Tasks & Teleop Exercise

Fall 2021
Class 4

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Plans for Today

- Each team
  - discuss tasks proposed by the team members
  - select top three proposed tasks
  - present top three tasks to the entire class
- While two teams discuss tasks, the third team will try implementing their teleoperation code on the robot

Next Three Classes are Guest Lectures with MS Teams

- Caregiving involves stakeholders and subject matter experts
  - Your primary expertise will be technical, but that's not enough
  - Talking with others is one of the first things you should do
- Guest lectures will provide important perspectives
  - Healthcare professionals: Dr. Vy Nguyen (occupational therapist (OT))
  - Healthcare researchers: Prof. Wendy Rogers and Dr. Travis Kadylak
  - People with disabilities and their caregivers: Henry and Jane Evans
- All of the guest lecturers
  - Have used the Stretch RE1
  - Collaborated on the same project with the Stretch RE1
  - Will have distinct perspectives
    - https://en.wikipedia.org/wiki/Rashomon
    - https://en.wikipedia.org/wiki/Rashomon_effect

Image from https://en.wikipedia.org/wiki/Rashomon#/media/File:Rashomon_poster_2.jpg

Hopeful Plan

- Three robots for your teams by our class on Wednesday, September 22
- Waiting on Georgia Tech procurement.
- Major lab demo for a sponsor on September 28

Changes to the Schedule

Make sure to look at the revised schedule.

Important: change to proposal presentation deadline

Get Started on Your Slides

Use the midterm proposal rubric as a guide

Look at example of final presentation from last term

Go to the robot’s home directory for code to modify

$ cd

$ ls | grep py

prof_kemp_teleop_20210901.py

team_red_teleop_20210901.py

team_green_teleop_20210901.py

team_blue_teleop_20210901.py

```
        print('finished calibrating the robot')
    else:
        if first_home_warn:
            print('press the start button to calibrate the robot
        else:
            first_home_warn = False

#########################################
## Prof. Kemp test
def prof_kemp(robot,controller_state):
    lift_height_m = 0.75 # lift height goal in meters
    auto_robot = controller_state['left_button_pressed']
    if auto_robot and robot.is_calibrated():
        robot.lift.move_to(lift_height_m)

# ############################## MAIN ##################################
use_head_mapping=True
use_dex_wrist_mapping=False
use_stretch_gripper_mapping=True

def main():
    global use_head_mapping, use_dex_wrist_mapping, use_stretch_
```