

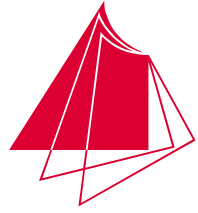


Hochschule Karlsruhe
Technik und Wirtschaft

UNIVERSITY OF APPLIED SCIENCES

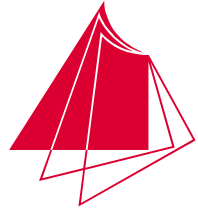
Näher dran.

Steuerung eines Roboters mit zwei Freiheitsgraden mit ROS



INHALT:

1. Aufgabe
2. Lösungsansatz
3. Aufbau der SW
4. Ablaufgraph
5. Ergebnisse

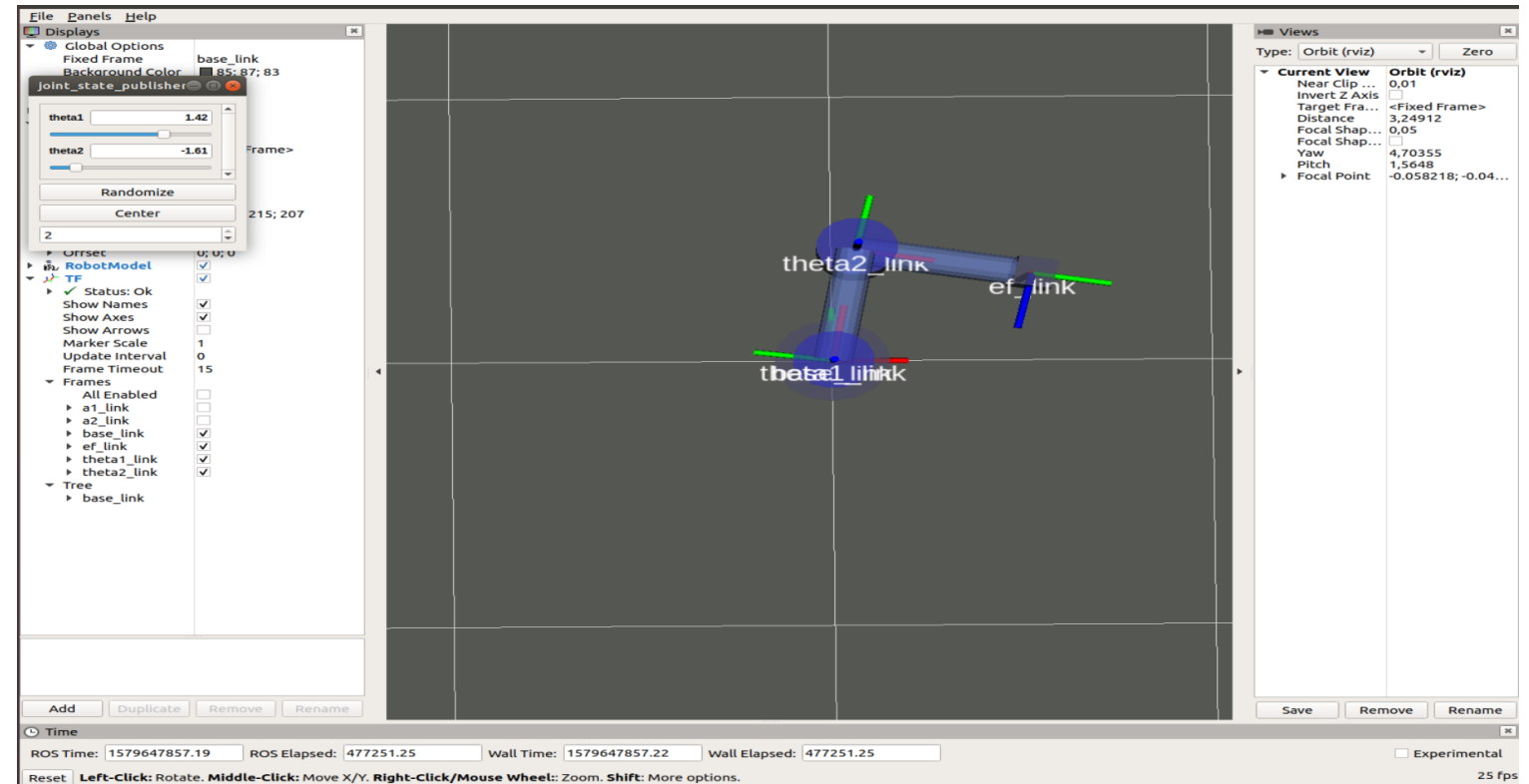


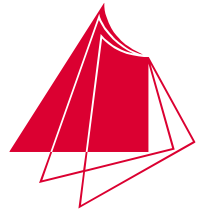
1. Aufgabe

- Steuerung eines Roboters mit zwei Freiheitsgraden

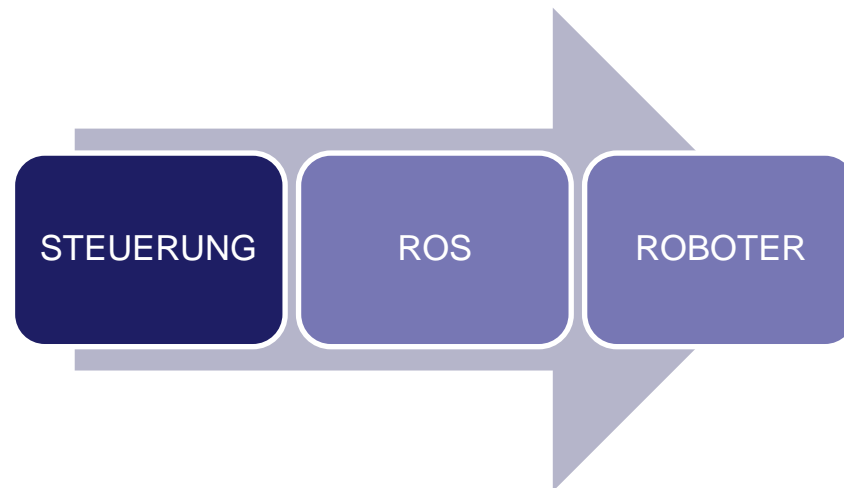
Roboter

- sdsdfsdf

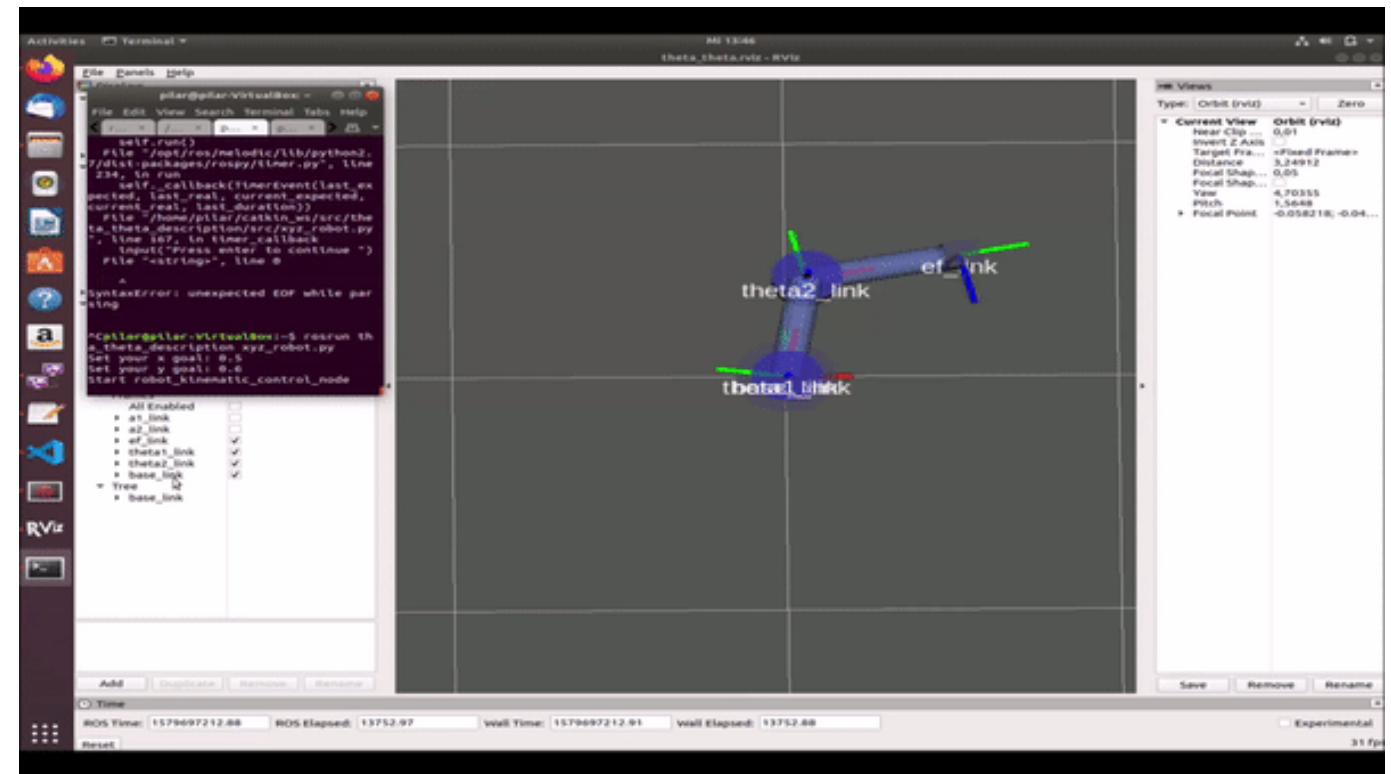
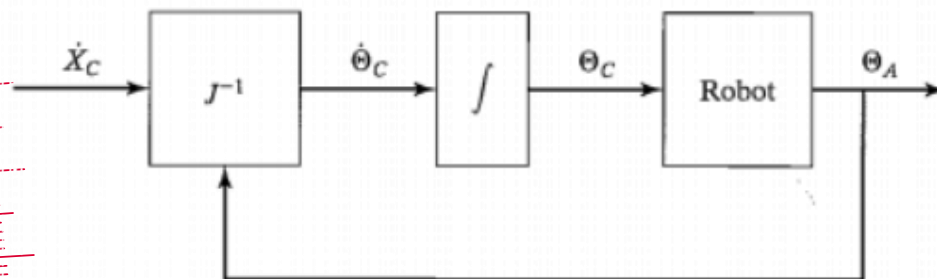


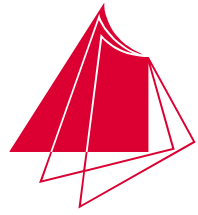


2. Lösungsansatz



Steuerung Diagramm

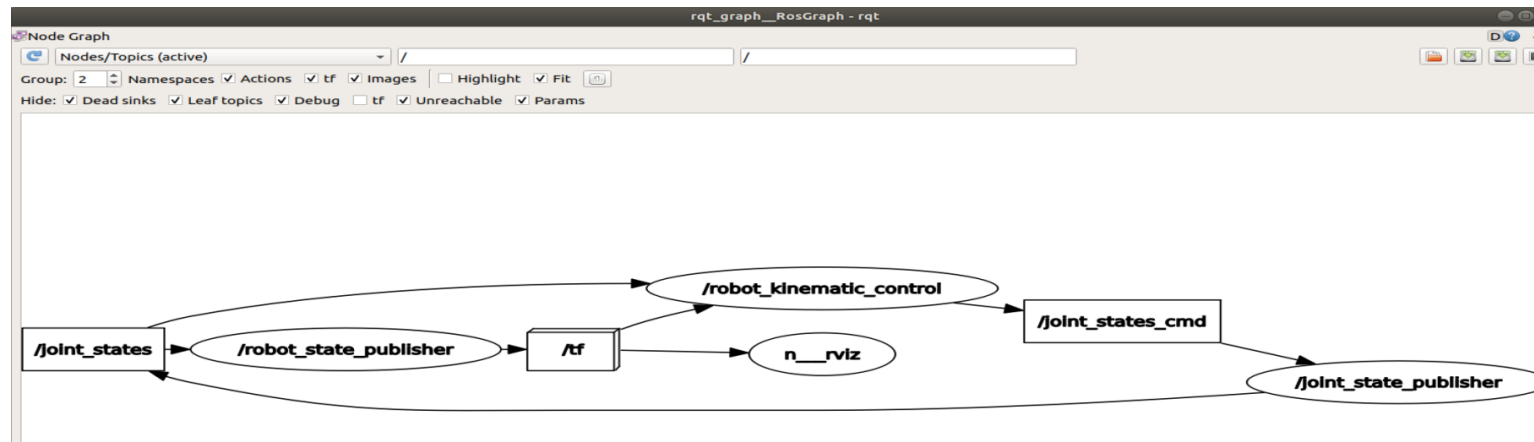
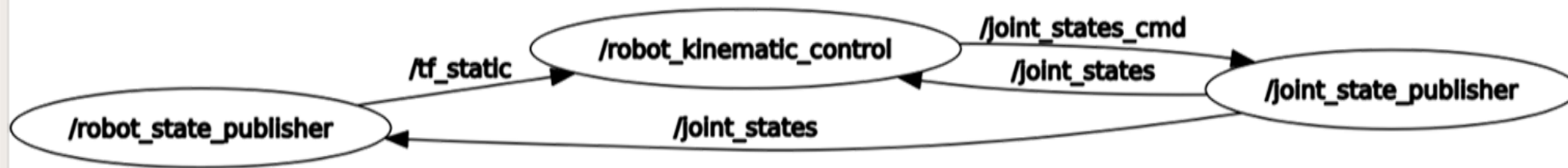


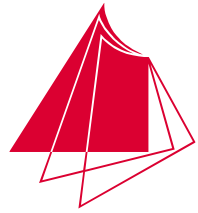


- Thinningsdasd

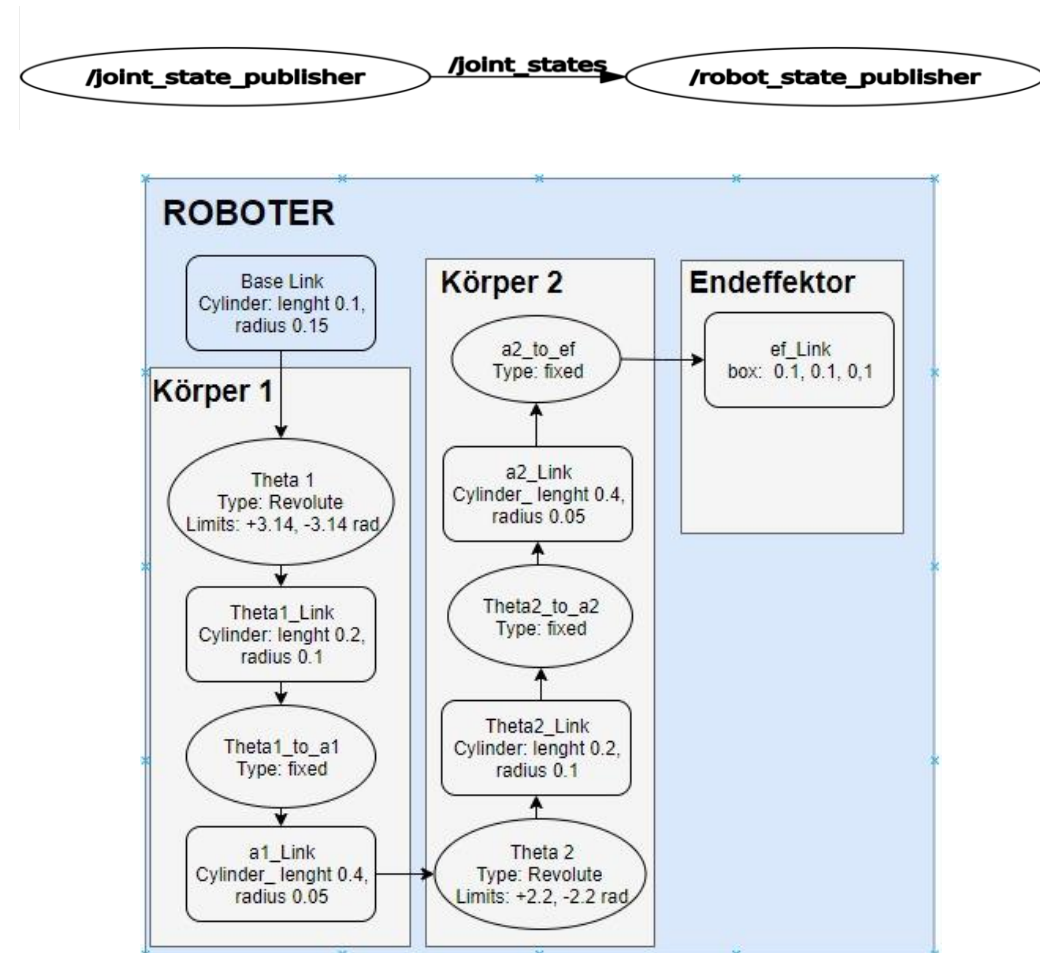
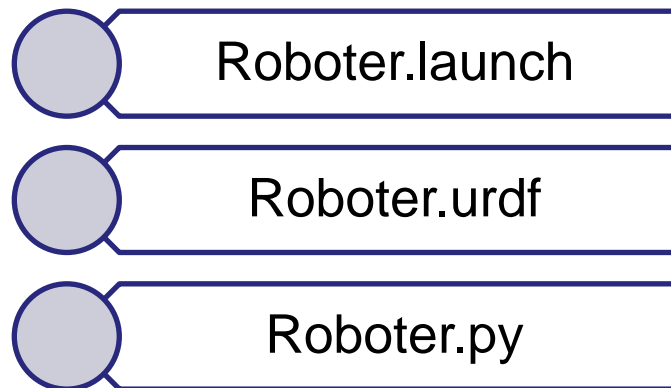
3. Aufbau der SW

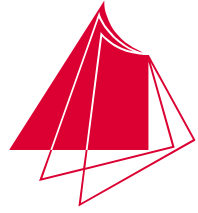
- Mechanical





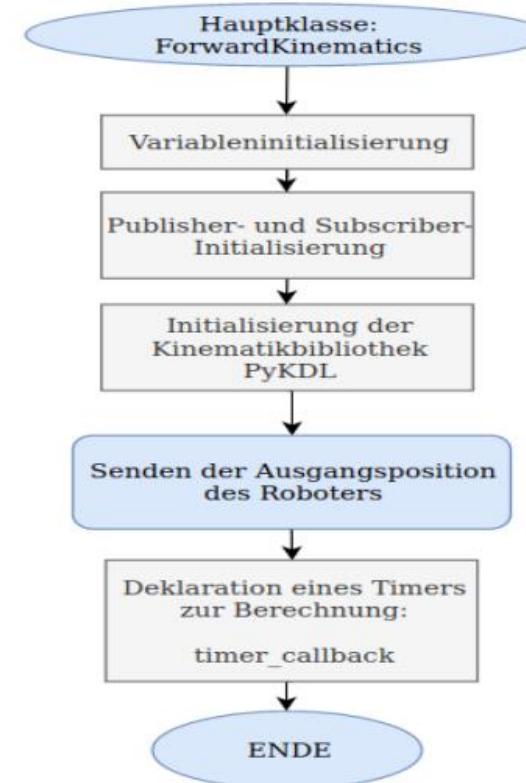
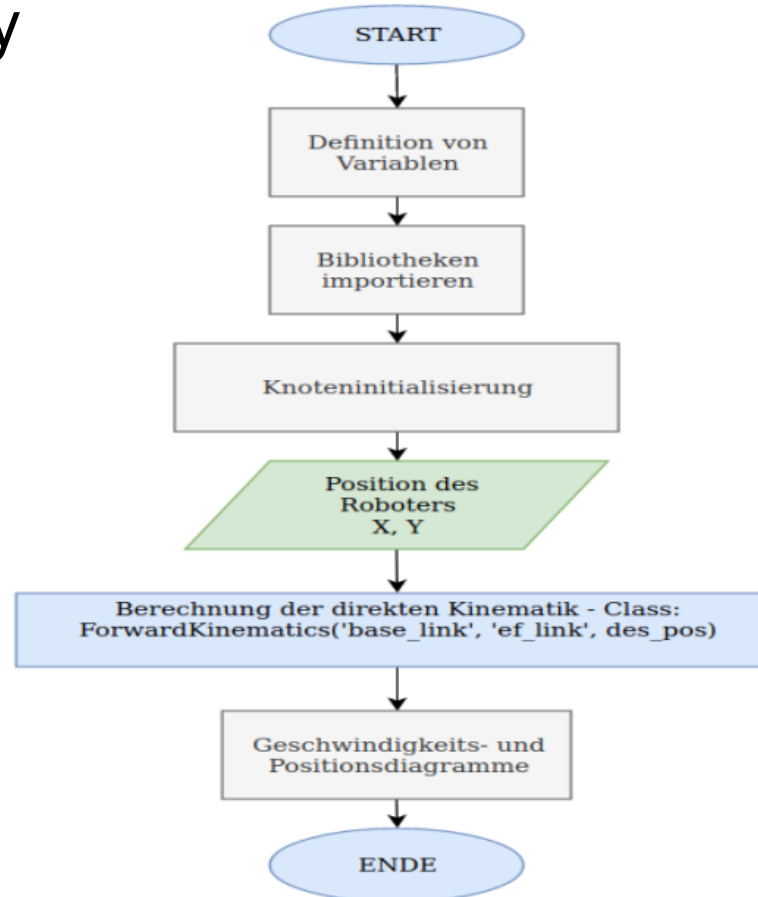
4. Ablaufgraph

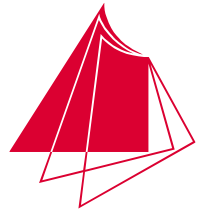




4. Ablaufgraph

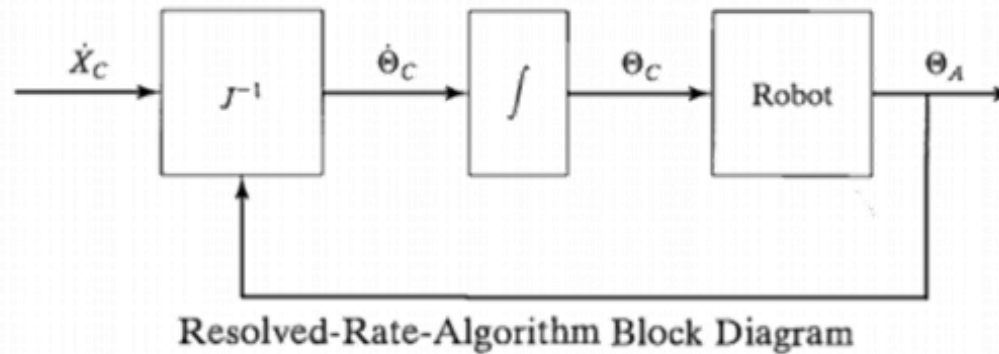
- xyz_robot.py





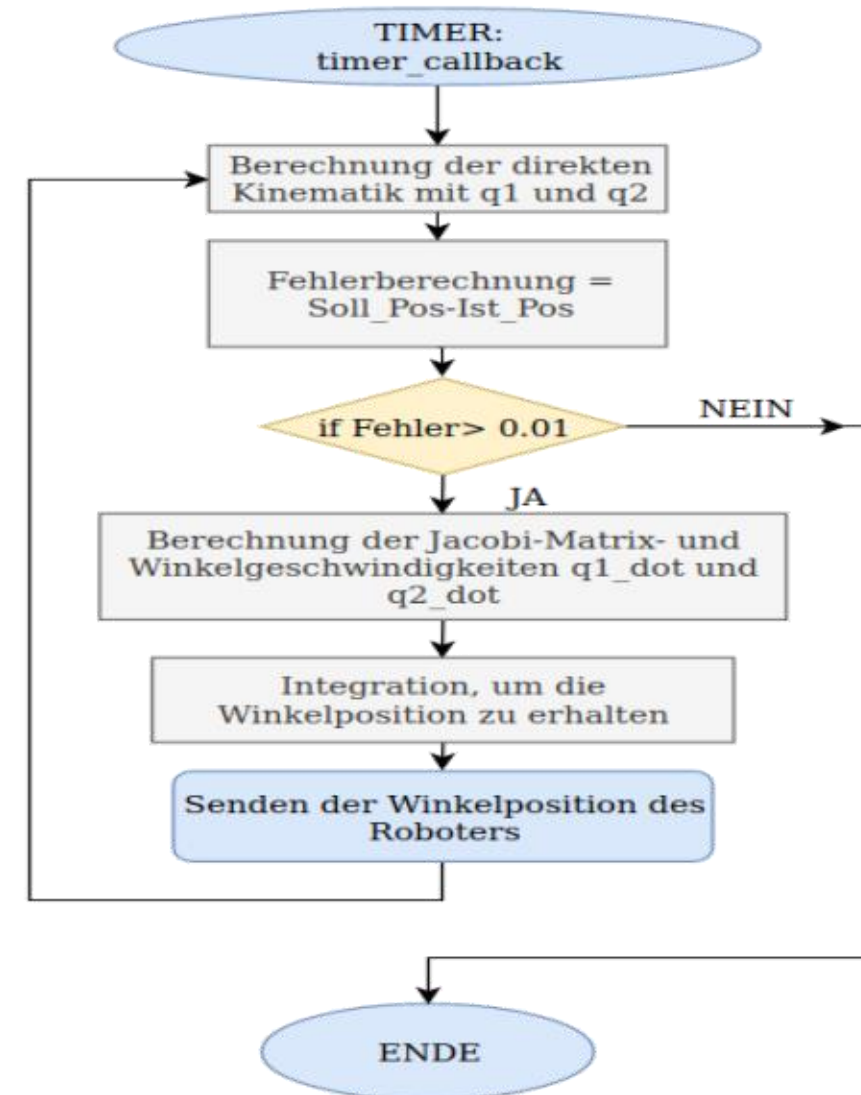
4. Ablaufgraph

- Timer



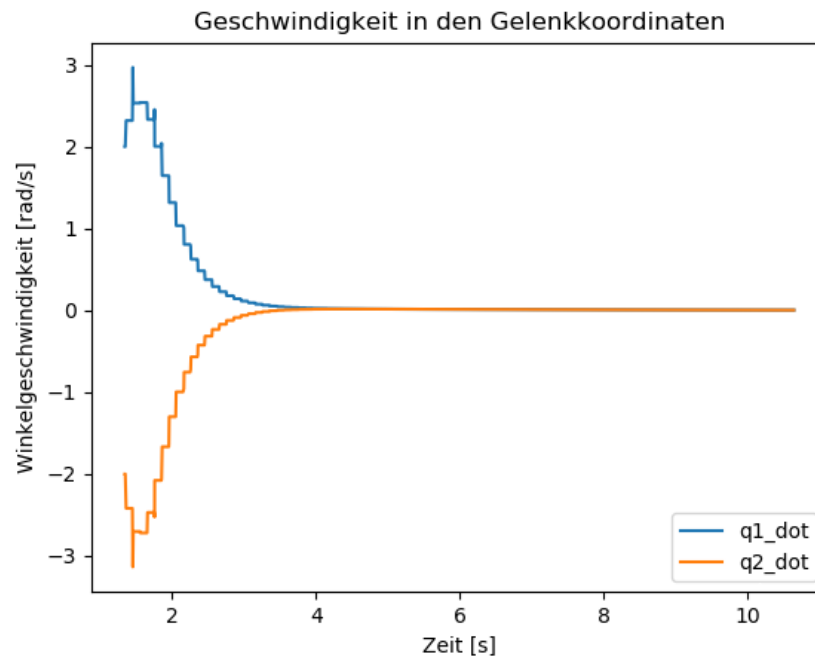
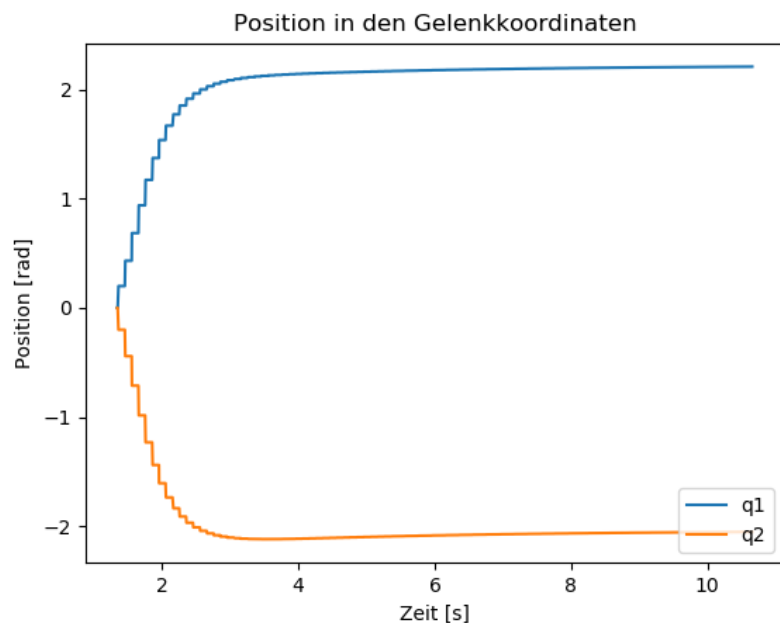
Denavit-Hartenberg parameters

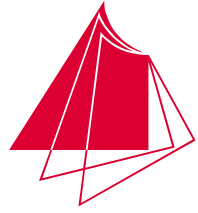
DoF	theta_i	d_i	a_i	alpha_i
1	theta_1	0	0.40	0
2	theta_2	0	0.45	Pi/4





5. Ergebnisse





Vielen Dank für Ihre Aufmerksamkeit!