

--- CoRo SLAM ---



AGV / AMR Lidar_Mapping_Navigating SLAM Software

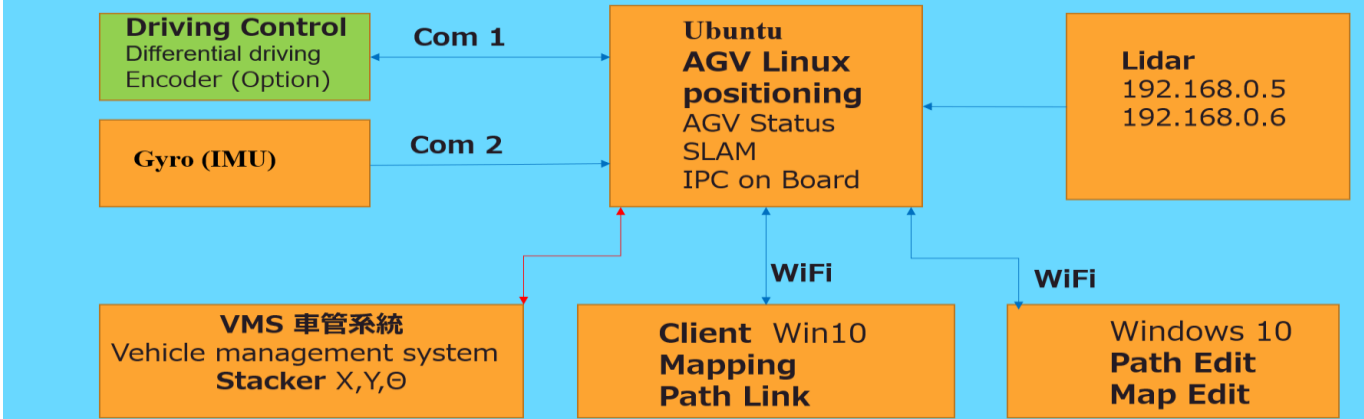
CoRo SLAM Features :

- * AGV/ AMR unmanned vehicle, lidar navigation, mapping, positioning and navigation
- * Lidar : SICK Lidar or PEPPERL+FUCHS Lidar
- * Natural contour positioning accuracy (+/-)2cm, Enable OdoFilter(+/-)1cm
- * AMR/ AGV moving speed 1m/sec (customization can be up)
- * Path planning can choose multi-path PathLink or AB two-point route
- * Forward, backward, in situ rotation, obstacle avoidance distance adjustment
- * Lidar can be single or double-lidar positioning
- * Provide 2 mapping methods (1) Real-time mapping (2) Calculate data and map after collected data
- * Map data can be exported and imported into Text File
- * Support wheel Odometry, encoder and gyroscope positioning navigation (IMU)
- * Support reflector positioning Reflector, no matter about dynamic environments
- * Support ten maps. Each map can be up to 40,000 square meters

Application :

- AGV / automated guided vehicles
- AMR
- Forklift AGV
- Autonomous Scrubber
- Service Robot
- Other mobile machine
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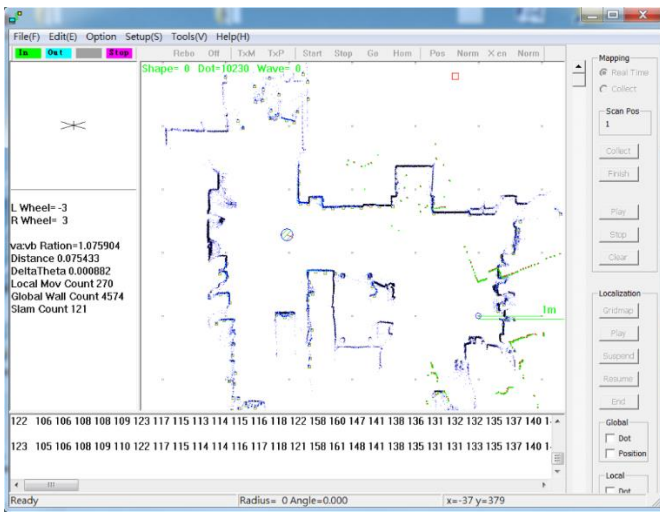
SLAM Simultaneous localization and mapping
即時定位與地圖構建



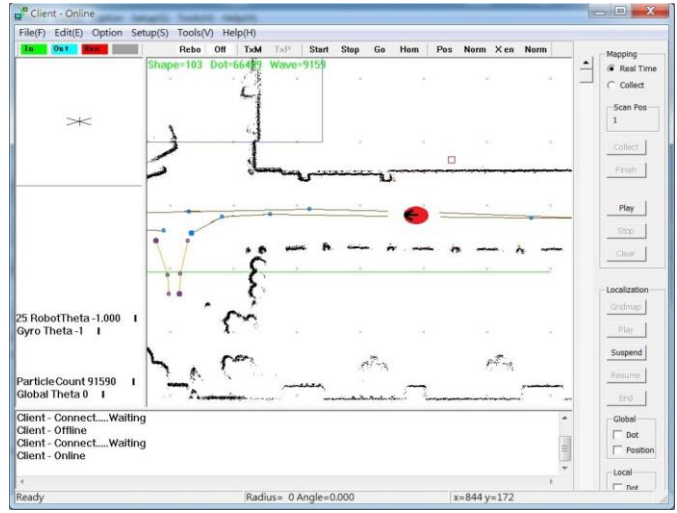
CoRo SLAM architecture diagram

Customer Benefits :

- * Mapping, path planning, navigation and driving control all in one , saving time and cost for development.
- * One-time authorization, permanent use, the more machines produced, the more profitable.
- * Accurate positioning, suitable for most occasions, eliminating the trouble of secondary positioning.
- * Natural environment positioning can also be used with reflectors, no matter with environmental changes or narrow alleys.
- * Equipped with a simple VMS, super-excellent CP value SLAM software, easy to use.
- * Non-ROS software, customization services can be provided to meet special needs.



Mapping



Path Planning & Navigating

Function Table for 3 Main Programs PathEdit, Client and AGV_Linux

Function\Application Software	PathEdit	Client	AGV_Linux
Lidar Scan Mapping	No	Yes	No
Lidar Reflector Mapping	No	Yes	No
Lidar Positioning	No	Yes	Yes
Reflector Positioning	No	No	Yes
Odometry Positioning	No	No	Yes
Path Link	Yes	No	Yes
Path Planning(Edit)	Yes	No	No
Map Edit	Yes	No	No
AGV_Linux Status Monitor	No	Yes	No
AGV_Linux Config	No	Yes	No

