# List of possible bugs detected in Morse Simulator

**Simulation and communications management in a multi-robot environment**
*Internship*

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# List of possible bugs detected

1. The robot **Jido()** doesn't fall with gravity:

   *jido.translate(x=-5, z=1)....* It is levitating all the time with this 'z' coordinate.

2. Documentation of **Supervision Services** doesn't present all methods like *get_all_stream_ports*.
   http://www.openrobots.org/morse/doc/latest/user/supervision_services.html

3. Class **Quadrotor()**, 2 different robots with the same name? The 2nd is the default (?)

   http://www.openrobots.org/morse/doc/latest/user/robots/quadrotor.html

   http://www.openrobots.org/morse/doc/latest/user/robots/quadrotor_dynamic.html

4. Error related with **Waypoint()** usage -> Radar (Left or Right). For example, running the script bellow, the B21 robot tries to stay in its initial position. Using the ATRV, if we constantly push B21 away from this initial (or other destination) point, at some moment the Blender quits and enunciates the errors shown in XXX.

   Script: https://raw.github.com/pauloet/morse/master/My_Simulations/bug1.py