

Lab 3: Safe Driving

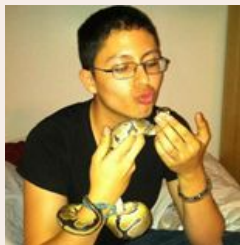
Team 6:
Big Hero 6

"You will be alright. There, there."





Evie
Kyritsis



Juan
Huertas



Brian
Plancher



Alan
Tham



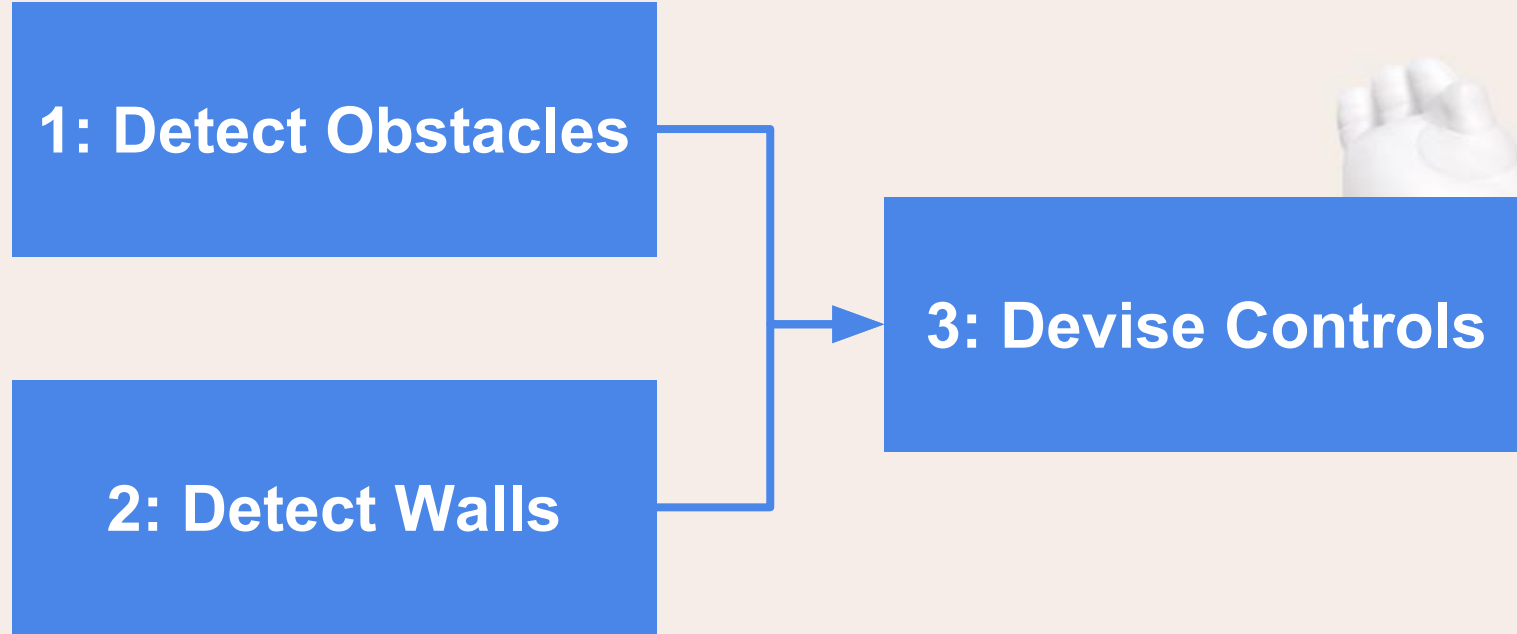
Mario
Pardo



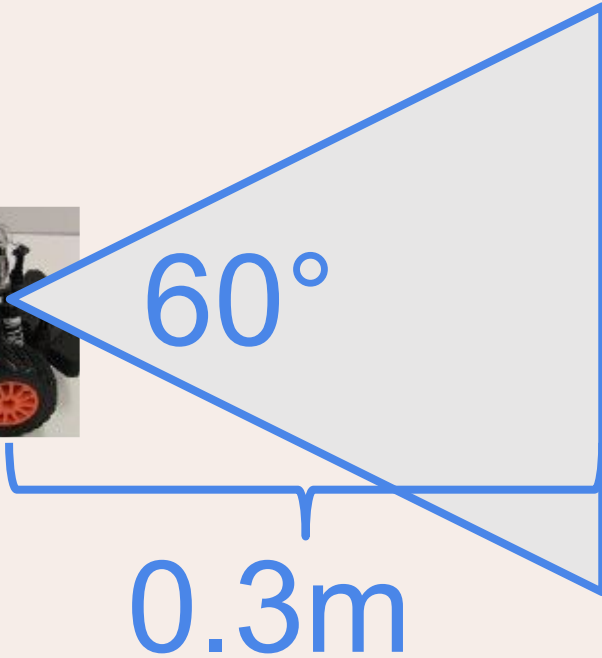
Liang
Zhou



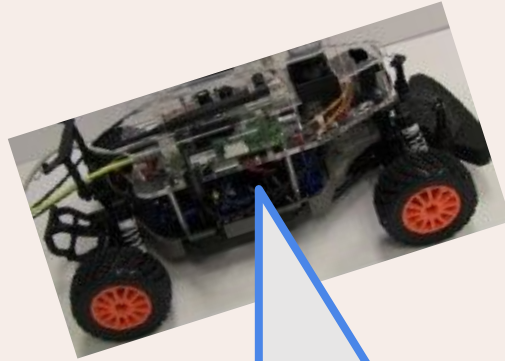
Assignment was divided into three teams of two



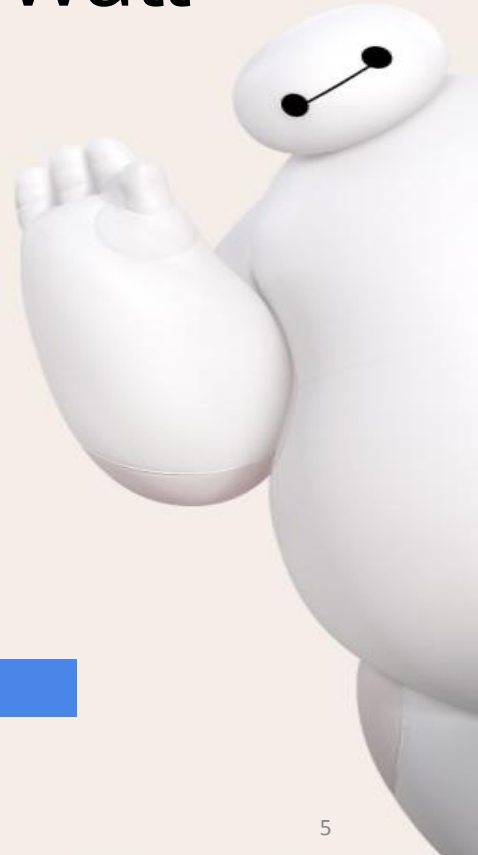
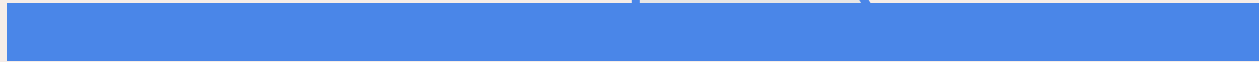
1: We detect obstacles by examining the cone of laser scan data in front of the car



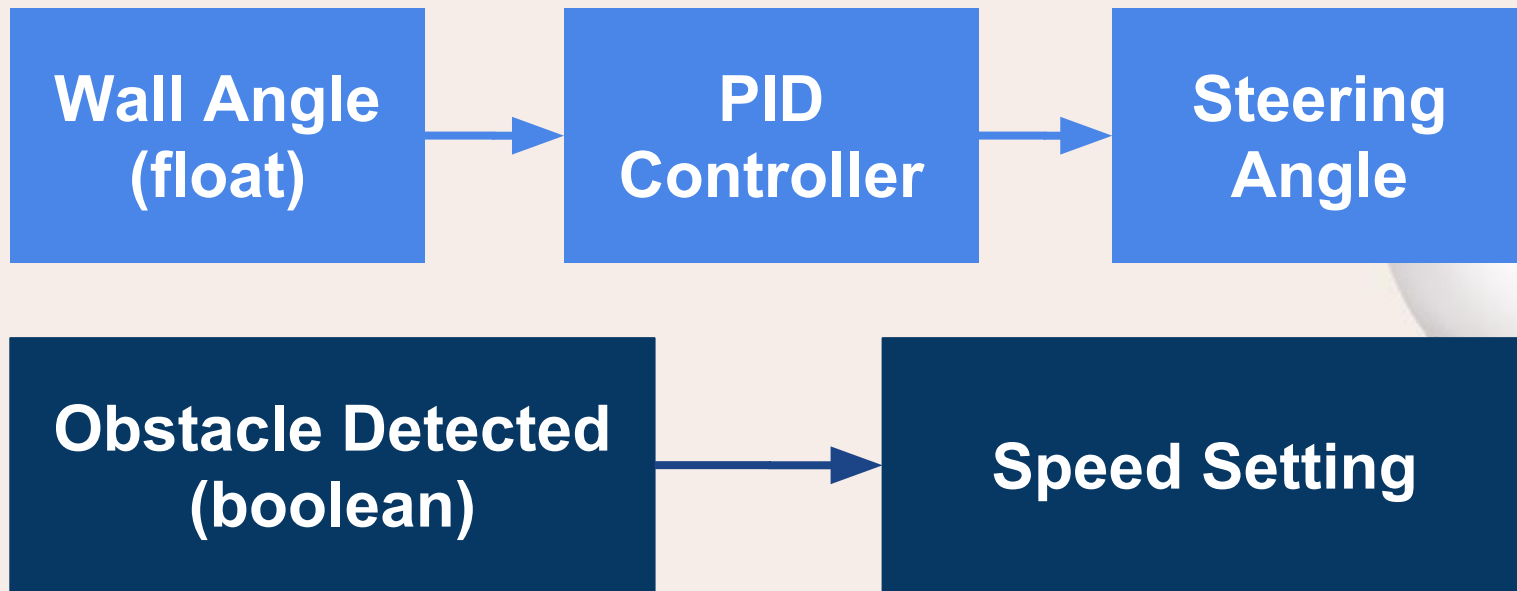
2: We detect walls by determining the angle of the shortest path to the wall



θ



3: A simple PID controller and boolean are used to safely follow walls



We could avoided obstacles but not follow walls due to a broken VESC



<https://www.youtube.com/watch?v=ftMEKGku-48>

Our key lesson learned: We need to improve our communication

**Between Nodes in
ROS**

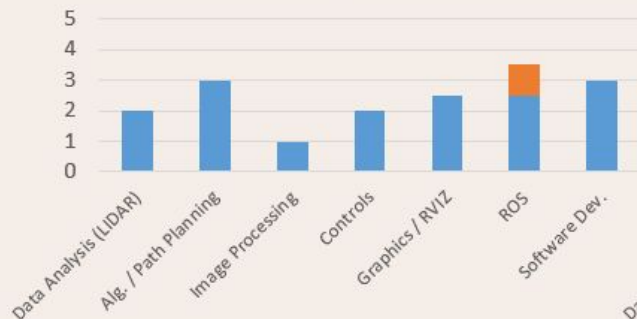
**Between Team
Members**

**Between Team and
Course Staff**

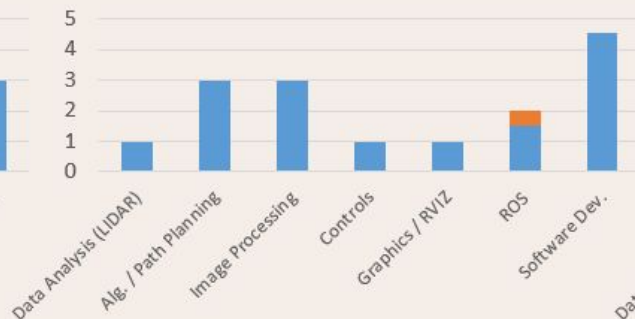


We learned most about ROS this week

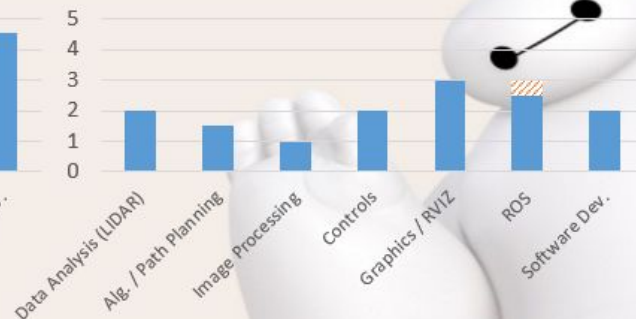
Evie Kyritsis



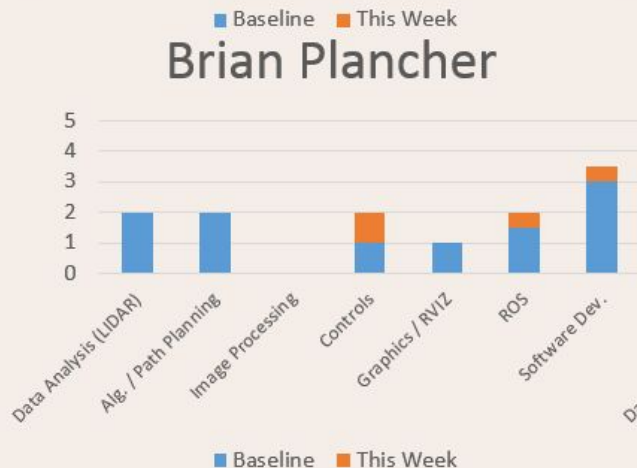
Juan Huertas



Mario Pardo



Brian Plancher



Alan Tham



Liang Zhou



Questions?
Comments?

