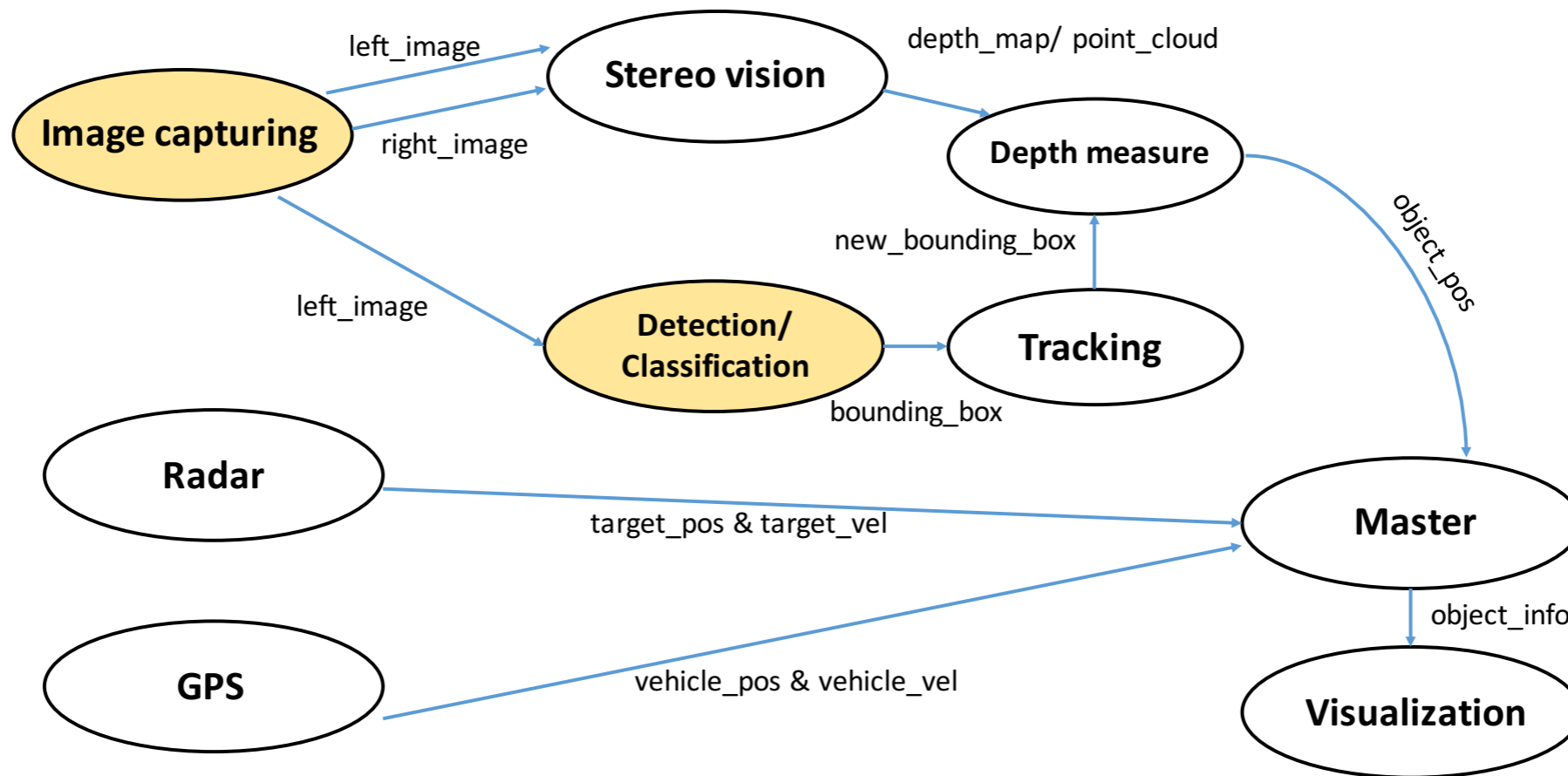


Progress Review 11

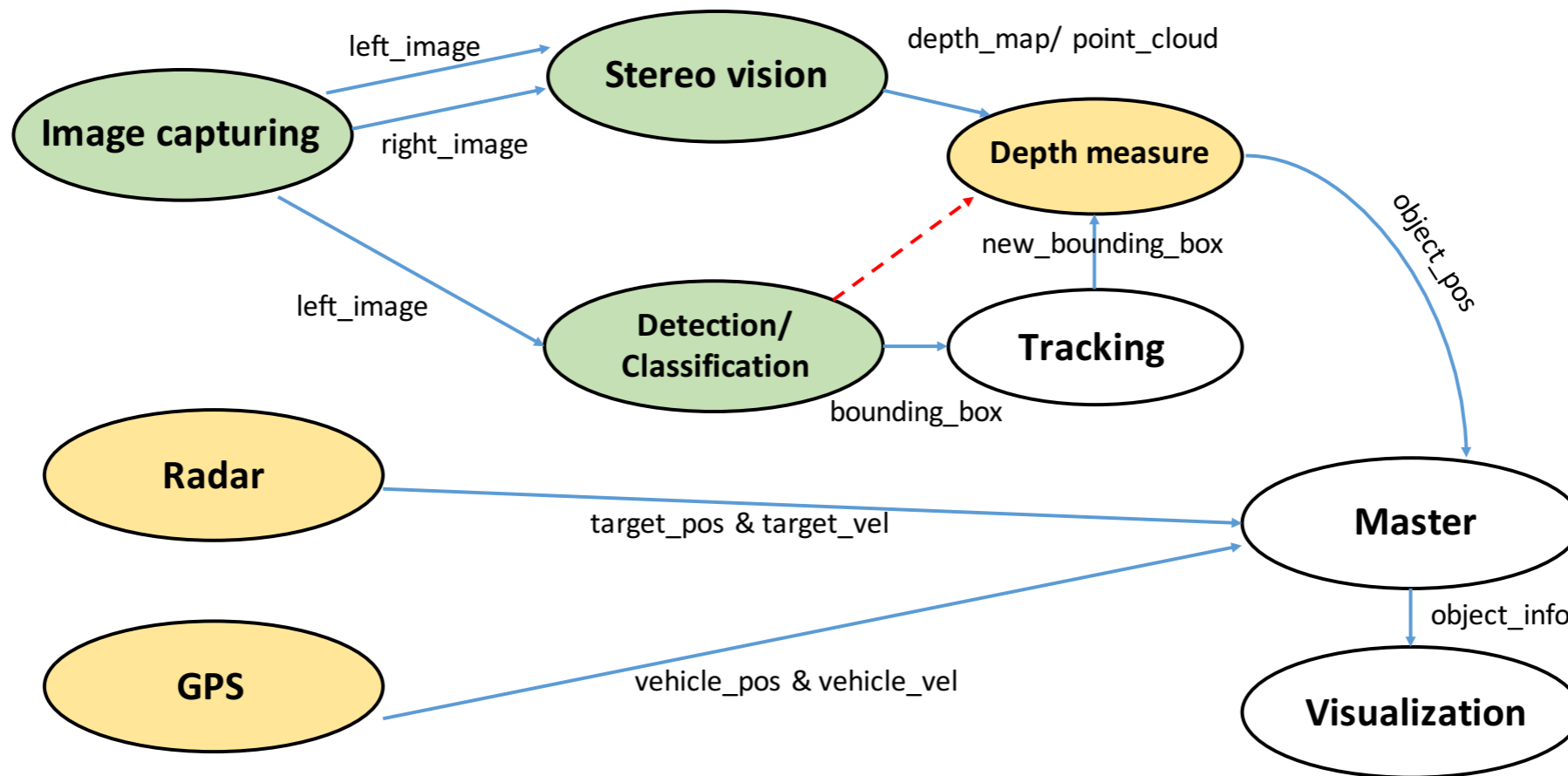
Team Aware

Amit Agarwal, Harry Golash, Yihao Qian, Menghan Zhang, Zihao Zhang

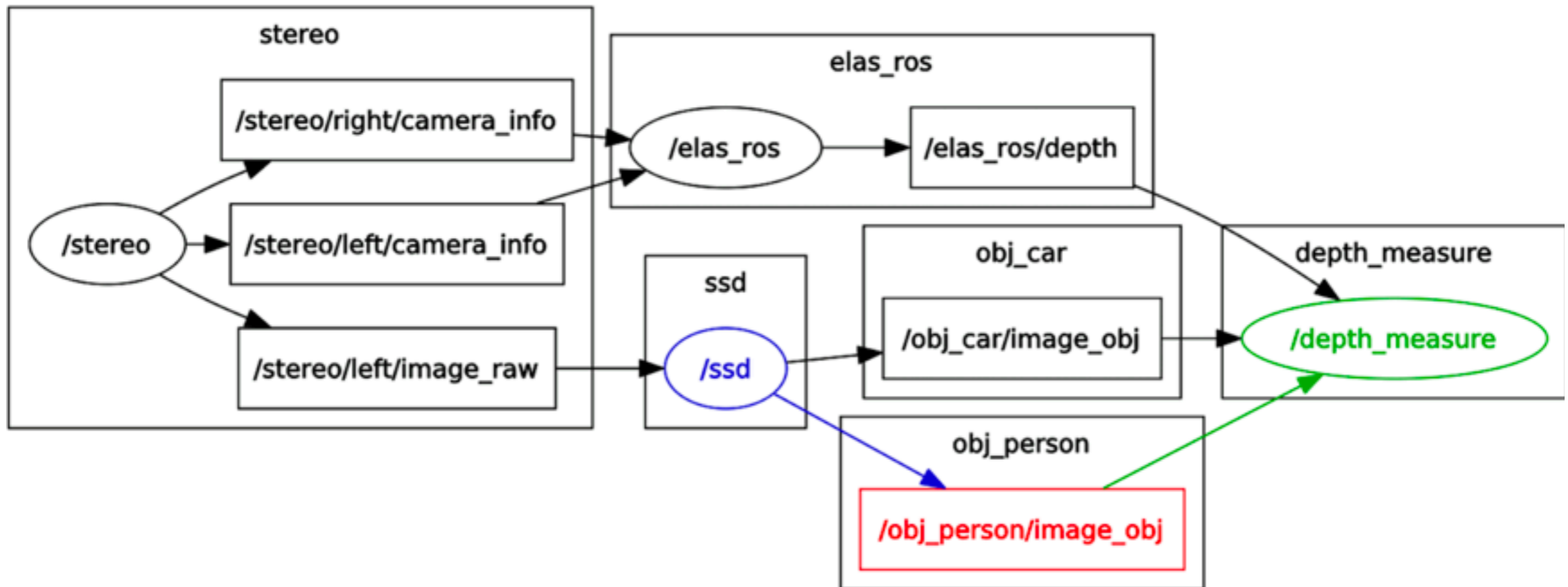
ROS Structure



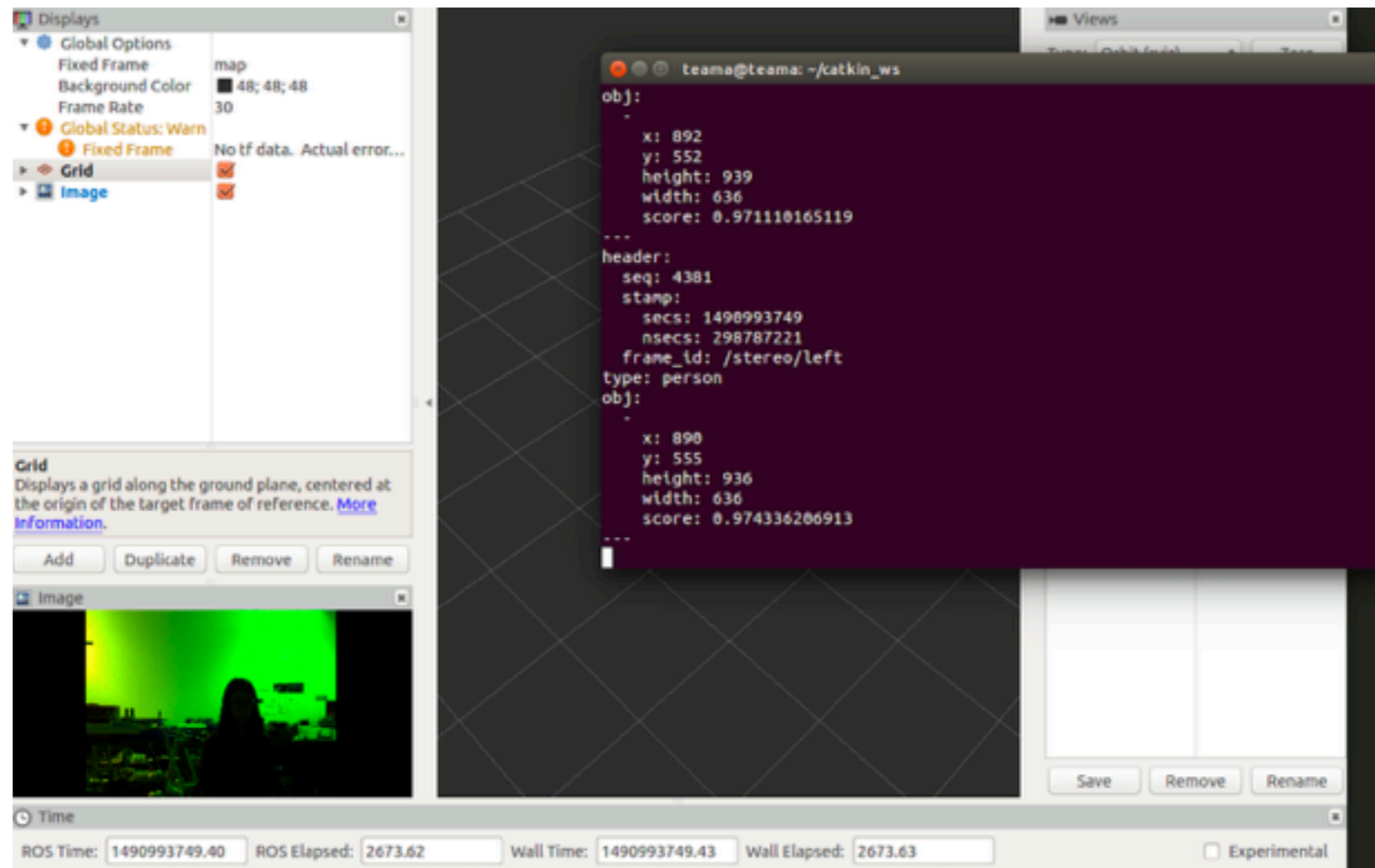
ROS Structure



Vision



Object Detection in ROS



The screenshot displays the ROS GUI interface. On the left, the 'Displays' panel shows settings for 'Grid' and 'Image'. The 'Image' panel shows a camera feed with a green overlay. The 'Time' panel at the bottom shows ROS Time: 1490993749.40, ROS Elapsed: 2673.62, Wall Time: 1490993749.43, and Wall Elapsed: 2673.63. The 'Views' panel on the right shows a terminal window with the following output:

```
teama@teama: ~/catkin_ws
obj:
-
  x: 892
  y: 552
  height: 939
  width: 636
  score: 0.971110165119
---
header:
  seq: 4381
  stamp:
    secs: 1490993749
    nsecs: 298787221
  frame_id: /stereo/left
type: person
obj:
-
  x: 890
  y: 555
  height: 936
  width: 636
  score: 0.974336206913
---
```

Radar

- Live visualization in RViz
- Ready to integrate
- ROS setup to get data

Future Goals

- Visualize stereo vision data
- Complete and integrate ROS pipeline
- Radar filtered data live visualization
- Sensor Fusion improvement attempt
- Start testing again (Test plan experiments)