Abstract

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Robot behaviour

The task of our robot is to continuosly follow a beacon which can change a position while the robot is following it. If the distance between the robot and the beacon is sufficly small, the robot will stop. While following the beacon it is avoiding obstacles. Obstacles are represented by a shape made with a black tape on the floor. The robot uses two motors (connected to wheels) for movement, infrared sensor for localization of the beacon and color sensor for detection of obstacles.

Programming language

We will use leJos language to implement the project.