

MCH4202 Project 1: Teleoperation

By using the inverse kinematics of the differential drive robot and CoppeliaSim-MATLAB teleoperate the mobile robot given in the scene by using keyboard. The keyboard inputs must adjust the linear and angular velocities of the robot in body frame.

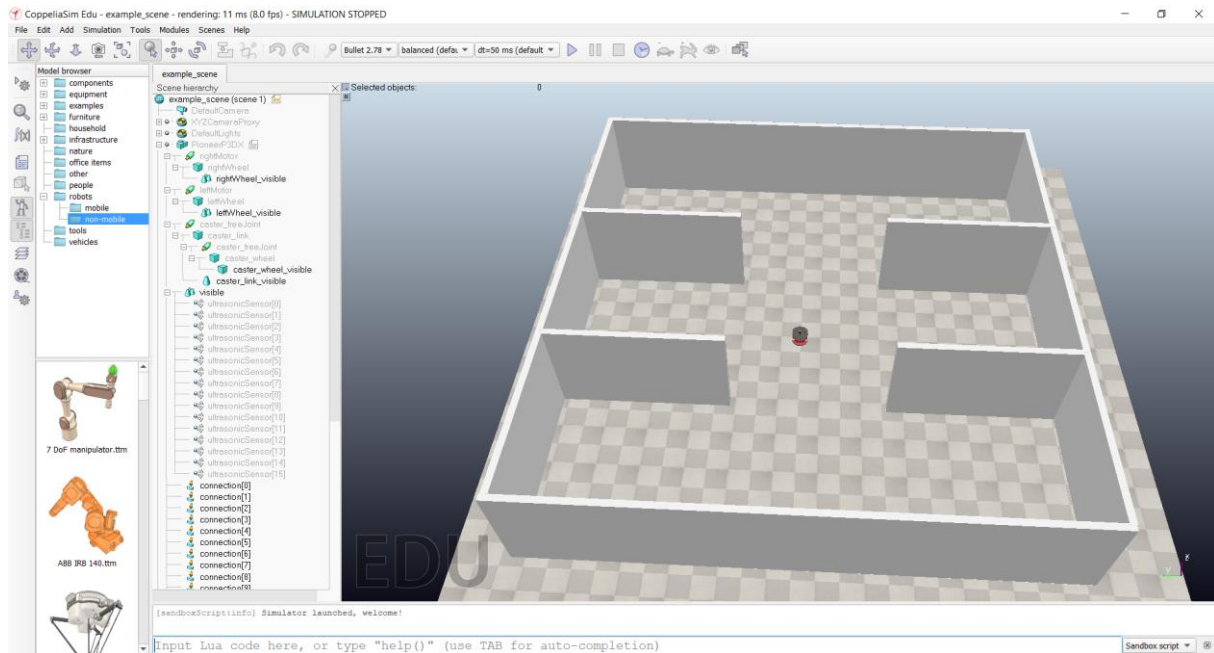


Figure 1 CoppeliaSim Scene

Note 1: The projects will be done in groups of four student with each student's responsibility in the project clearly stated.

Note 2: The students may use the project template files which include the CoppeliaSim scene and MATLAB scripts.