Design of a holonomic five legged robot

Final Report

L. Steyn
04496486

Submitted as partial fulfilment of the requirements of Project EPR400
in the Department of Electrical, Electronic and Computer Engineering
University of Pretoria

November 2017

Study leader: Dr. D. le Roux

Part 1. Preamble

This report is a description of the work I completed during the year on my final year project, Design of a holonomic five legged robot.

This report contains a copy of my approved project proposal and documentation on the technical parts of my project. These can be found in parts 3 and 4 respectively. The technical documentation contains a detailed recording of the steps taken to overcome design challenges. This includes circuit diagrams, algorithm flowcharts and test results. This section appears on the CD that accompanies this printed report.//

TABLE OF CONTENTS

Part 2.

[1]

References

[1] A. Hidayat, A. N. Jati, and R. E. Saputra, “Autonomous quadruped robot locomotion control using inverse kinematics and sine pattern method,” *IEEE*, 2017.