**Project Status Report**

|  |  |
| --- | --- |
| **Project Name** | Elevator CAN bus system |
| **Team Members** | Chris Brown, Jack Morgan |
| **Report Date** | 2014-05-26 |

**Project Overall Status: Green**

After the first three weeks of the Elevator CAN bus system project, we have so far managed to get loopback CAN bus frames working on the Axman dev board and created an interface for the sonar senor board in order to measure distances. Initial code setup for the CAN bus on the HCS12 was a bit lengthy at first because of all of the registers involved, but after this work is done the CAN bus code can be reused on all other CAN nodes in the system. The sonar sensor interface currently has an LCD module attached to an Axman board displaying the current measured distance.

**Activities – During the Past Week**

|  |  |  |
| --- | --- | --- |
| **Activity** | **Planned Completion Date** | **% Complete** |
| CAN bus module initialization code | 2014-05-26 | 100 |
| Interface with sonar sensor on Axman board | 2014-05-26 | 100 |
| Create data protocol collectively with other project group | 2014-05-26 | 100 |
| LCD display module on Axman board | 2014-05-26 | 100 |

**Activities Planned – For the Next Week**

|  |  |
| --- | --- |
| **Activity** | **Planned Completion Date** |
| Send/receive CAN messages across at least two physical nodes | 2014-05-30 |
| Integrate CAN bus module init code with sonar distance measuring code | 2014-05-30 |
| Construct “call boxes” consisting of proto boards with buttons attached to an Axman board | 2014-05-30 |
| Successfully send a CAN message when a call button is pressed, and receive it at the controller node | 2014-05-30 |

**Outstanding Issues**

|  |  |  |  |
| --- | --- | --- | --- |
| **Issue** | **Responsibility** | **Date to be Resolved** | **Proposed Resolution** |
| None | - | - | - |

**Changes to Plan**

|  |  |  |
| --- | --- | --- |
| **Change** | **Date of Change** | **Impact to Project** |
| No changes | - | - |