

Minutes test meeting 29-05

Test issues

- Pico drives backwards due to no odometry reset
- Program crashes at wall merging (probably due to array size in recursive function)
- Wall avoidance trough door is too tight. Keeps repositioning in door, does not drive trough.
- Program stops after emergency, does not plan again
- Pico plans a path trough walls because it drives on lrf data only.

Todo

- Finish localization → **Martijn + Jeroen**
- Change wall find arrays to a vector → **Ruben**
 - Check if recursion now works with lot of small objects in sight
- Reset odometry when starting a new path from 0,0 → **Bram**
- Let RRT algorithm produce orientation of path → **Ruben**
- Prevent pico from being stuck in a door due to wall avoidance → **Marcel**
- Change FSM to work with the emergency situation (gets stuck at goalAvoid now) → **Bram**
- Set control input to zero instead of nan when position is reached in one direction
- Recognition of obstacles which are not in the map + add them to the map