

Ingenieurspraxis, Forschungspraxis, Interdisciplinary Project

Implementation of robotic motion planning

The motion planner of a robotic arm requires planning of the necessary motion, under collision avoidance and regarding the joint limitations of the robot. In this project, we will focus on motion planning of the Panda robot arm, using several planners. We will test OpenRave motion planner and compare it to the moveit motion planner.

We will also implement and test cartesian path planning using methods like the Descartes path planner.

At the end of this project, the student will learn about implementation and usage of different motion/path planners.

Prerequisites

Useful background:

- Robotic control
- Experience with ROS

Necessary background:

- Experience with C++

Contact

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(Please provide your CV and transcript in your application)

Advisors

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