

Epsilon Group

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EECS 376/476 Mobile Robotics

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Lab 3: A Path Service

We changed the speed from 1 to 0.3 for both spinning and translating in the real Kobuki robot. We also had to change the command topic from `/robot0/cmd_vel` to `/cmd_vel` for the real Kobuki robot. The difference in behavior was minimal, the simulation was fairly accurate to the real-world path. Also, we had to turn the robot around by hand when executing the path because the space we have in the lab is not as big as the simulation maze.

Pointer to github code: <https://github.com/Trent0881/mr376lab/tree/master/lab3>

Link to youtube video: <https://youtu.be/UHJfY4ECMCI>