Notes: tutor meeting 1:

Date: 29-03-2017

Absent: None, (Casper not invited)

General notes:

* Scum was not yet used until now. But the tasks were properly defined with the expected time. Scrum will need to be implemented from now on.
* Scrum options: Onnu Puts scrum board, Scrum online, for example with GitHub.
* Spin of learning goals need to be send to Sjriek ASAP.
* The project will be graded. A passing grade is needed for the project to pass the minor.
* Bas will be responsible for communicating with Sjriek.
* Robot collision package (Bas knows what).
* Possibility to clean the laptops of the turtlebots so bots of the other group can be used (of course with some sort of backup). Sjriek will handle this task.
* Next meeting time: Monday after the pitch or Wednesday.

Notes about the Plan of Approach:

* Not very extensive, but enough.
* Requirement about most efficient time (R2R), was unclear. This will need to be formulated properly.
* Interesting with time efficiency: testing to see if it is really more time efficient. And also, to test if it is also more energy efficient.
* Swarm is currently defined as a requirement, but should be a wish. The requirement should be decentralized control.
* Requirements about the products (like weight and size) are to be defined by the project group (done).
* About the requirement: *There has to be a structured docking/charging sequence.* Possibility of a peak work load of the bots should be accounted for.
* More research/ideas are needed about the specialized robots and these specializations need to be defined. Current ideas: many light/small products, one heavy/big product.
* Sjriek would like us to use as much local communication as possible.

Notes about the Pitch of next Monday (03-04-2017):

* Attending the pitches is mandatory, with the exception if you have an exam at that time.
* Goal of the pitch: share knowledge with other students and tutors of other groups.
* What we should do for the pitch: just present the project for a few minutes, see the mail about it.

Notes about Swarm ideas:

* Somehow leave trails to follow for other bots.
* If a bot has found a ‘interesting’ spot (products are there) then the bot will communicate with other bots about that spot.
* Give central information about what products are where to the bots, the bots communicate about which bot does what.
* Static Loading points may be placed in the map. Can be in combination with a docking point.
* Smart loading points that communicate with the bots is also a possibility.
* Using a bot as a temporary smart loading point is also a possibility.
* Let bots search for load points. When found, the bot communicates with other bots it encounters and tells them about the load point.
* Robot mapping project for info. This was done with turtlebots, decentralized control, autonomous driving. Bots communicated with each other and updated each other’s maps.

To Do’s:

* Scrum will need to be implemented from now on.
* Spin of learning goals need to be send to Sjriek ASAP.
* Requirement about most efficient time (R2R), was unclear. This will need to be formulated properly.
* Swarm is currently defined as a requirement, but should be a wish. The requirement should be decentralized control.
* About the requirement: *There has to be a structured docking/charging sequence.* Possibility of a peak work load of the bots should be accounted for.
* More research/ideas are needed about the specialized robots and these specializations need to be defined. Current ideas: many light/small products, one heavy/big product.
* Make a presentation for the pitch next Monday.
* Other to do’s according to the planning.