Software   →* End Feb 2014

- Vision

    - integrate modules in Seneka
    →*   - sensor recognition   → UGV position direct in front
                                          → Handle position

    (- repositioning UGV)

- Planning and motion

    - Reaching handle and bring back
    →* - 1 arm
    →* - 2 arm (master-slave)

    - Grasping/Release
    →* - preprogrammed motion
          - "trial and error" w. sensor feedback

    - Communication w. sensor sonde
    →* - turn trunk for handle alignment
          - deploy/fold legs

    - "Supervision"
          → State machine

Hardware

- Gripper/Handle
    - passive
    - ...

- Integration of UR-10
    - mechanical ⇒ mock up
    - electrical

- Magazine for sensor sonde
- Camera fixation
- Computer + control system
- Cabeling

? Place for computers ?