

COLLISION AVOIDANCE ROVER

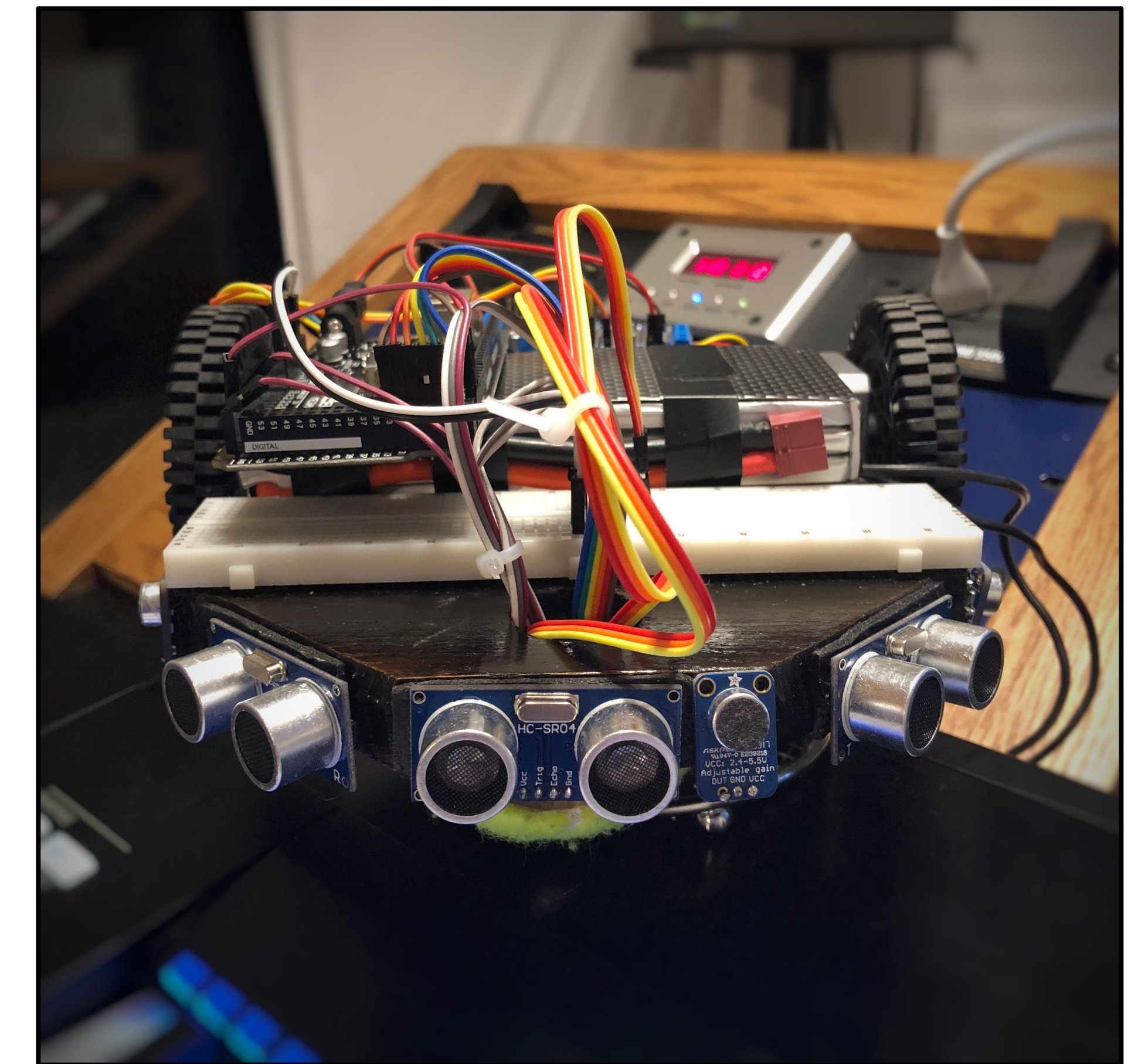
PROJECT GOALS

This project includes the design and implementation of a rover capable of autonomously avoiding environmental obstacles while self-navigating towards a moving endpoint.

Applications of this implementation may include navigation of areas dangerous to humans and carrying heavy loads while following a user.

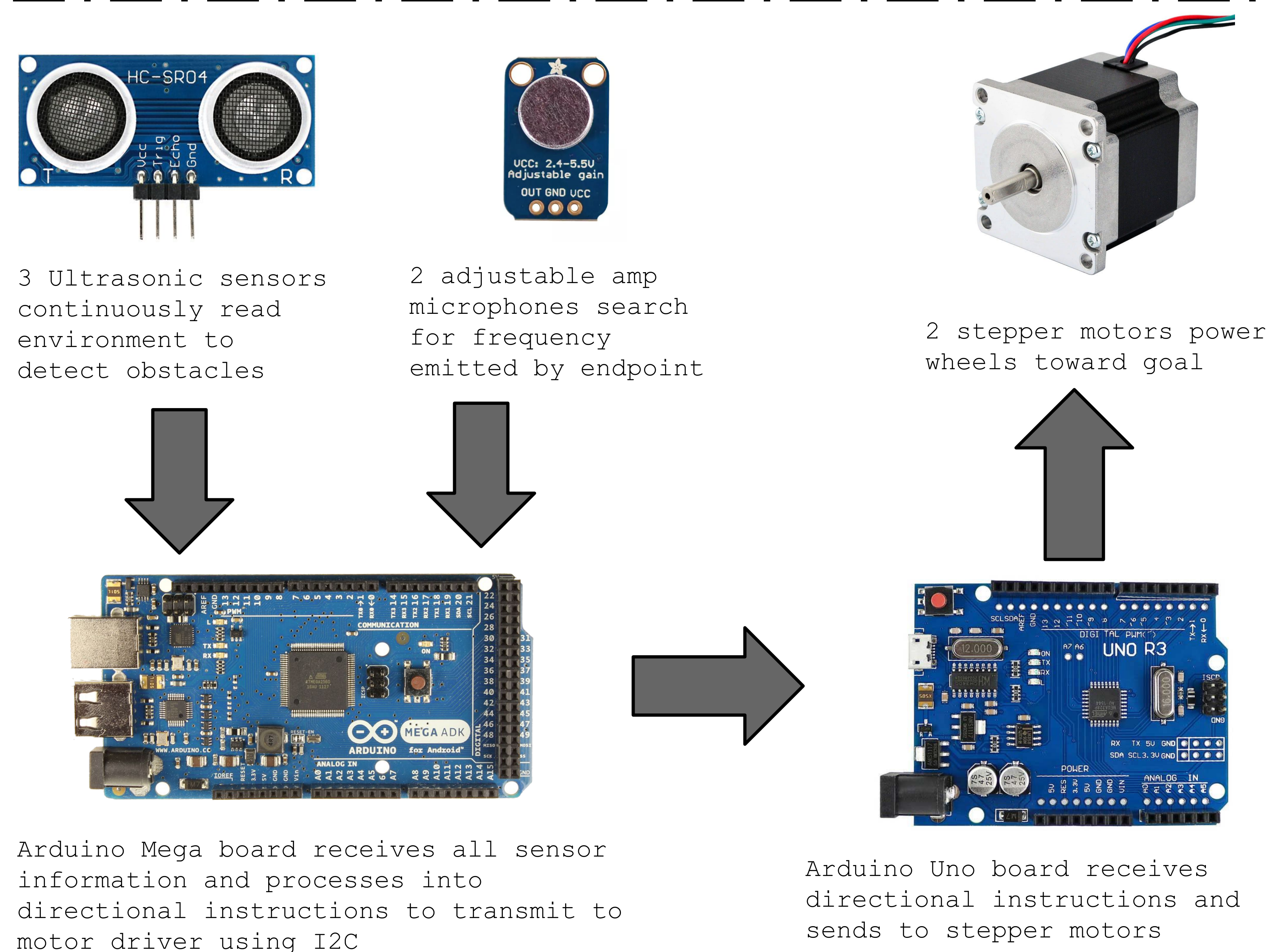
All components are mounted and wired to a hand cut and stained oak wood base.

Sensors angled for optimal detection of obstacles and endpoint frequency.



IMPLEMENTATION

KEY COMPONENTS



Thomas Doty - Evan Bissell - Matt Kravitz - Amber Yeasin

SHEEP SQUAD