Group 3: Voice-Controlled Robot
Assignment 4: Code Testing
6 April 2024

# Test cases for voicerobots-server/src/decisionmaker.py

**Test Case ID: 1**
**Test Priority (Low/Medium/High):** High
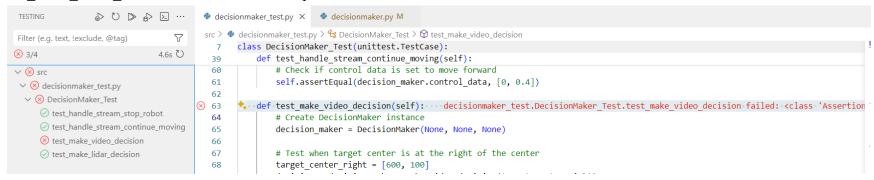**Module Name:** decisionmaker.py
**Test Designed & Executed By:** Japheth Beiler
**Test Design Date:** 4 April 2024

| Step | Test Name | Class & Method | Test Data/ Parameters | Expected Result | Actual Result | Status (Pass/ Fail) | Comments |
|---|---|---|---|---|---|---|---|
| 1 | test_handle_stream_stop_robot | Class: DecisionMaker Method: _handle_stream | target_center: [480, 100] lidar_scan: [90, 100, 70] | control_data: [0, 0] | control_data: [0, 0] | **Pass** | |
| 2 | test_handle_stream_continue_moving | Class: DecisionMaker Method: _handle_stream | target_center: [480, 100] lidar_scan: [60, 80, 110] | control_data: [0, 0.4] | control_data: [0, 0.4] | **Pass** | |
| 3 | test_make_video_decision | Class: DecisionMaker Method: _make_video_decision | target_center: [600, 100] | video_control_decision: [0.125, 0] | video_control_decision: [0.125, 0] | **Pass** | |

| 4 | test_make_video_decision | Class: DecisionMaker Method: _make_video_decision | target_center: [300, 100] | video_control_decision: [-0.1875, 0] | video_control_decision: [-0.1875, 0] | **Pass** | |
|---|---|---|---|---|---|---|---|
| 5 | test_make_video_decision | Class: DecisionMaker Method: _make_video_decision | target_center: [480, 100] | video_control_decision: [0, 0.4] | video_control_decision: [0, 0.4] | **Pass** | |
| 6 | test_make_video_decision | Class: DecisionMaker Method: _make_video_decision | target_center: [0, 0] | video_control_decision: [0, 0] | video_control_decision: None | **Fail** | Returning "None" here won't break anything, but it should probably be fixed |
| 7 | test_make_lidar_decision | Class: DecisionMaker Method: _make_lidar_decision | lidar_scan: [] | stop_robot: False | stop_robot: False | **Pass** | |
| 8 | test_make_lidar_decision | Class: DecisionMaker Method: _make_lidar_decision | lidar_scan: [[60, 80, 110]] | stop_robot: False | stop_robot: False | **Pass** | |
| 9 | test_make_lidar_decision | Class: DecisionMaker Method: _make_lidar_decision | lidar_scan: [[90, 100, 70]] | stop_robot: True | stop_robot: True | **Pass** | |

# Screenshots

test_make_video_decision fails because of Step 6:



With Step 6 commented out, all tests pass: