

SBot Common Interface

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Wednesday 18th Jan 2006

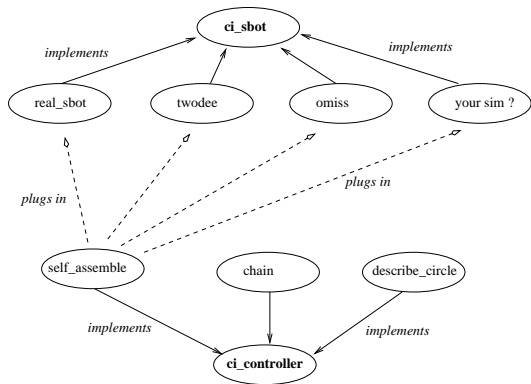
Reasons for Developing SBot Common Interface

- Code portability between platforms.
- Code reuse between researchers.
- Minimize errors in porting from simulation to real robot.
- Quick prototyping / testing.
- Library of standard functions would allow high level controller design.

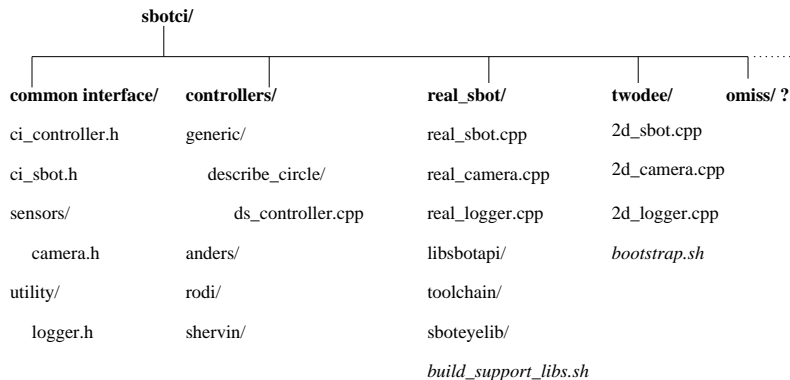
Design Principles

- Ability to add further implementations easily
- Controller coding should not require expertise in a particular implementation
- Everything in one place - implementation, controllers, support libs
- Very few restrictions enforced between implementations (different build systems allowed)
- Easy to use - get up and running quickly

Class Diagram



Directory Structure



Going Forward

- Still plenty to do - meta sensors etc. Input and testing / working with system needed.
- Use this experience to get to the same point quickly in future projects
 - Epucks
 - Swarmanoid
- Work in progress
 - Gripping
 - Waiting