IMPLEMENTATION CAMERA VISION FOR OBJECT TRACKING IN QUADRUPED ROBOT

By

Jason Fernandez Tatuil Gosal
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SWISS GERMAN UNIVERSITY
EduTown BSD City
Tangerang 15339
Indonesia

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STATEMENT BY THE AUTHOR

I hereby declare that this submission is my own work and to the best of my knowledge, it contains no material previously published or written by another person, nor material which to a substantial extent has been accepted for the award of any other degree or diploma at any educational institution, except where due acknowledgement is made in the thesis.

Jason Fernandez Tatuil Gosal

Student _____ Date _____

Approved by:

Dr. Rusman Rusyadi, B.Eng., M.Sc

Thesis Advisor _____ Date _____

Erikson Ferry S. Sinaga, ST., M. Kom

Thesis Co-Advisor _____ Date _____

Dr.Ir. Gembong Baskoro, M.Sc.

Dean _____ Date _____

ABSTRACT

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By

Jason Fernandez Tatuil Gosal
Dr. Rusman Rusyadi, B.Eng., M.Sc, Thesis Advisor
Erikson Ferry S. Sinaga, ST., M. Kom, Thesis Co-Advisor

SWISS GERMAN UNIVERSITY

The purpose of this thesis is to develop a quadruped robot and to implement camera vision system for object tracking. The camera vision system intended to be used for tracking an object while the legged robot will be move to follow the object.

The main scope of the thesis is the development of the camera vision system which enables the robot to tracking a particular object and the performance of the robot while moving.

The robot will be controlled manually using Laptop and automatically by using camera to detect object. The input command will be transmitted wirelessly using Wi-Fi adapter as the communication media.

Keywords: Legged Robot, Quadruped Robot, Inverse Kinematics, Object Tracking

DEDICATION

I dedicate this works for the almighty God, myself, my family, my lecturers, SGU, my country Indonesia, and to all the people who supported me and gave me the opportunity to learn.

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