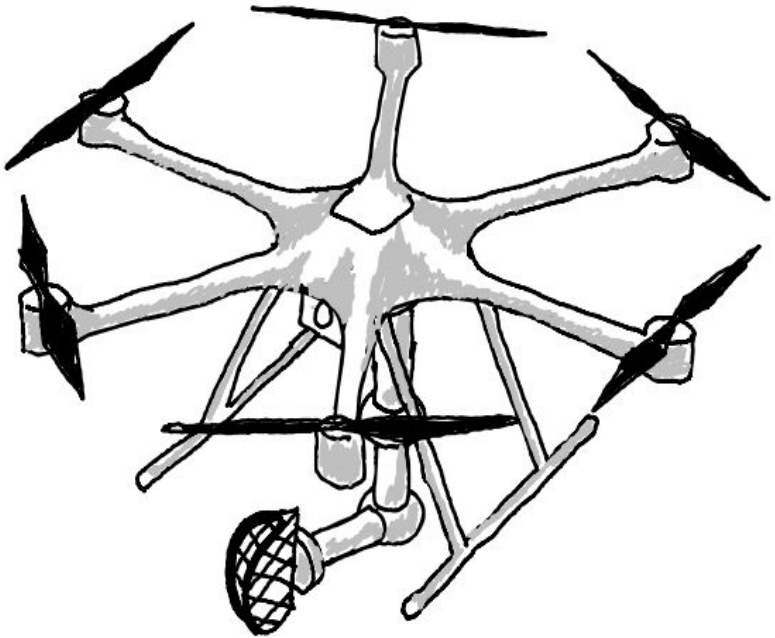
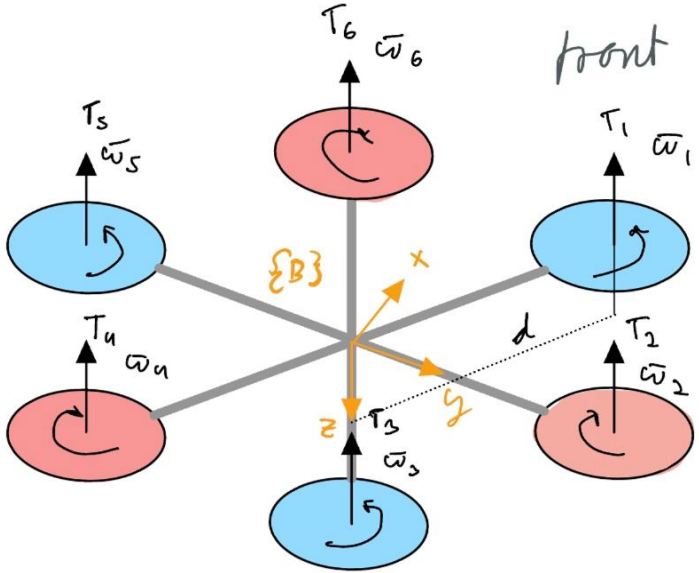
ELE306 Gruppe 6: Magnus Anthun, Eskil Digernes, Stian Flåten, Joakim Johansen, Asbjørn Tjensvold

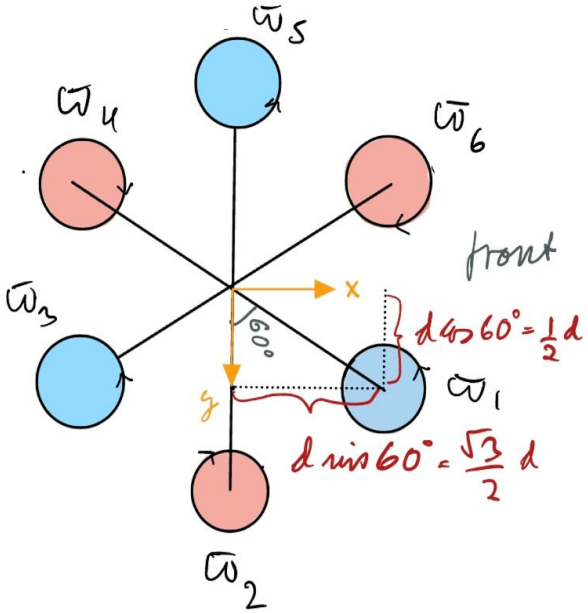
Robot design challenge 6: **Hexacopter for picking fruits from trees**

Midlertidig design





Kinematisk og matematisk modell



$$T = b\varpi_i^2, \qquad i = 1, 2, 3, 4, 5, 6$$

$$\tau_x = db(\varpi_2^2 - \varpi_5^2 + \tfrac{1}{2}(\varpi_1^2 + \varpi_3^2 - \varpi_4^2 - \varpi_6^2))$$

$$\tau_y = db\tfrac{\sqrt{3}}{2}(\varpi_1^2 + \varpi_6^2 - \varpi_3^2 - \varpi_4^2)$$

$$\tau_z = k(\varpi_1^2 + \varpi_3^2 + \varpi_5^2 - \varpi_2^2 - \varpi_4^2 - \varpi_6^2)$$

T: kraft

b: oppdrift konstant

ϖ: rotorhastighet

i: antall rotorer

d: lengde fra senter til rotor

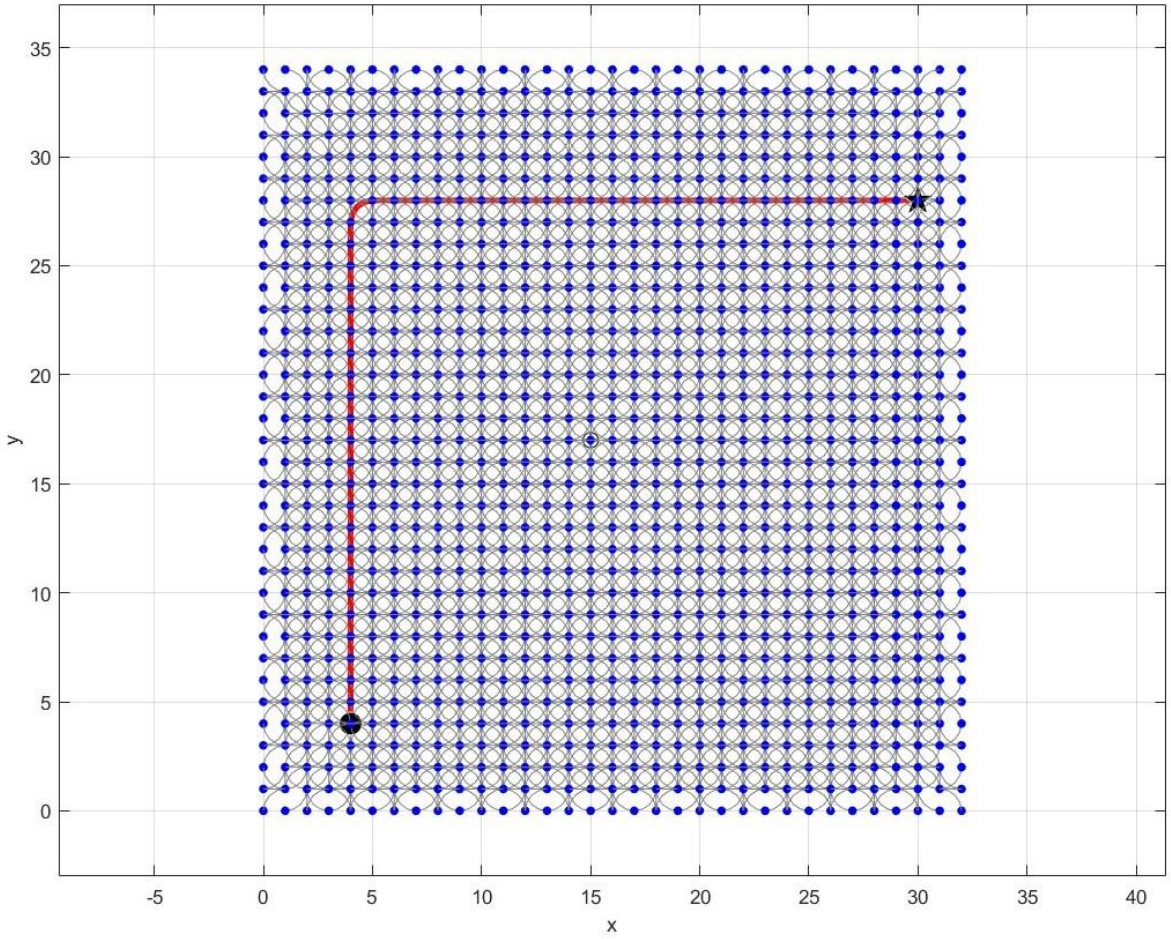
τ: dreiemoment

k: lufttetthet

$$\begin{pmatrix} T \\ \tau_x \\ \tau_y \\ \tau_z \end{pmatrix} = \begin{pmatrix} -b & -b & -b & -b & -b & -b \\ \frac{1}{2}db & db & \frac{1}{2}db & -\frac{1}{2}db & -db & -\frac{1}{2}db \\ \frac{\sqrt{3}}{2}db & 0 & -\frac{\sqrt{3}}{2}db & -\frac{\sqrt{3}}{2}db & 0 & \frac{\sqrt{3}}{2}db \\ k & -k & k & -k & k & -k \end{pmatrix} \begin{pmatrix} \varpi_1^2 \\ \varpi_2^2 \\ \varpi_3^2 \\ \varpi_4^2 \\ \varpi_5^2 \\ \varpi_6^2 \end{pmatrix} = A \begin{pmatrix} \varpi_1^2 \\ \varpi_2^2 \\ \varpi_3^2 \\ \varpi_4^2 \\ \varpi_5^2 \\ \varpi_6^2 \end{pmatrix}$$

Lattice Planner

- Svingradius på 10 cm
- Frukthage størrelse 10 m^2
- Flatt område (toppen av trær)
- For ikke-holonomiske kjøretøy



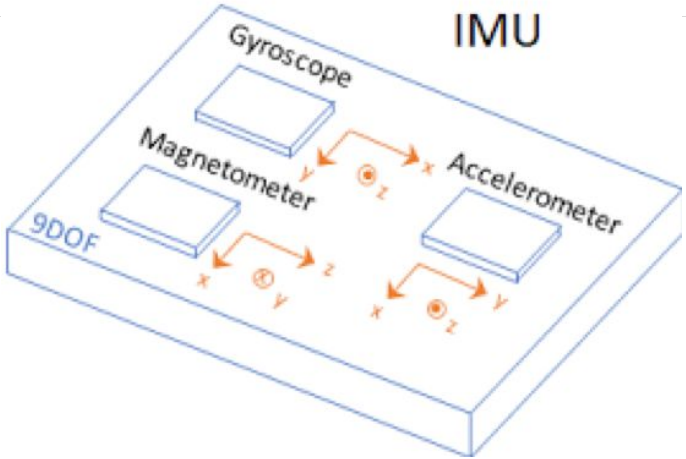
Komponentar og styring

-Enkoder → rotorhastighet

-IMU → orientering

-GPS → posisjon

-3D kamera → detektere frukt



Neste steg

- Simulering i MATLAB og Gazebo
- Kinematisk modell for robotarm
- Implementere i ROS