Mobile Robotics Assignment 2  
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In this project the robot uses ultrasonic sensor to measure distances, colour sensor for detecting white colour and servo motor for the grabber.

The robot starts moving forward until it detects obstacle or a wall. Then it turns right and continues that way it no obstacle is in its way, but if the route is blocked, the robot turns 180 degrees and proceeds that way. Same time driving times are stored in milliseconds and turns are also stored in memory.

The robot continues this behaviour until it recognises white colour. Then the robot moves forward until it reaches block or another object it is supposed to grab. Robot then turns 180 degrees and drives back home using stored drive times and turns. No sensor data is necessary at this point.

On the next page is project’s flow chart.

