

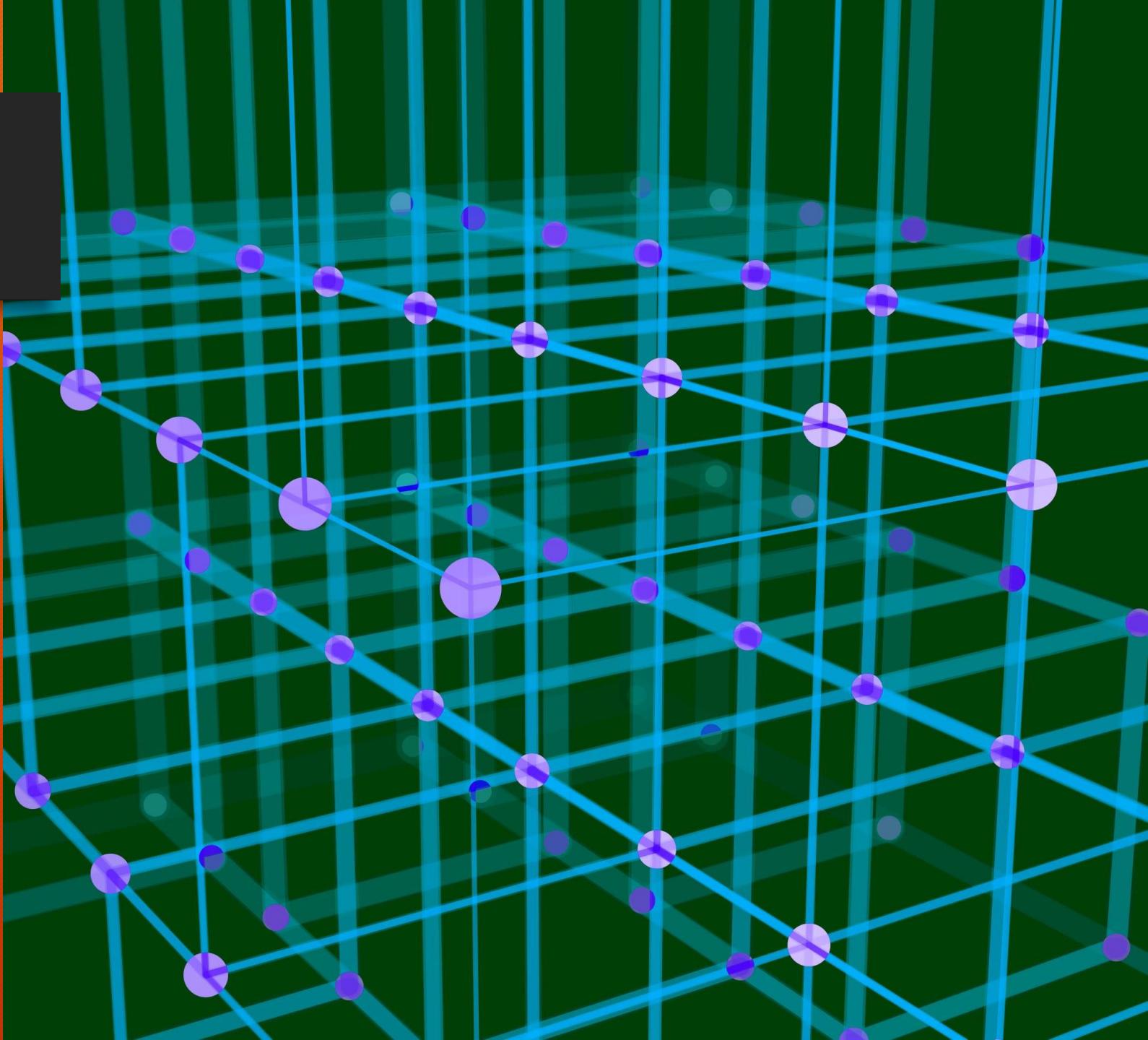
Final Presentation

Forklift with manipulator



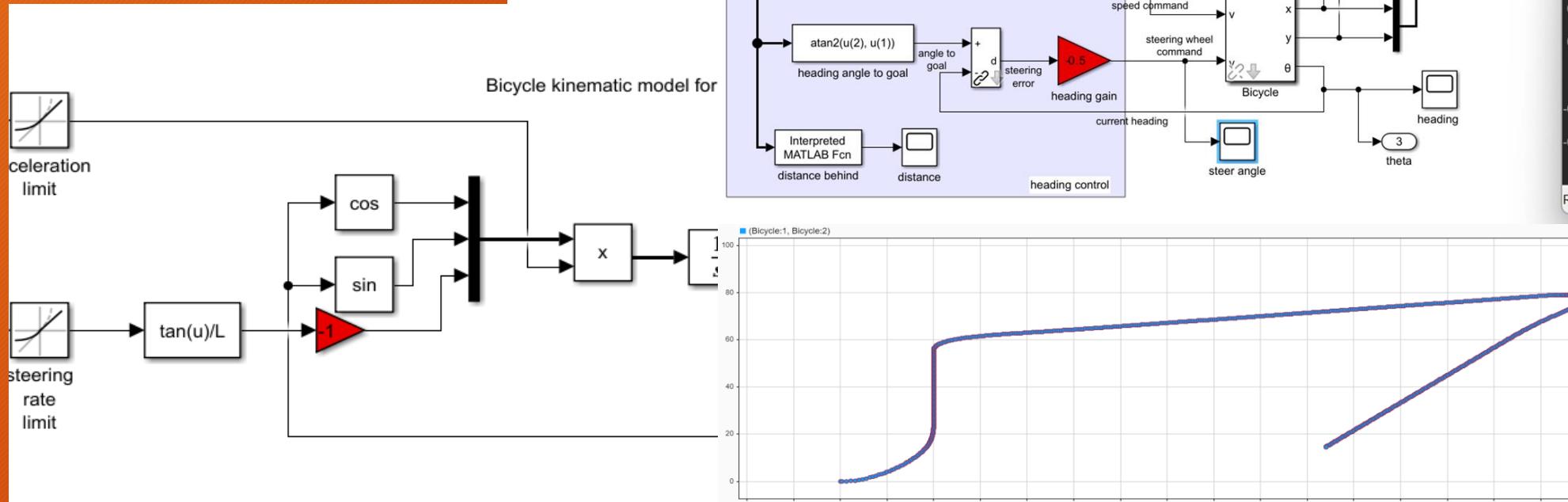
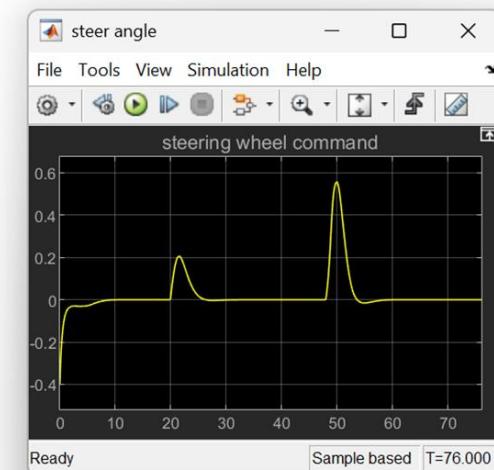
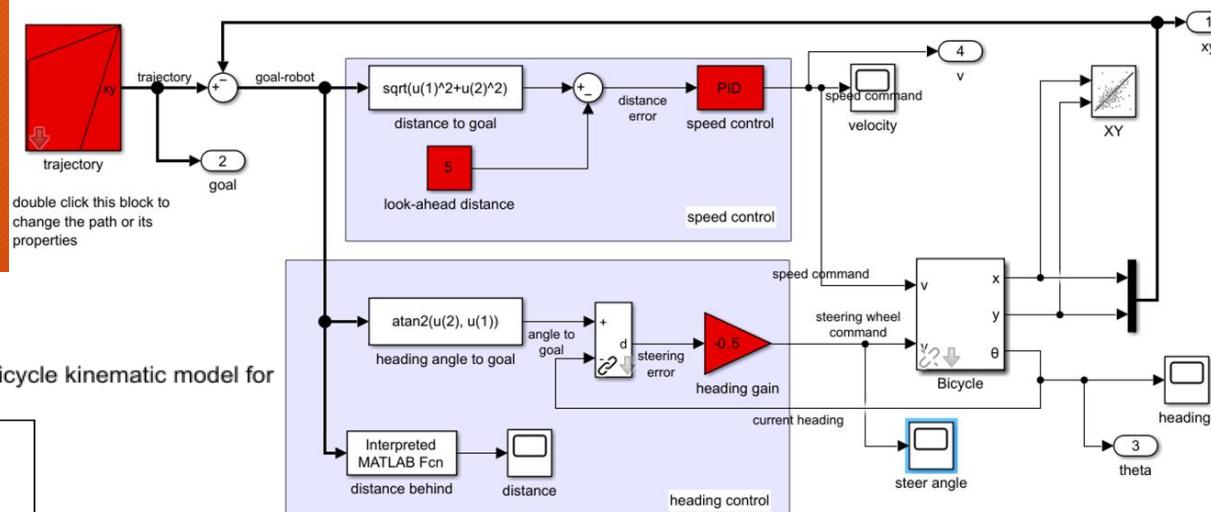
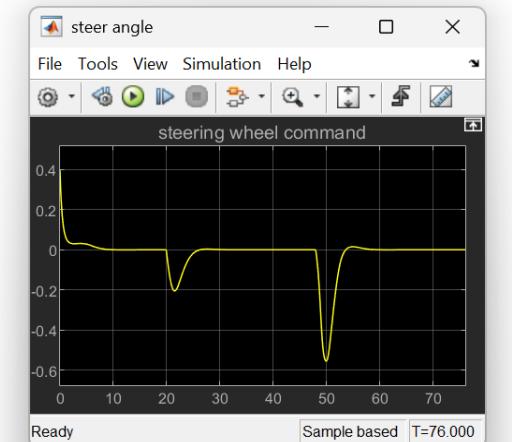
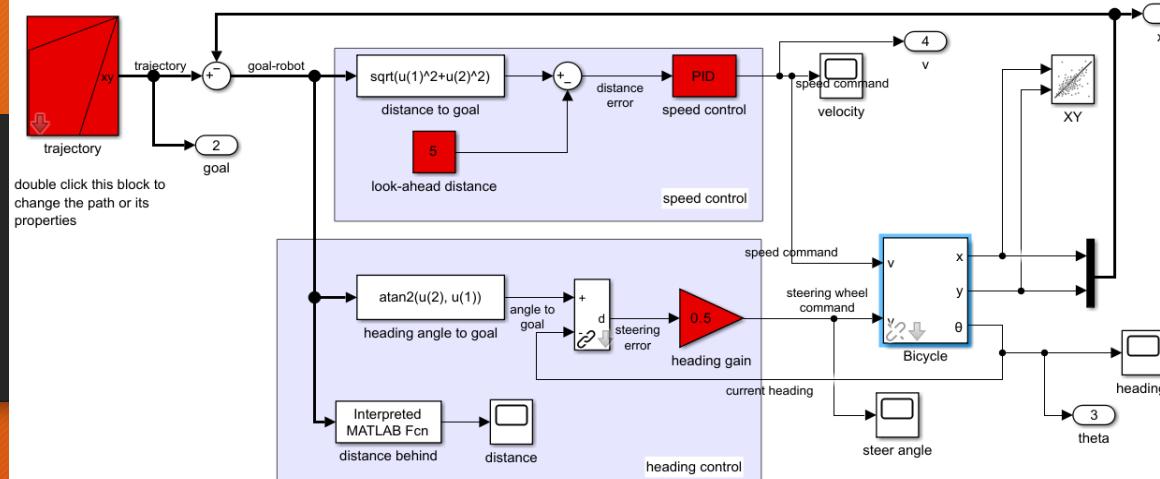
System

- Navigasjon - lattice planner
- Lokalisering - dead reckoning og et predefinert map
- Kontroll - trajectory og move to pose



Kinematikk og kontrollering i matlab

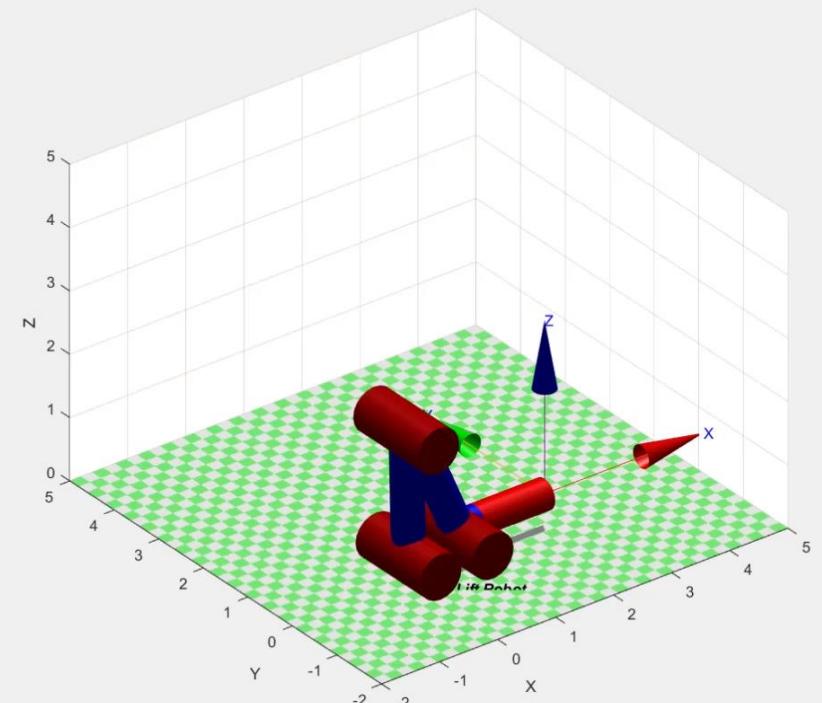
- SL_pursuit
- SL-drivepose



Simulerings av arm

- Cartesian motion (inn til pall)
- Joint motion (opp til reol)

j	theta	d	a	alpha	offset
1	q1	0	2	0	0
2	q2	0.2	2	0	0
3	q3	-0.2	0.4	0	0
4	0	q4	1.2	-1.5708	0



Simulerings i gazebo

Styring

- Joints for swinging
- Tastaturstyrt

