S#2 :: Obstacle Avoidance

Monday, 12 July 2021 10:49 AM

Lidar Sensor Data Processing

A#1 ⇒ [0 2 inf inf 0]

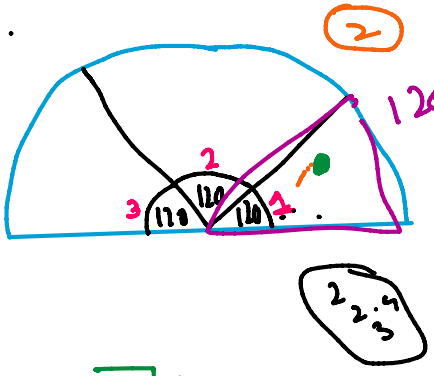
- Area Division
- Data Pre-Processing:

→ min (A#1, 100) ⇒ 100.

mA = min (A#1)

min(mA, 100)

min [0 2 1 3 inf inf] (120)



360

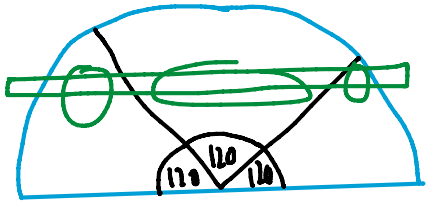
A#1 = 0 : 120

A#2 = 120 : 240

A3# = 240 : 360

L.S = inf

Logic



Case # 1 : Straight Moving

Case # 2 : Taking Left Turn

Case # 3 : Taking Right Turn

Case # 4 : Stop and Turn Full

A1 = 100 → (#3)
A2 = 100
A3 = 2.5

A1, A2, A3 → 100 → (#1)

A1 = 1.5
A2 = 100
A3 = 100 → (#2)

(#4) A1 = ! 100
A2 = !
A3 = !