PDR Week 3

3D SLAM Rover

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Requirements

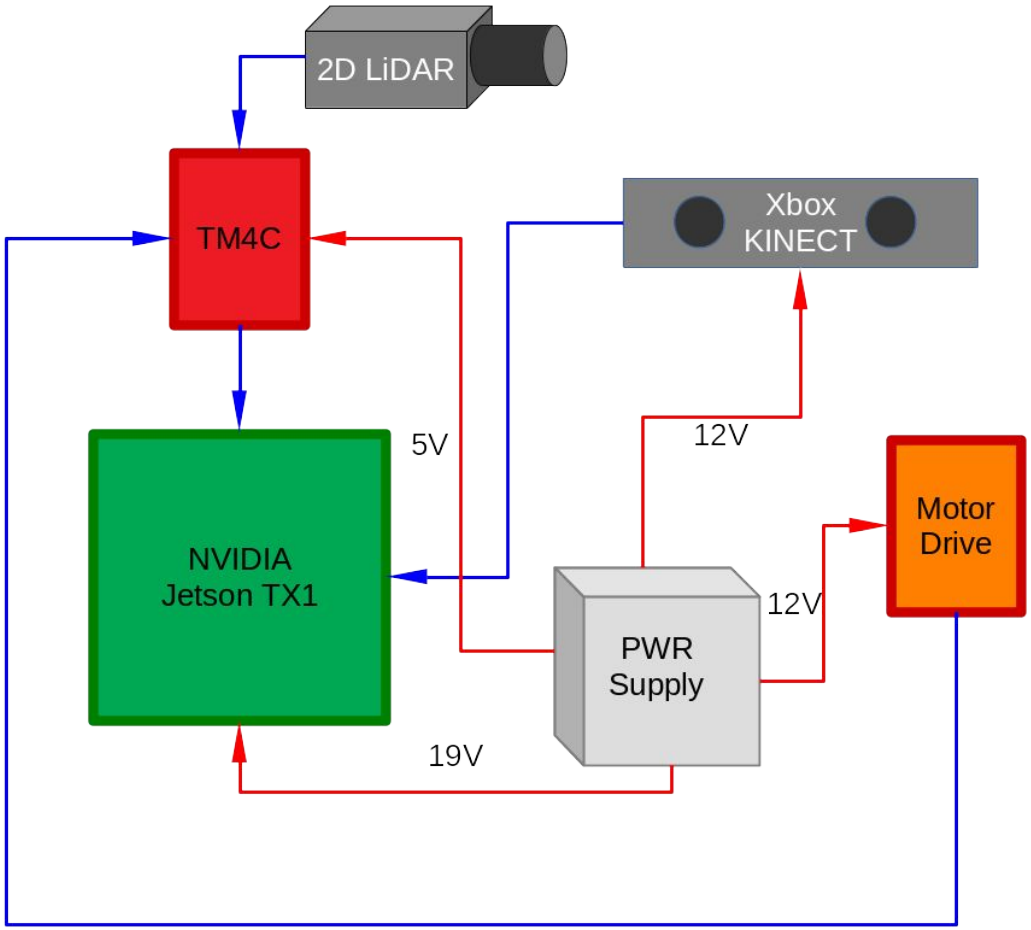
- **The design shall map unknown coordinates through exploration on passable terrain.**
  - Location of choice should not dictate mapping method, i.e. a room vs a field.
- **The design's structural capture shall be capable of producing a visual map.**
  - The scans must produce an image with the desired map.
- **The design shall be capable of 2D SLAM.**
  - SLAM shall be used to handle 2D coordinate recognition, and assist in 3D sampling.
- **The design shall be capable of 3D capture.**
  - 3D capture can be pulled from samples or from real-time/soft real-time capture.
- **The design shall be powered from an independent power supply.**
  - This power source shall provide enough power to explore, at minimum, 20 minutes of capture.

Limitations

- **The design is not confined to low light, visible image capture.**
  - High resolution 3D structural capture is used to compensate for loss of visuals under low light.
- **The design is not confined to autonomous navigation, simply the capability of such.**
  - The design will be capable of mapping and localization, but the platform may not drive autonomously as functionality of mapping is the first priority.
- **The design is not confined to real-time 3D mapping, due to limitations of price and available algorithms.**
  - Real-time 3D is sometimes limited to ability of hardware readout, and may be an unrealistic endeavor. 3D may instead be done from sampling.
- **The design is not interested in object recognition.**
  - Point clouds will be used to simply display raw data, and points on a 2D plane will only be used to determine the explored area.

Systems Engineering

Top Level Block Diagram



3D Capture

- XBox Kinect
  - Use of NIR projector and receiver for depth information.
  - RGB Camera: 640x480 @ 30 FPS
  - Depth: 320x240 @ 30 FPS
  - Allows for image overlay, with point cloud for depth

KINECT™ for XBOX 360.

SLAM

- 2D Tracking
  - Captures 2D representation for birds-eye view
  - Allows for positional data of visual tracked
  - Keeps track of previously explored territory
- 3D Tracking
  - Recognizes elevation difference in tracked territory
  - Allows for tracking regardless of incline/decline

Software Engineering

Kinect Driver

- OpenKinect
  - Apache License open-source Kinect Driver
  - Used for point cloud registration and image overlay
  - Allows for motor function of the assembly

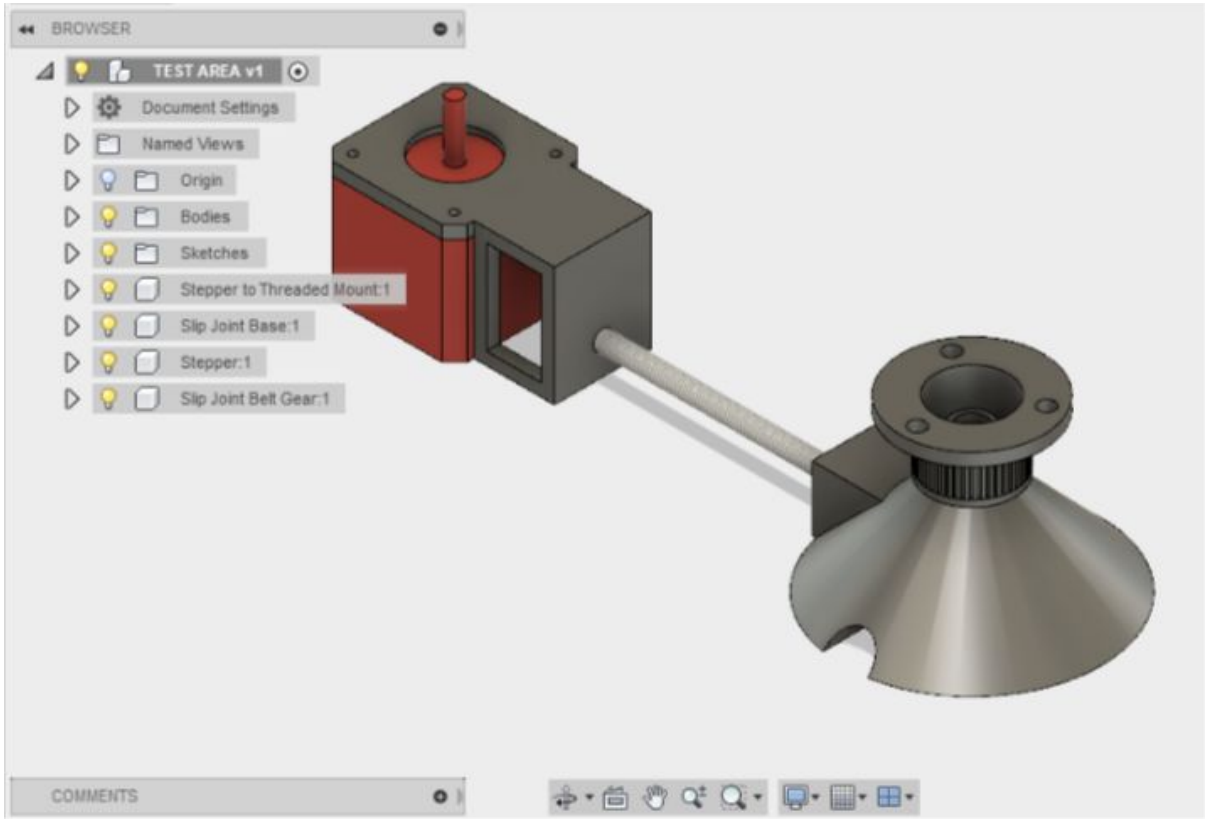
3D Rendering

- OpenGL
  - Open-source license
  - Graphics rendering framework
  - Permits 3D rendering and image overlay
- PCL
  - Permissive open-source BSD license
  - Permits structural capture and representation

Mechanical Engineering

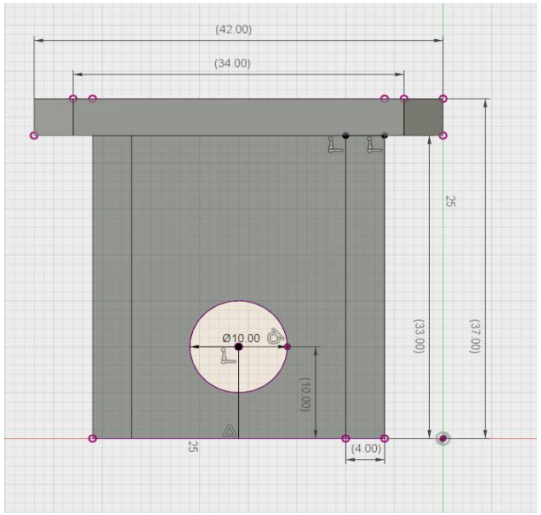
Top Level Motor Assembly

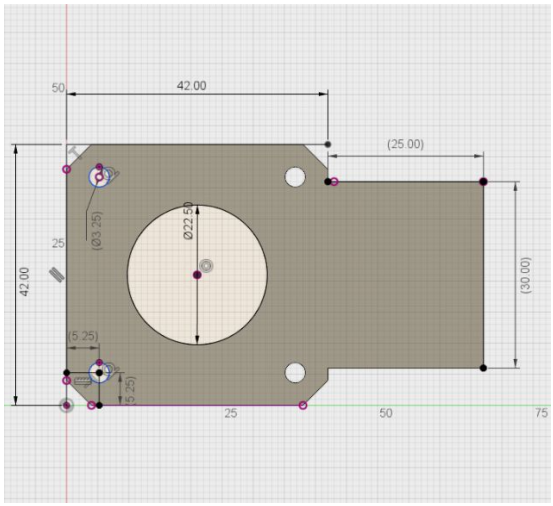
3D capture bay assembly, driven by stepper.

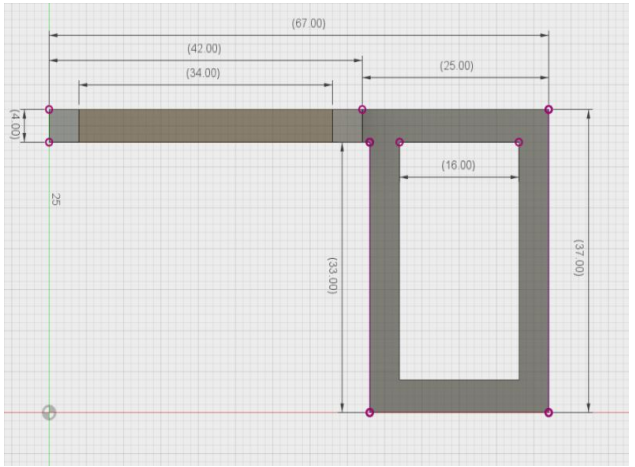


Motor Mount Assembly

Motor drive support assembly

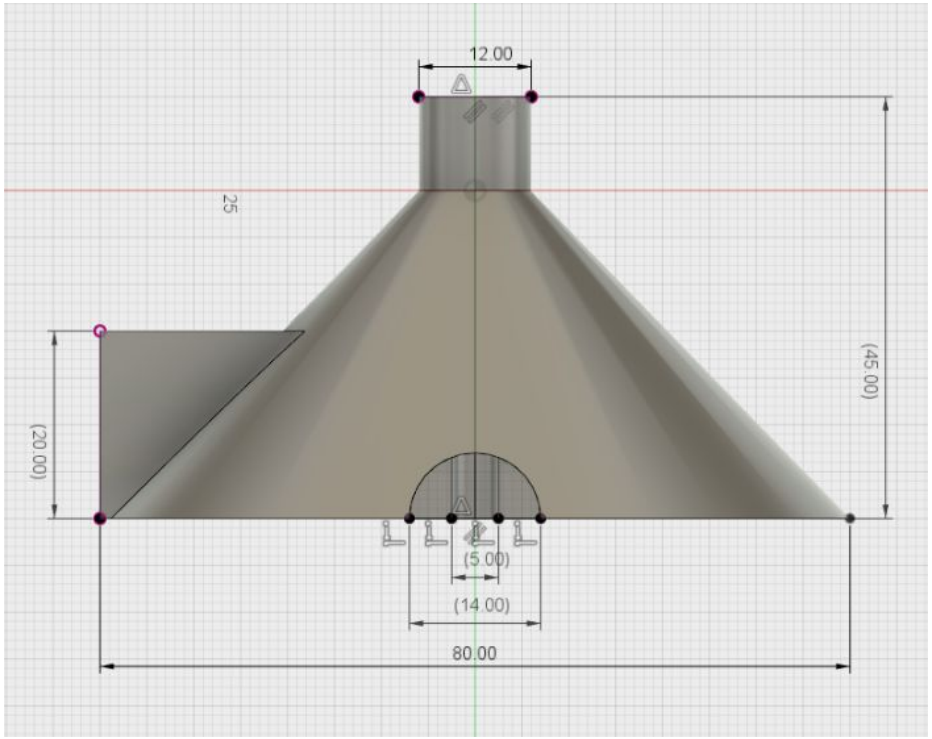


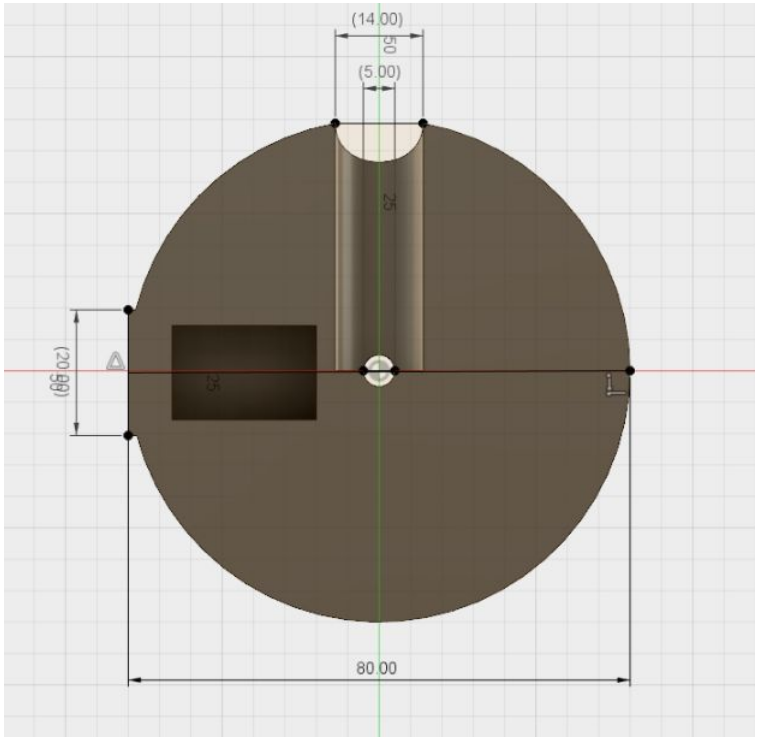




Motor Platter Assembly

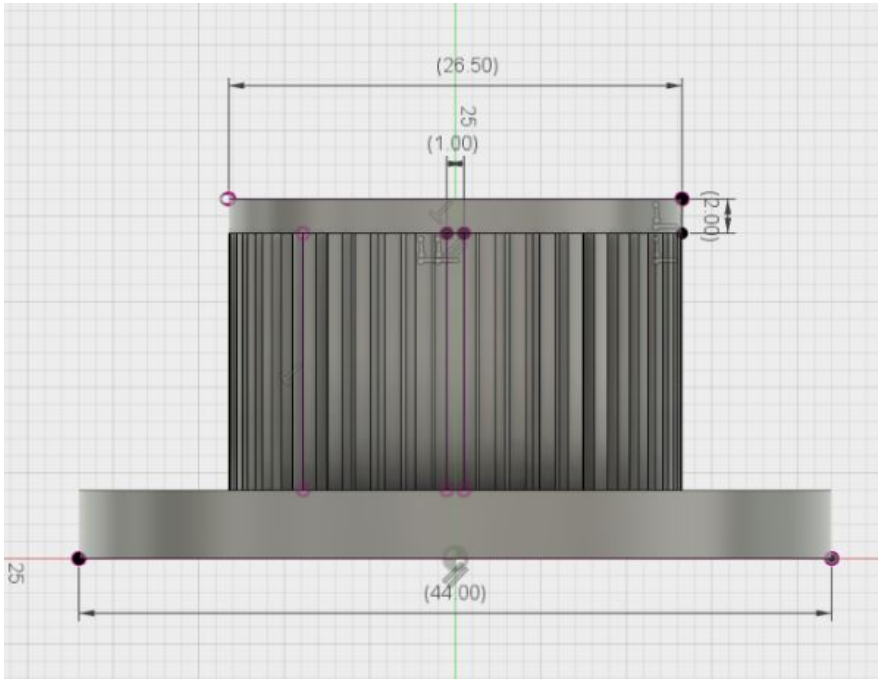
Platter support assembly

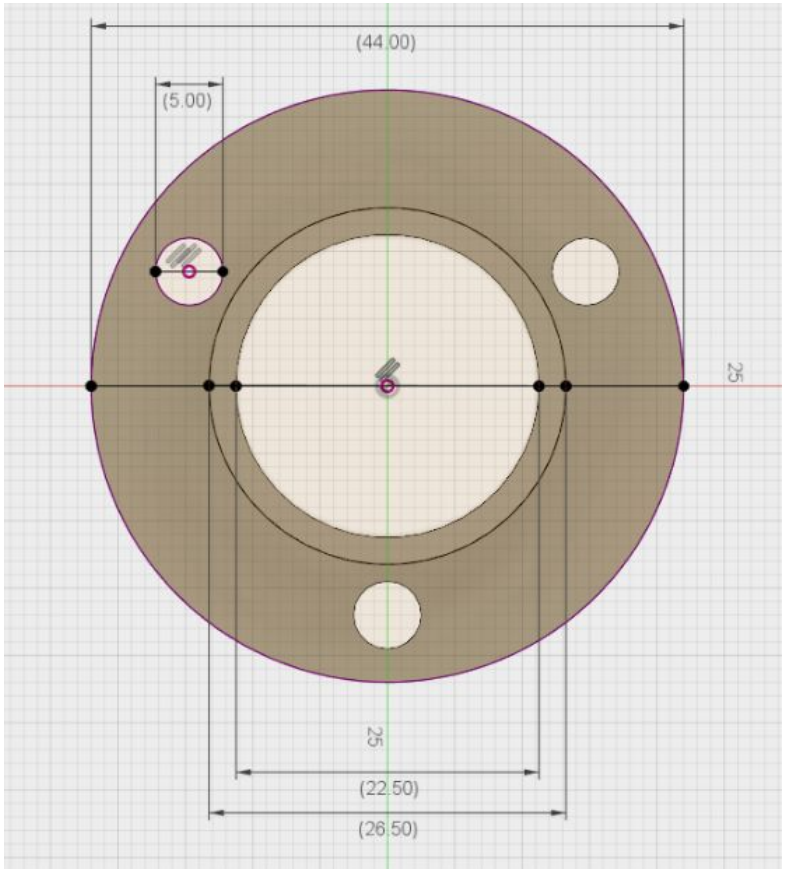




Platter Belt Ring Assembly

Gear Belt Platter Attachment

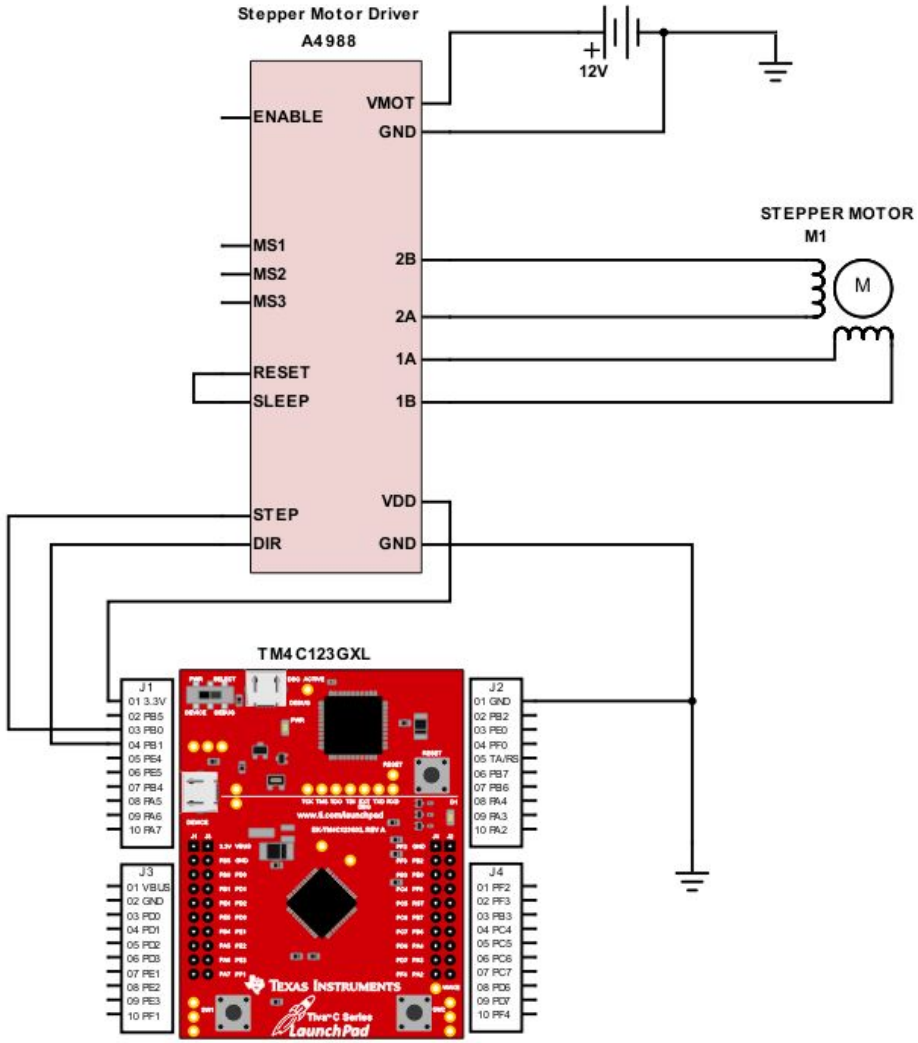




Electrical Engineering

Motor Control Circuit

A4988 Driver to TM4C



Power Supply

Devices with corresponding voltage, and current draw in amps.

DEVICE (Amps)	3v3	5v	12v	19v
TM4C		0.50		
Jetson TX1				0.80
xBox Kinect			0.50	
Motor			0.50	

Power Supply

Voltage supplies, current draw in amps, and total power in watts.

VOLTAGE	CURRENT	PWR 29.8
3.3	0	0
5	0.52	2.6
12	1.00	12
19	0.80	15.2