

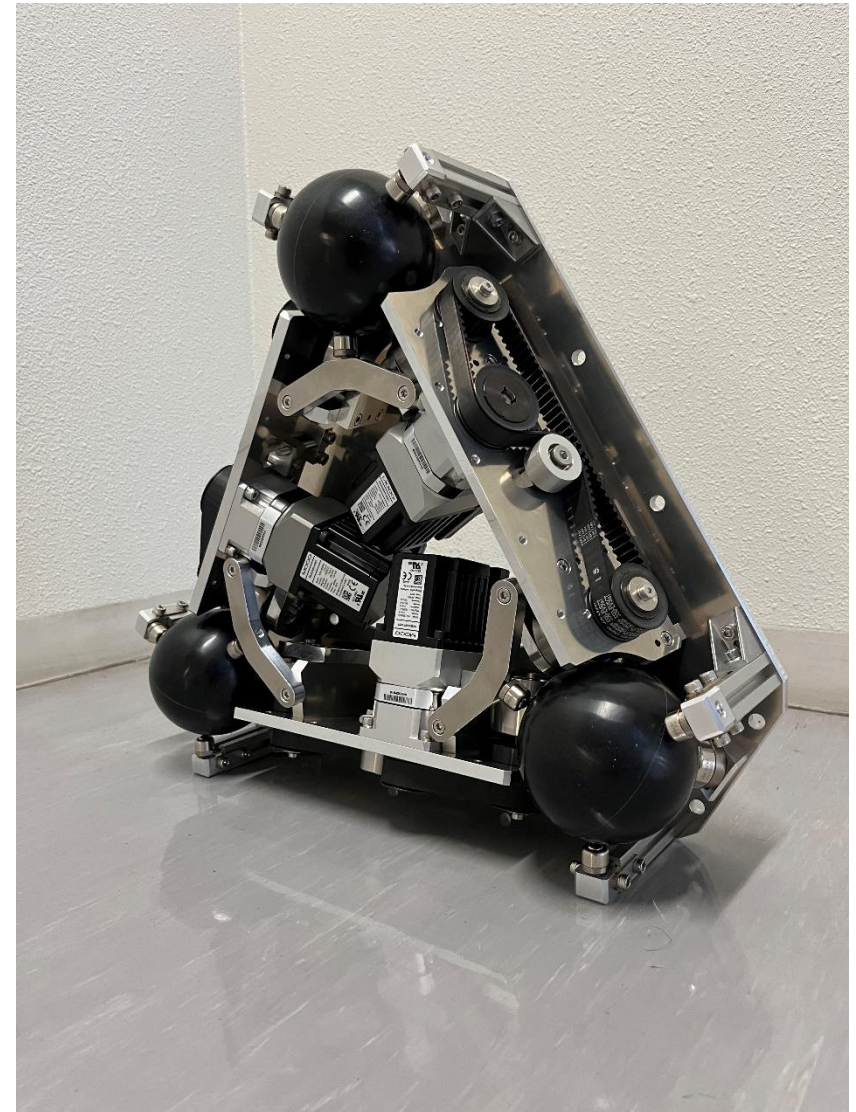
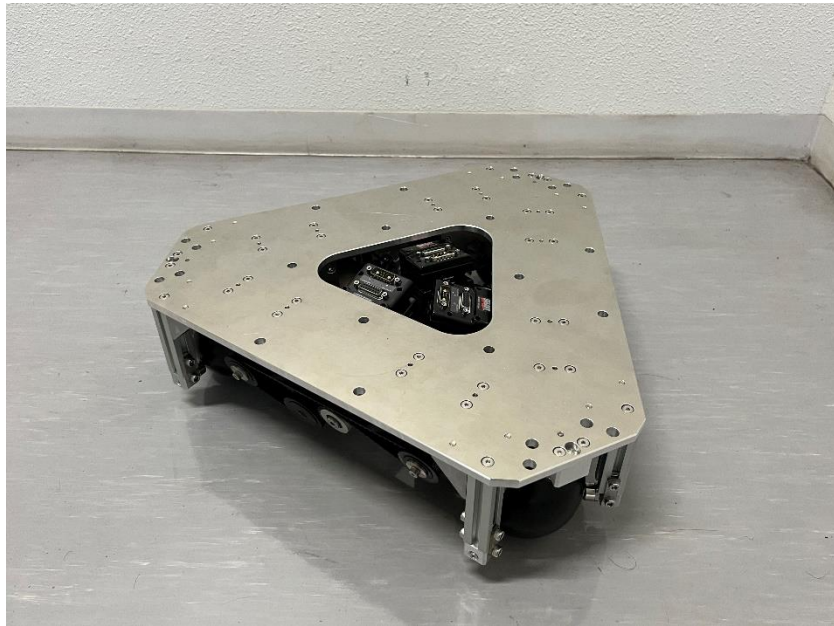
for mobile robots

Ball-driven omnidirectional movement mechanism

Sensing System Research Center

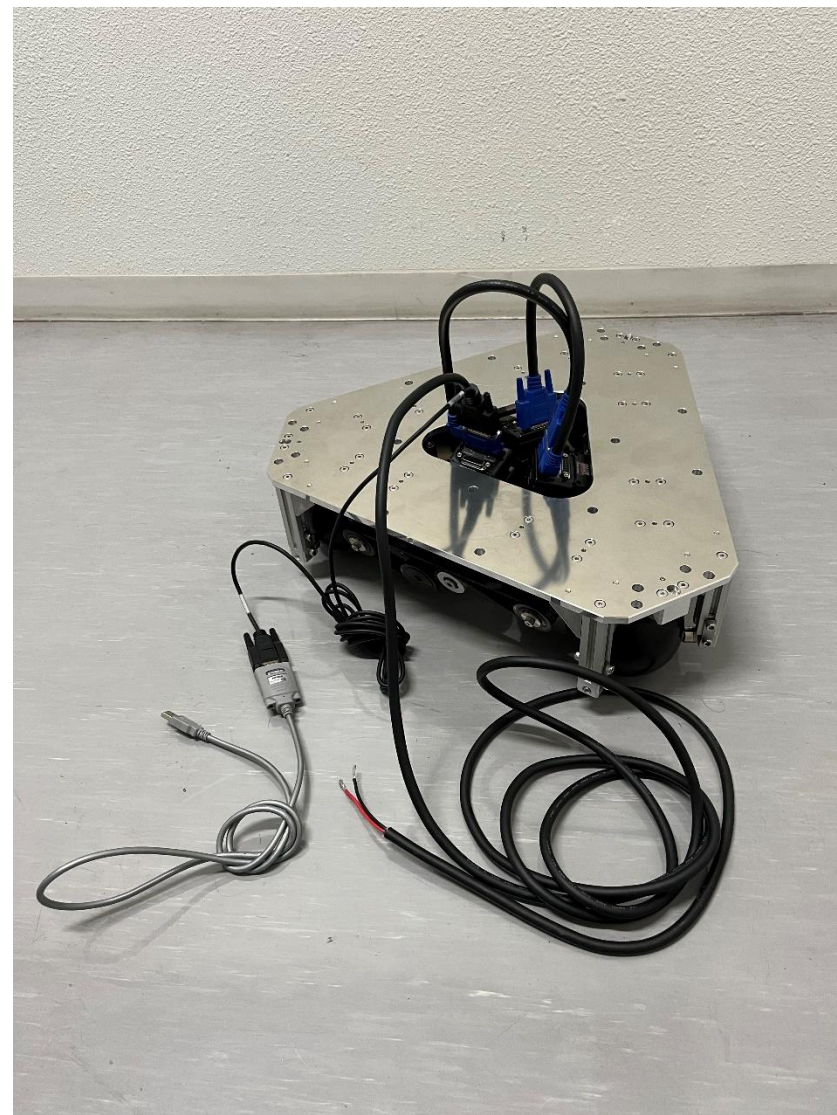
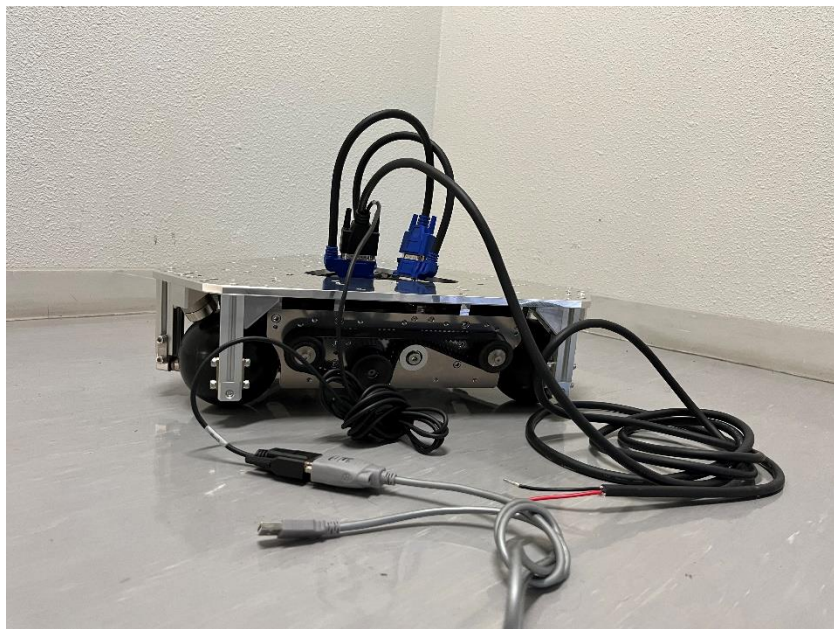
Production process evaluation research team

Shuichi Ishida





Installing the default communication cable





Delivery of the drive unit (hardware) has been completed,³We are currently adjusting the communication method for speed commands etc. to the motor of the machine.

ROS(Including ball drive kinematics) I can issue commands to the drive unit, but RS232CThe communication baud rate is low and some delays are occurring.

→ We are currently checking with the manufacturer to find out how to set the baud rate, etc.

MOOGThe genuine cable of the motor isp⁴It takes up space in the height direction like

→ p⁵With the connector kit shown on the rightp⁵Space-saving as shown in the diagram on the left
Genuine13cm → self-made4cmdegree

As soon as the delay issue is resolved, we would like to proceed with schedule adjustments for delivery etc.