

Advanced AMR-Project Concept

Objective: Moving the Tiago robot to goal positions and picking up the beer cans and throw it in the bins placed next to it.

Packages used: Move Base, Move It, QR-code reader

Procedure: Tiago robot placed at initial position will scan for the alvar markers placed Infront of the beer cans at different positions. After it receives the goal position from alvar markers, it reaches the nearest goal position and start the manipulation task of picking and disposing a beer can in trash. After disposing, it searches for the next nearest goal position and start navigating to that position and so on.

Achievement:

- Robot reaching the goal positions without colliding with other objects in environment.
- Successful disposal of waste.
- Reaching the original position after collecting and disposing all waste.