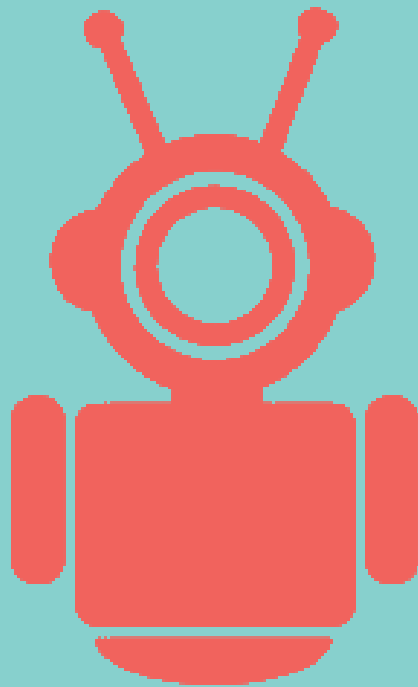


USER MANUAL



Automated
Kiwifruit Picking

Test Drive

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START-UP

The ROS simulation can be initialised by running the start-up script provided.

To do so, please navigate to the “se306project” folder in the linux terminal and enter the following command -
`./startup.sh`

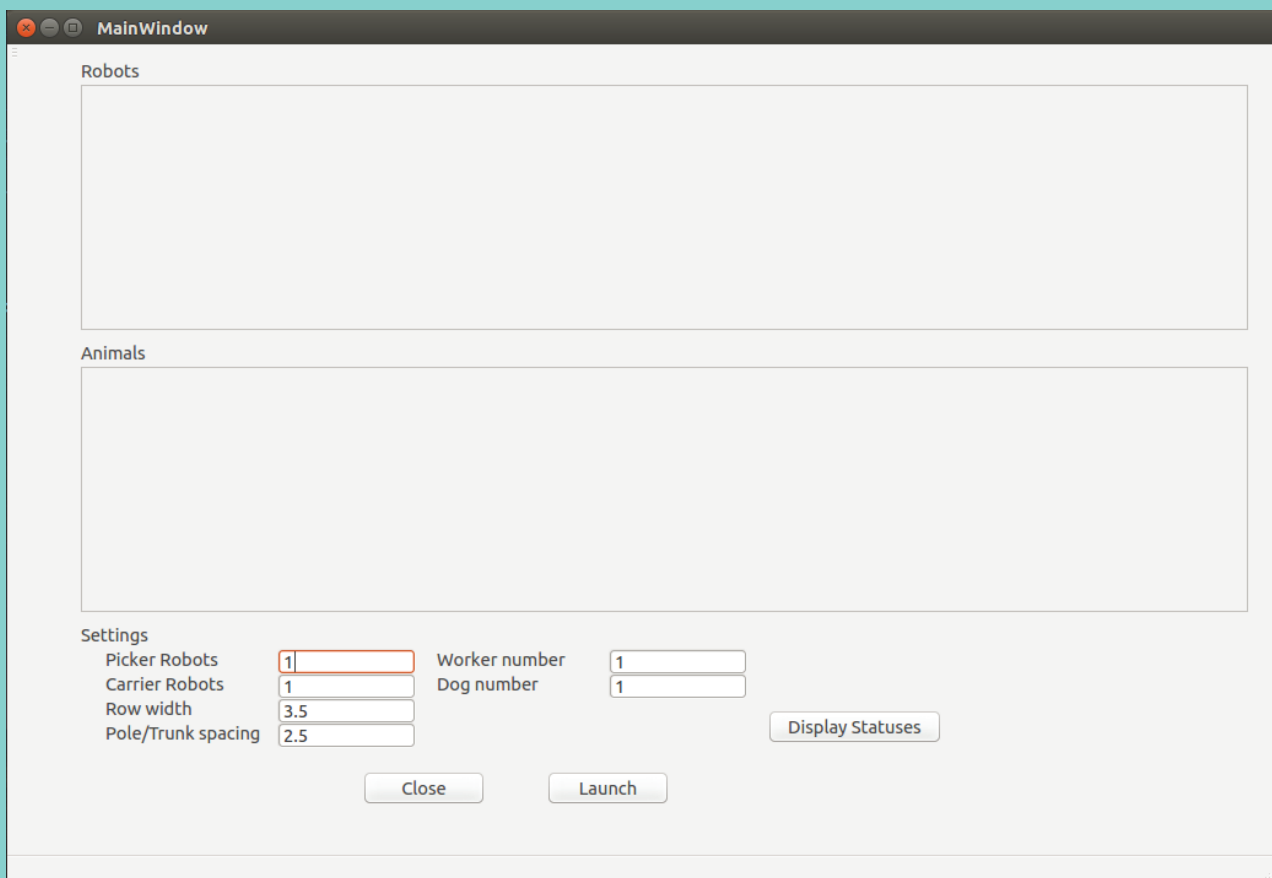


Figure - 1.0

The script will compile & launch the project. Once the project has been successfully compiled the following interface will be presented.

The world of the simulation can be configured on this interface. Simply, enter the desired number of each world component and select the “Launch” button.

STATUS

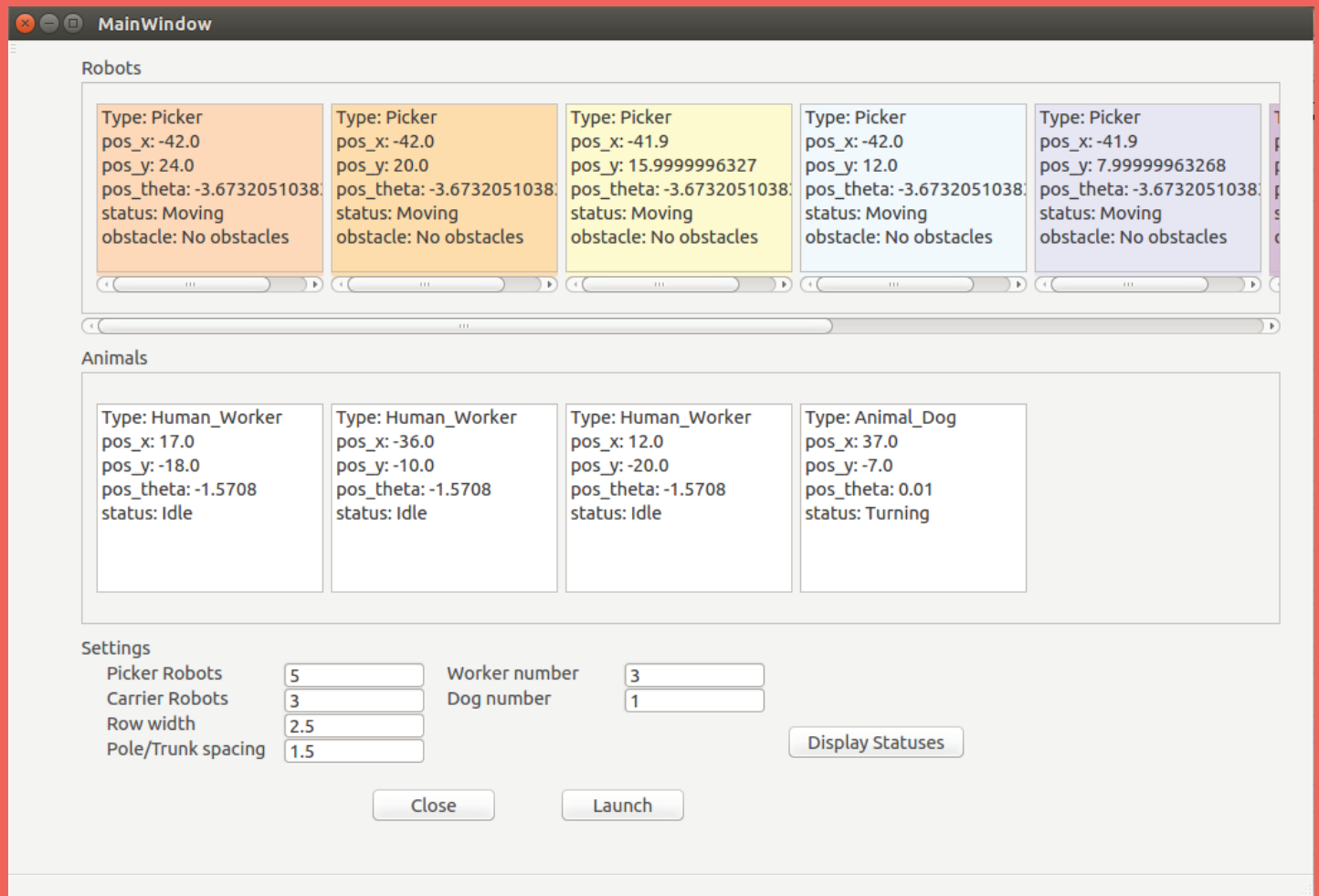


Figure - 2.0

During the simulation the statuses of the world components, such as the picker robot, can be followed on the interface.

For the picker and carrier robots the colour of the panel represents the colour of the robot in Stage.

STAGE

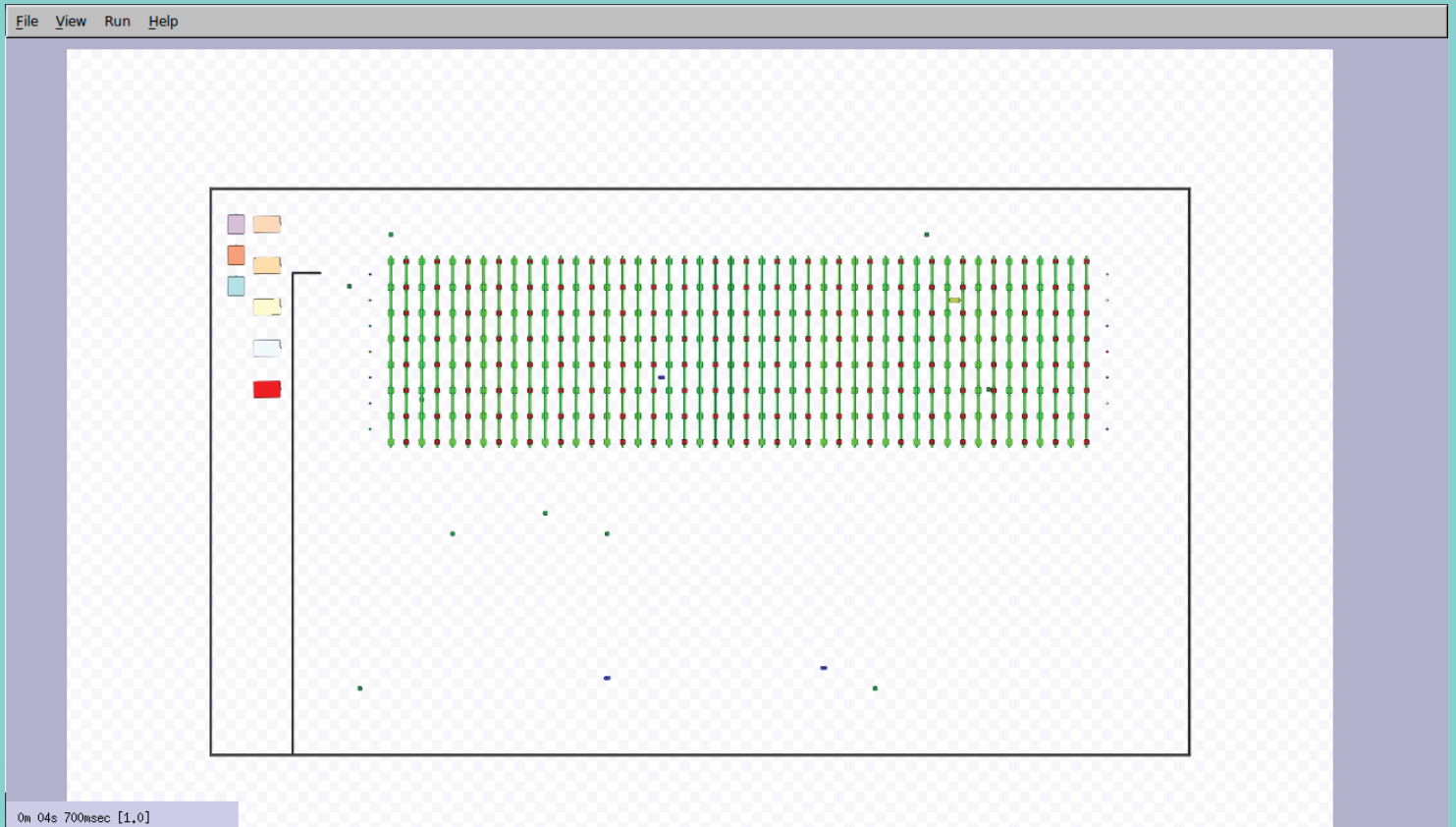


Figure - 3.0

The simulation can be viewed on the Stage window once the “Launch” button on the interface has been pressed. Here the simulation of the robots picking kiwifruits can be viewed; combined with the environment components, such as the worker and dog components.

To close the Stage window press the “Close” button the interface.