

28 July 2017

~~Todo~~

ROS eBUG SWARM

I will check ROS
I may create a lockstep
mechanism with the
timestamp read from the camera.
(may or may not
be needed)

3

RADIO

30 f/s

Call get-blobs
until you receive
an empty response
from the camera

main communication
thread
(only this one
talks to the
radio)

now we have
full frame
blob info

write into

bloblist

read robot
commands

robot commands

Send robot
Control
Commands

read
blob information

Calculate
robot poses

write them
in

robot poses

"Ros topic"

write robot
commands

read robot
poses

Calculate
Correction
Commands

desired
trajectories

(pre-calculated)

SIMPLIFIED ARRANGEMENT
→ PRE-DEFINED
TRAJECTORIES ARE USED

This ~~is~~ setup for
following
pre-calculated
trajectories

WE CAN
CALCULATE
TRAJECTORIES DYNAMICALLY

TRAJECTORY
PRE-CALCULATIONS