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## Robotteknik - Rapport

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31013 INGENIØRARBEJDE



Figur 1: SMR-8

24. November, 2016  
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# 1 Bilag

## 1.1 Opgave 6 - script

```
%Distance measurement
ignoreobstacles
followline "br"@v 0.25
:($drivendist > 0.8)
followline "bm"@v 0.25 :($irdistfrontmiddle <= 0.30)
stop
q = $irdistfrontmiddle
eval
$odoy-q-0.175

%Box gate
fwd -0.2 @v 0.4
turn 90
drive @v 0.15 :($crossingblackline == 1)
stop
fwd 0.1
stop
drive @v 0.15 :($crossingblackline == 1)
stop
fwd 0.175 @v 0.3
turn -90
ignoreobstacles
followline "bm"@v 0.2 :($crossingblackline)
ignoreobstacles
fwd 0.1
ignoreobstacles
fwd -1.2 @v 0.25
stop
turn -90
drive @v 0.2 :($crossingblackline == 1)
fwd 0.175
turn 90
followline "bm"@v0.2 :($crossingblackline == 1)
stop
fwd 0.175
turn 90
stop followline "bm":($crossingblackline == 1)
fwd 0.1 @v 0.1
followline "bm":($crossingblackline == 1)
stop

%Wall
turn -20
fwd 0.25
followline "bm"@v 0.2 :($crossingblackline == 1)
```

```

stop
fwd 0.1
followline "bm"@v 0.2 :($crossingblackline == 1)
stop
fwd 0.1
followline "bm"@v 0.2 :($crossingblackline == 1)
stop
fwd 0.1 followline "bm":($crossingblackline == 1)
stop
fwd 0.175
stop
turn 90
followline "bm":($crossingblackline == 1)
stop
fwd 0.5
turn 90
fwd 0.3
followwall "l"0.15 :($irdistleft >= 0.40)
stop
fwd 0.345
turn 90
stop
fwd 0.55
turn 90
fwd 0.3
followwall "l"0.15 :($irdistleft >= 0.40)
stop
fwd 0.37
turn 90
%White line
followline "bm":($crossingblackline == 1)
stop
fwd 0.1
followline "br":($drivendist < 1.3)
drive @v 0.25 :($crossingwhiteline == 1)
stop
fwd 0.175
turn 90
%Goal
followline "wm"@v 0.15 :($crossingblackline == 1)
stop
fwd 0.1
followline "bm"@v 0.2 :($crossingblackline == 1)
fwd 0.175
stop
turn -90
ignoreobstacles
followline "bm":($irdistfrontmiddle <= 0.15)

```

```
turn 90
followwall "r"0.10 :($irdistright >= 0.40)
fwd 0.35
turn -90
fwd 0.15
turn -100
ignoreobstacles
fwd 0.5
stop
turn 90
followline "bm"@v 0.3 :($irdistfrontmiddle <=0.15)
stop
```