The background features a dark blue gradient with a subtle pattern of white stars. On the left side, there are several technical diagrams in a lighter blue color. These include circular gauges with numerical scales (140, 150, 160, 170, 180, 190, 200, 210, 220, 230, 240, 250, 260) and various circular arrows indicating rotation or movement. The text is positioned on the right side of the image.

ROBOTOUR 2018- ROBOSOFT

ADRIÁN DYLÍK

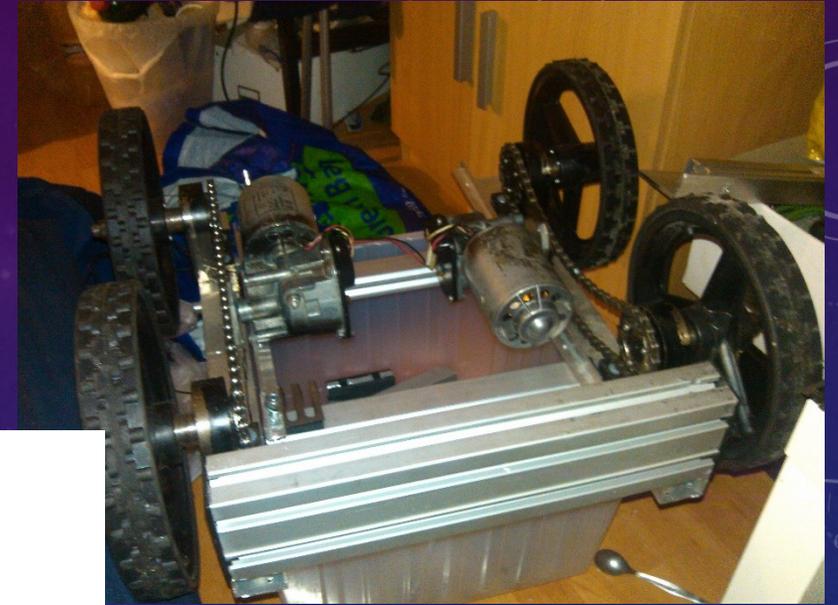
NEURON 2 (2015)

HISTORY – ROBOT NEURON

NEURON 1 (2012)



NEURON 3 (2017)



† NEURON (2017) – 10.9.2018 MONDAY LAST TEST



Ahoj/Szia

NEURON 4 (2018) – 11.9.2018 FIRST DAY

RYCHLYPRESUN.sk

Vyhľadavanie Vyhľadavanie Košík 0,00 €

KATEGÓRIE

- Hoverboardy
 - Hoverboardy 6,5"
 - Hoverboardy 8"
 - Hoverboardy 8,5"
 - Hoverboardy 10"
 - Minisegway a príslušenstvo
- Detské elektrické autička
 - AUDI
 - BENTLEY
 - BMW
 - FORD
 - MERCEDES
 - MINI Cooper
 - RSX
 - SMART
 - TOYOTA
 - VOLKSWAGEN
- Detské elektrické motorky
- Detské Elektrické štvorkolky
- Samochodiacie autičko RiriCar
- Elektrické kolobežky
- Náhradné diely
- Elektrické bicykle



VolksWAGEN

BENEO VOLKSWAGEN TOUAREG

Volkswagen Touareg, EVA kolesá, čalúnené sedadlo, 2,4 GHz DO, Kľúč, 2 X MOTOR, čierna, USB, FM Rádio, Bluetooth, SD karta, odpruženie, 5 bodový pás, ORIGINAL licencia

Široké čalúnené sedadlo, 5 BODOVÝ PÁS, Mäkké EVA kolesá, USB, Bluetooth, FM Rádio, SD karta, NÚDZOVÁ BRZDA, 2,4 GHz diaľkové ovládanie Kľúč na štartovanie, Odpružené nápravy

  ORIGINAL VW LICENCOVANÝ PRODUKT

VOLKSWAGEN_TOUAREG_BLACK Nový produkt

287,00 € s DPH ~~399,00 € s DPH~~ -112,00 €

Farba 

Tovar dostupný sklodom

1 + - KÚPIŤ

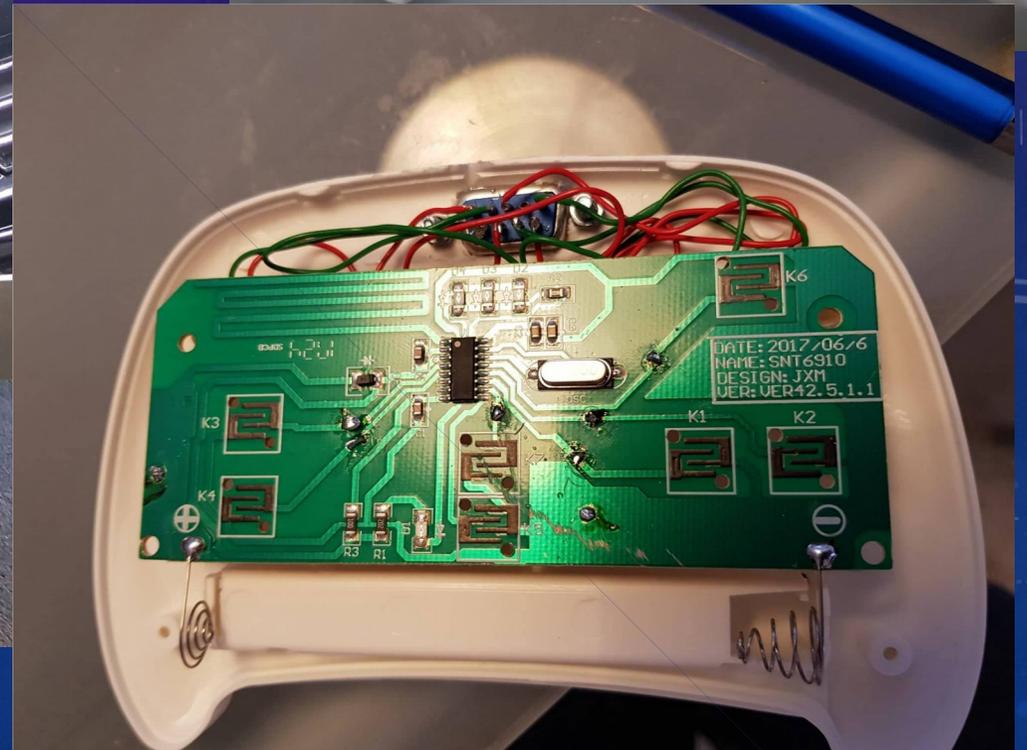
Porovnať



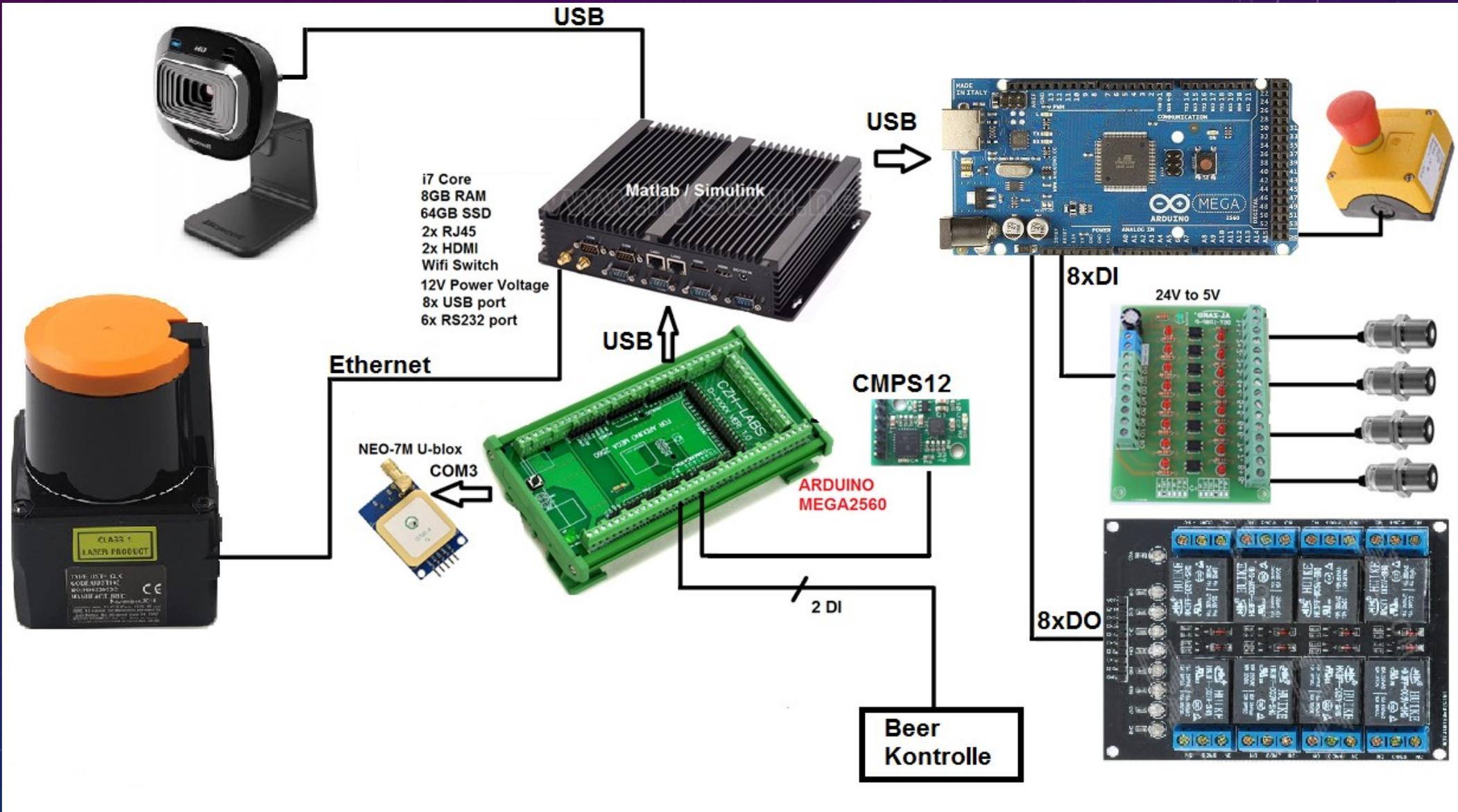
Napište Váš názor

VLASTNOSTI	NA STIAHNUTIE	DETAILY	OBSAH BALENIA	NÁZORY ZÁKAZNÍKOV(0)
Motor		2 x motor 12 V / 45W		
Max. rýchlosť		7km/h		

SENSOR INTEGRATION + HACK DRIVER



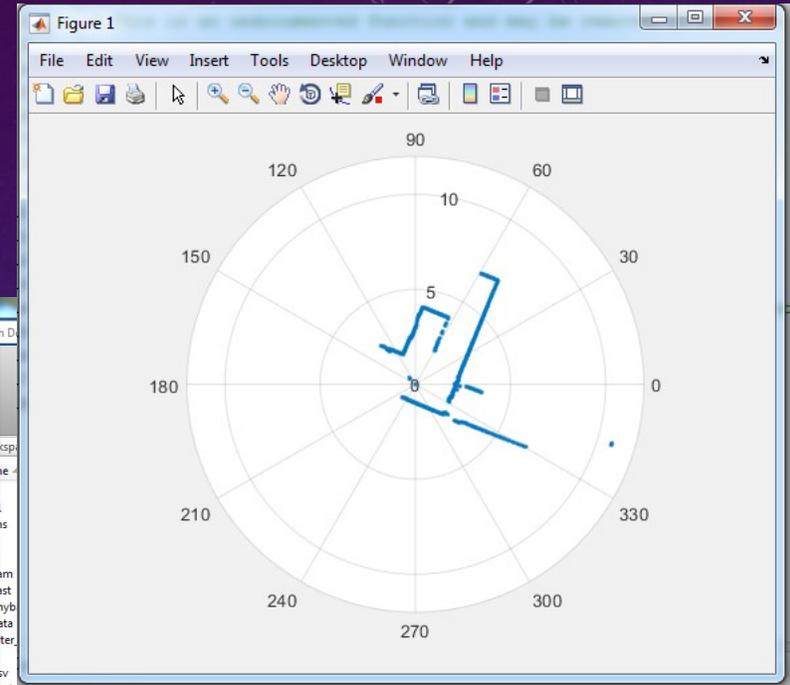
ROBOT- TOPOLOGY



SOFTWARE

The image shows the MATLAB R2017a software interface. On the left is a file explorer showing a folder structure with files like 'arduino_drive_closedloop_ert...', 'MATLAB', 'slprj', 'stateflow_test_ert_rtw', 'untitled_ert_rtw', 'UST_10_LX_test', '180208_001.png', '180208_002.png', 'a127.png', 'aaaaa.m', 'arduino_drive_closedloop.eep', 'arduino_drive_closedloop.elf', 'arduino_drive_closedloop.hex', 'camParam.mat', 'First18.m', 'funkcne_data_serial.slx', 'funkcne_data_serial.slx.autos...', 'funkcne_data_serial_2.slx', 'green_filter.jpg', 'hľadanie_cesty.m', 'hmi_obraz.m', 'hsv17.jpg', 'im.mat', 'im1.jpg', 'im2.jpg', 'im3.jpg', 'im4.jpg', 'im5.jpg', 'im6.jpg', 'im7.jpg', 'im8.jpg', 'im9.jpg', 'im10.jpg', 'im11.jpg', 'im12.jpg', 'im13.png'. The main window (Figure 2) displays a landscape image with a red-filled area plot overlaid. The plot shows a large red area that peaks in the center and tapers off towards the right. A vertical blue line is drawn across the plot. The status bar at the bottom shows '8.8706'. On the right, a command history window is visible, showing a list of commands and their execution times.

```
Command History  
priechodnost  
$-- 4. 5. 2018 17:34 --$  
First18  
$-- 4. 5. 2018 17:40 --$  
First18  
$-- 7. 5. 2018 13:39 --$  
First18  
First18  
First18  
priechodnost  
First18  
imshow(im)  
imshow(hsv)  
imshow(hsv18)  
imshow(hsv1)  
imshow(hsv2g)  
plot(hsv2g)  
First18  
$-- 7. 5. 2018 19:31 --$  
First18  
$-- 10. 5. 2018 13:34 --$  
First18  
cam.Resolution  
First18
```



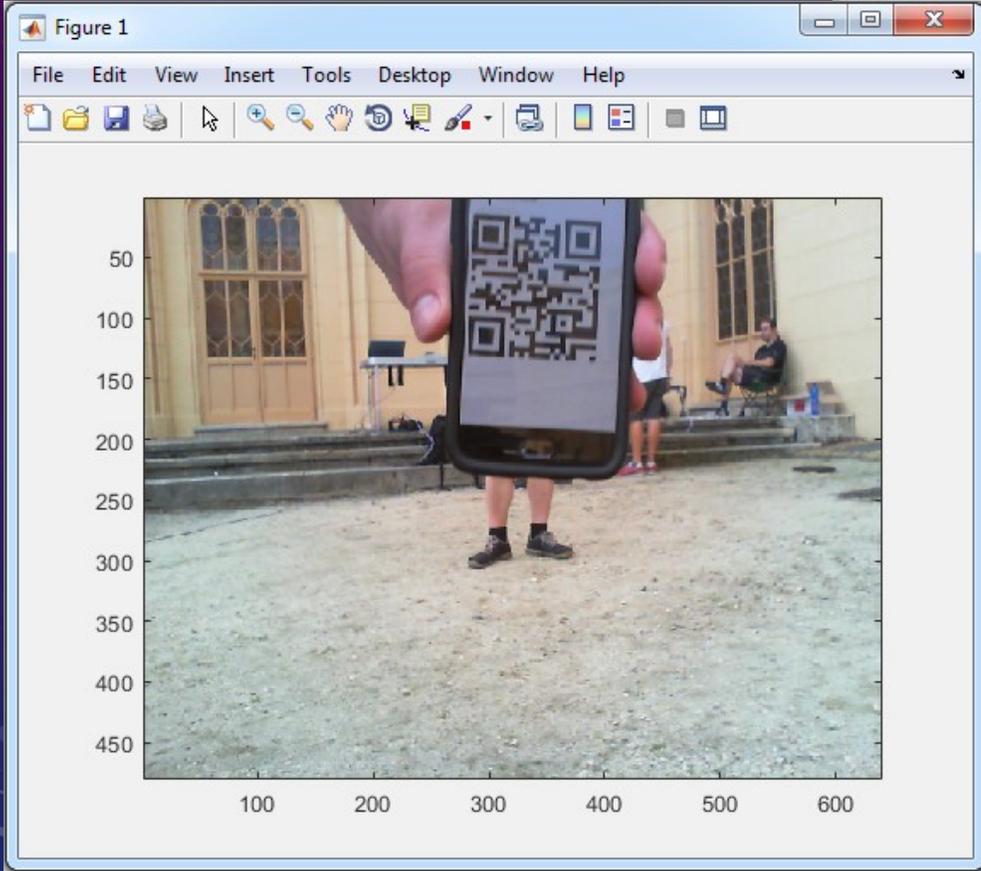
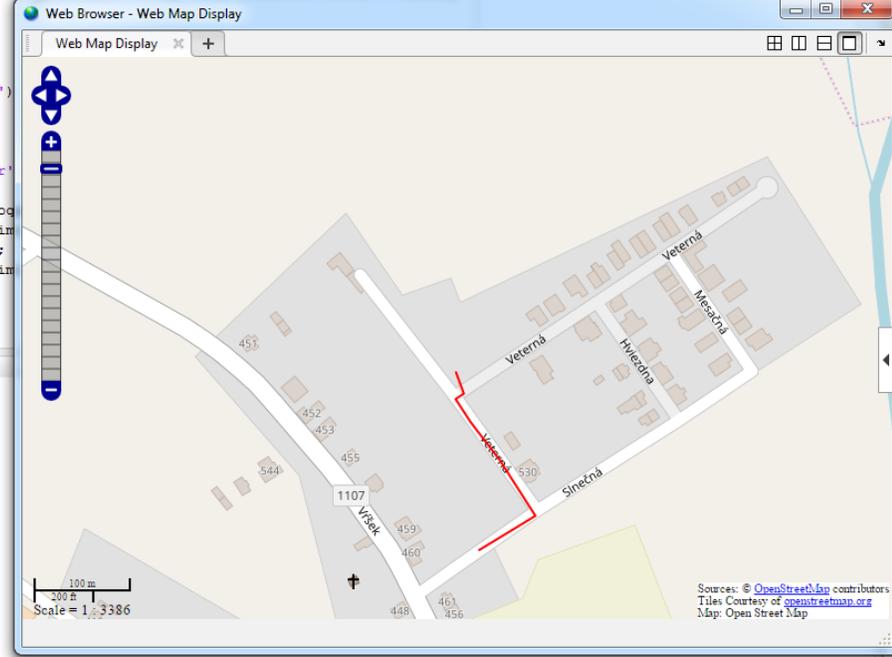
```
720x1280x3 double  
720x1280x3 logical  
34  
1  
m
```



SOFTWARE

```
MATLAB Robotour2018
Editor - C:\Users\Adrian\Documents\MATLAB\Robotour2018\osm_1.m
robotour_01.m first_19.m skurvene_1.m online_data.m osm_1.m hybrid_18.m test_qr.m addPolarAxesBehaviors.m
1 T = readtable('ROBOTOUR1.xlsx','Sheet','2018');
2 pocet_bodov=7;
3 A = table2array(T(1:pocet_bodov,1:4));
4 %geo:48.3710820,16.9704510
5 %aktual_lat=A(1,3) % suradnice z GPS prijimaca 48.00000000
6 %aktual_lon=A(1,2) % suradnice z GPS prijimaca 16.00000000
7 cislo_next_point=A(next_point,1);
8 lon_next_point=A(next_point,2); % suradnice z tabulky bodov
9 lat_next_point=A(next_point,3); % suradnice z tabulky bodov
10 typ_next_point=A(next_point,4); % typ bodu lokalneho ciela z tabulky
11
12
13
14 % colors = {'red'};
15 webmap('openstreetmap',
        {'red'};
        {'sirka'};
        {'dlzka'};
        lat, lon, 'Color'
        (lon0, lat0);
        lonlim, lonlim
        (latlim, lonlim
        (lon0, lat0);
        (latlim, lonlim
```

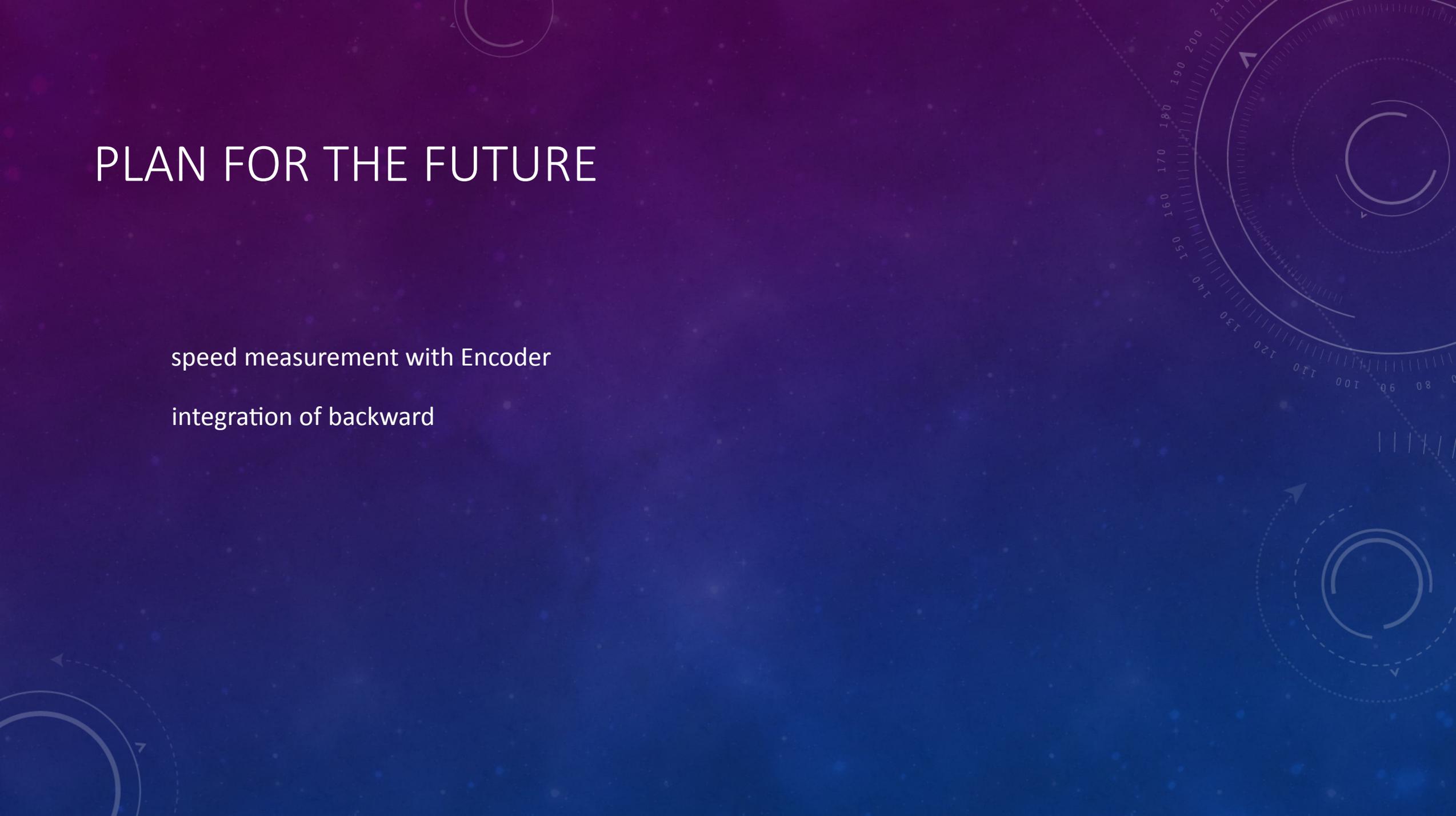
Name	Value	Max	Min
A	7x4 double	48.3712	1
cislo_next_point	1	1	1
colors	1x1 cell		
filter_pixel	30	30	30
flag	0	0	0
FM_QRcode	0	0	0
lat	[48.3712;48.3711;48.37...	48.3712	48.3701
lat_next_point	16.9704	16.9704	16.9704
lon	[16.9704;16.9705;16.97...	16.9711	16.9704
lon_next_point	48.3712	48.3712	48.3712
M_QRcode	0	0	0
nakladka	0	0	0
next_point	1	1	1
okno	320	320	320
otien	0.2000	0.2000	0.2000
pocet_bodov	7	7	7
QR_kod	0	0	0
s1	1x1 serial		
sud_ok	0	0	0
T	7x5 table		
test	0	0	0
test_cam	0	0	0
test_gps	0	0	0
typ_next_point	1	1	1



PLAN FOR THE FUTURE

speed measurement with Encoder

integration of backward



THANK YOU

