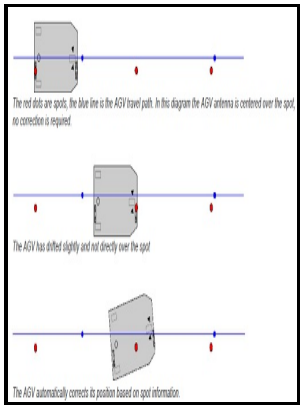
Navigation and control of autonomous guided vehicles.

University of Wolverhampton - AMRs vs. AGVs: The Difference Between a Robot and a Guided Vehicle



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To start with assume that the vehicle is standing still, i. We know at what height the laser beam will.

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For convenience, this will be omitted for the input signals.

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We assumed that the measured angles had been associated with the correct reflectors. This is in addition to their notorious reputation when it comes to adapting to change. In the light of the previous discussion, the idea of stabilizing the error system over a revolution of the laserbeam is quite obvious.

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The detec-tor, which is placed on the optical axis in the focal plane of the lens, is a Fig 2 The prototype anglemeter. The angle 6 is also the heading of the AGV.

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In this simulation the initial errors are reduced. We will now briefly summarize each component in the system.

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