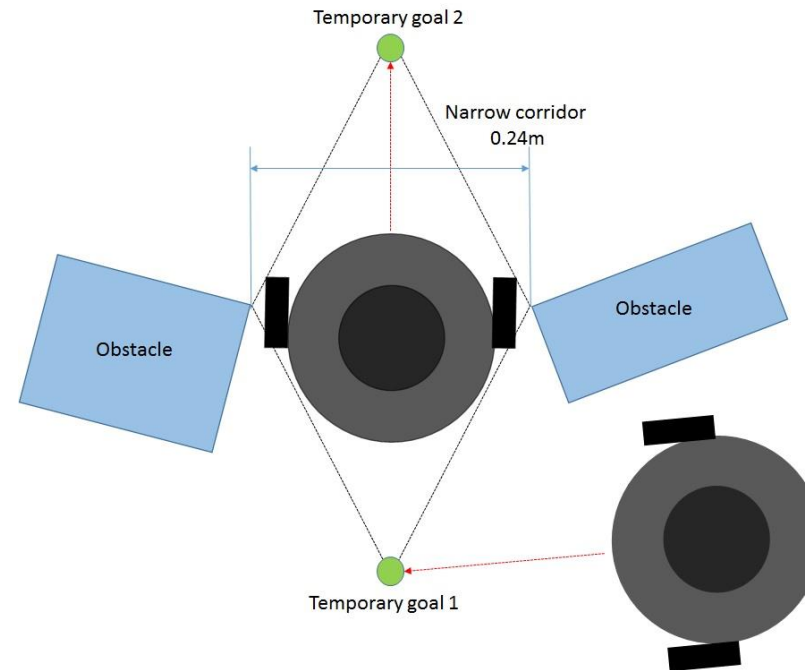


# Things exclusive to JiMaKi (hopefully)

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What will we do if *move\_base* fails to reach any goal ?

We switch to the manual driving mode



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# THANK YOU

