

ROB301 Lab 1 Report

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Deliverable 5.1

The robot will go forward for 5 seconds at 0.2m/s and will stop after a meter of moving and start rotating 360 degrees. The robot will stop moving after this.

The function we wrote is running at 10 hz. We used a while loop and initialized two counters outside of the loop both to be 0: one for rotation and one for forward motion. In the while loop there are if conditions for when the robot's speed should be set and when it should be rotating. If the motion counter is less than 50 it will continue to set the motion to 0.2m/s and increment the motion counter by one each time. After the motion counter is over 50, it will check if the rotation counter is less than 50. If so, the forward speed will be set to 0 m/s and the rotational speed will be set to 0.2rad/s. If both conditions are not met, the robot's rotational speed will be set to 0.

We were able to complete the deliverable.