

Lab Report 9

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March 19th, 2021

Summary: Hours Spent: 11 hrs

Monday: (2 hrs) Attempted implementing a while loop to handle rotations after my conversation with the others. I do not know how it could work seeing as I cannot get any new updated sensor readings from the robot from within the while loop.

Wednesday: (2 hrs) Corrected my errors I built up from adding the while loop. I did not have a recently updated file on hand. I decided to create a github repository for this so I do not need to worry about having backups on hand. This also allows for easy collaboration. I went through some of the tutorials finally since I have only used github one other time, and all I did was edit a friends file.

Thursday: (3 hrs) I changed the logic around so that it worked smoother with the XY coordinate system. It's taking roughly 5-10 minutes to test each change because you mostly see the changes near the end of the course.

Friday: (4hrs) A lot of trial and error today. I am trying to swap everything back to just moving 10 inches and not worrying about X and Y for anything but finding the current square my robot is in. This took longer than expected due to the length of each run. I had a brilliant idea of having the robot change the direction of rotations each square it is in so that near the end of the course it can make up for the error the IMU is experiencing. There are some bugs still though.

Next Week:

Put simply next week I want to finish. My robot just needs camera readings since I already have the logic for triangulation waiting to be tested in my mass of logic. I agreed to help Zachary out with the logic of making the robot move accordingly. In return he will help me get some camera readings. I have a lot of quirks to fix but with some luck I will be done.