

Progress report week 41

This week we have completed assignment 1 including all the milestones. We also began working on assignment 2 but didn't finish milestone 2.1.

During the first lab we encountered problems in running our code since neither the simulator nor running the program on the robots worked from our workstation. Since the first milestones could be completed by simple copying the code in the description we focused on understanding the syntax and how the FSM's worked.

On the second occasion, we started with trying to run our file `Assignment_1_3.py` which included the previous code from 1.2 and 1.1 plus new functions and states for 1.3 but encountered problems since there was information missing this time in the description. We soon found this through the returned exception in the terminal when running the program on a robot. After adding the missing states to the FSM the program ran perfectly on the robot.

We then began working on Assignment 2 and milestone 2.1. We started by designing a state diagram but encountered problems when trying to implement transitions to properly execute the walk – stop – turn movement. Our next challenge is to find a way to make the robot walk for a set amount of time or distance before transitioning into the next state. We have some ideas which we are working on implementing involving the World model key “time”.