Software Development Project

Final Presentation

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Introduction

Challenges
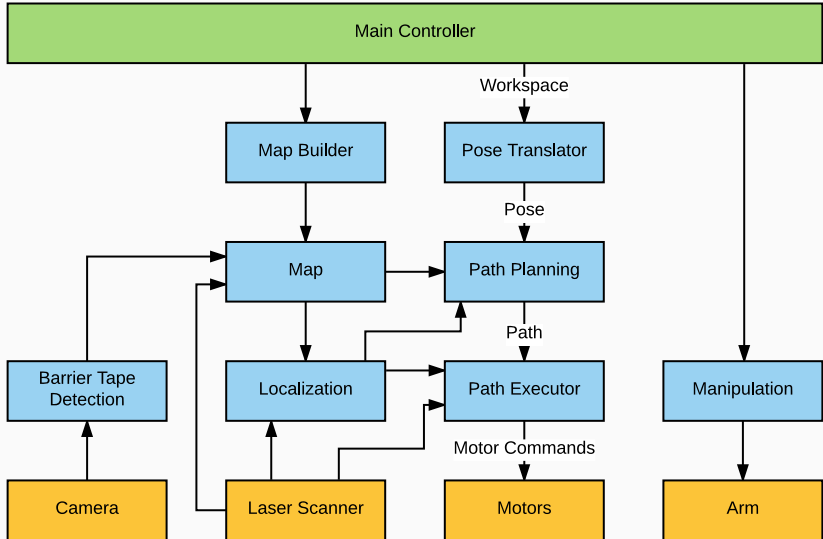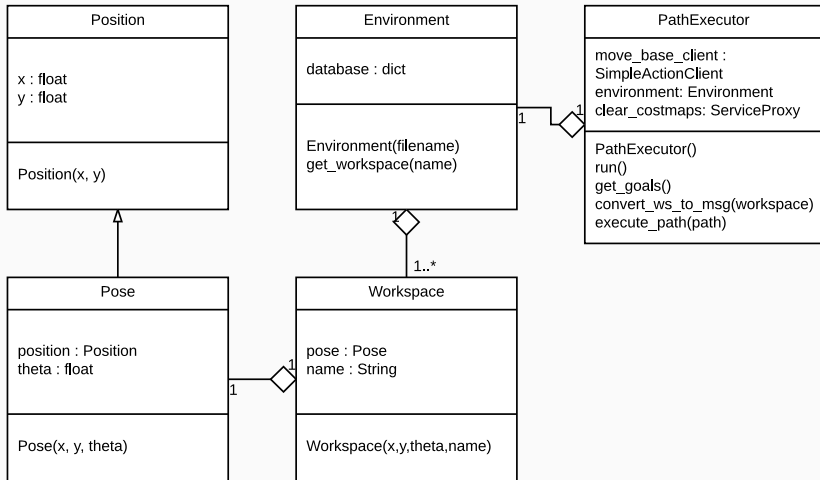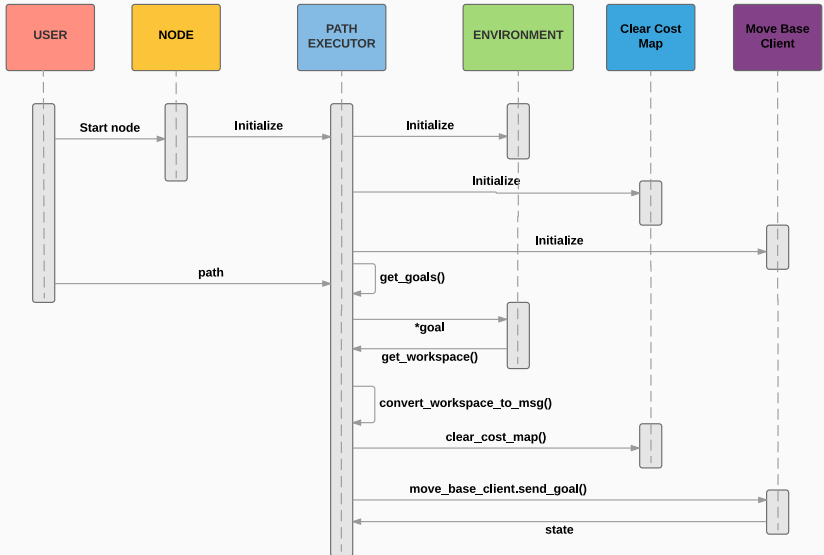
Robot Operating System (ROS)

Approach

Realization

Results

Class Diagram

Position

x : float
y : float

Position(x, y)

Environment

database : dict

Environment(filename)
get_workspace(name)

PathExecutor

move_base_client :
SimpleActionClient
environment: Environment
clear_costmaps: ServiceProxy

PathExecutor()
run()
get_goals()
convert_ws_to_msg(workspace)
execute_path(path)

Pose

position : Position
theta : float

Pose(x, y, theta)

Workspace

pose : Pose
name : String

Workspace(x,y,theta,name)

1..*

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Sequence Diagram

Conclusions

Conclusions

Future Work