Feature #6598

Data Recorded in Aveleda with AgRobv16 v2 (23-07-2020)

Added by Luis Santos 7 days ago. Updated 7 days ago.

Status:	In Progress	**Start date:**	
Priority:	Normal	**Due date:**	
Assignee:	Luis Santos	**% Done:**	0%

Description

We recorded all sensors available in this robot:

1. Frontal Stereo Camera (ZED) (with Depth Image)
2. Frontal Fisheye Stereo Camera (Intel Real Sense)
3. Sideway Stereo Camera (ZED)
4. Flir Thermal Camera
5. IMU data
6. GNSS Data
7. Wheel Odometry
8. Visual Odometry (Intel Real Sense)
9. Velodyne

Bag aveleda_2020-07-23-09-42-25.bag:

- **Path**: navigation on one line in both directions. The returning path should be similar to the starting path. The robot reached the end of the line but did not reach the starting point in the return path, so we can consider this bag to contain about 1.5 lines of data.

- **Velocity**: 0.5 m/s (started at 0.4 m/s and finished at 0.6 m/s).

Bag aveleda_2020-07-23-11-13-01.bag.active

The remote computer ran out of battery, and we are out of memory to verify the content of this bag. If the data is not damaged, we expect to have:

- **Path**: navigation in one line in both directions. The returning path should be similar to the starting path, as well as the starting point, which should be the same as the finishing point.
- **Velocity**: 0.6 m/s

Bag aveleda_2020-07-23-13-36-08.bag

- **Path**: navigation in two lines. The robot started in Line 1 and returned by line 2. The computer ran out of memory near the end of line 2. The robot was always closer to the right vegetation wall.
- **Velocity**: 0.6 m/s

Afternoon Speeding Bags:

These bags are still on the AgRoBv16 v2 computer. We have two bags:

First:

- **Path**: navigation in two lines. The robot started in Line 3 and returned by line 4. The U-turn was performed before the end of line 3, as there is a zone with no vine-trees. The robot was always closer to the right vegetation wall. The starting point is similar to the finishing point.
- **Velocity**: 1 m/s

Second:

- **Path**: navigation in one line in both directions. The returning path should be similar to the starting path, as well as the starting point, which should be the same as the finishing point.
- **Velocity**: 1 m/s

Checklist

- ☐ Copy all the bags to the external HDD
- ☐ Upload compressed bags to the vcriis server

Subtasks

Related issues

History

Updated by Luis Santos 7 days ago

#1

- **Description** updated (diff)

Updated by Luis Santos 7 days ago

- **Status** changed from *New* to *In Progress*
- **Assignee** set to *Luis Santos*

Updated by Luis Santos 7 days ago

- **Description** updated (diff)