Name of vehicle: MSAS
Name of team leader: Janusz Będkowski
Team Name: IMM-MSAS
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Return form to: elrob@elrob.org
Team Description: Our team is working on autonomous mobile mapping system. Our goal is to provide accurate 3D maps in real time. We are focused on parallel implementation of 6DSLAM integrated with ROS (Robot Operating System). Our platform is Husky from ClearPath robotics equipped with 3D measurement unit provided by MANDALA.

Sponsors: MANDALA (www.mandalarobotics.com)

Selection of scenario:

- X Reconnoitring of structures (focus on radiological and nuclear measuring and mapping)
- ___ Mule (shuttle between two locations)
- ___ Movements / Convoying (transport with two vehicles)
- ___ Search & Rescue (SAR) / MedEvac (find and drag a dummy body)
- ___ Reconnaissance and disposal of bombs and explosive devices (EOD/IED; **for professionals only!**)

Proof of citizenship:: A copy of team leader passport will do (will not be published)!

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