22/8/21

Replan and re-strategize

Things done:

- Changing of ideas
- Researching of guides
- Sourcing for new components (Nvidia Jetson Nano)
- Reading up on the usage of new parts
- Sketch of the camera system done by Ryan

Current state of project:

- Decided to mount the camera's servo motor onto the ceiling, allowing panning and tilting of the camera
- Camera will send coordinates to the autonomous robot in the case of a rule violation of a cluster
- Once the robot reached its destination, an action will happen to inform the cluster of rules being breached (current idea is to release a helium balloon)

Problems faced:

- The plan of placing the Jetson Nano onto the other side of the false ceiling (the one opposite of the camera) brought about challenge to connect both the camera and the Jetson Nano with wire due to the false ceiling itself.

- Current materials needed are quite expensive (Jetson Nano, Lidar, autonomous robot)

Work to be done:

- Finding a way to bring the wire across the ceiling from the camera to the Jetson Nano
- After solving the problem for the wire connection between the camera and the Jetson Nano, design a 3D CAD model for the system
- Reading up the documentation of the Jetson Nano library
- Continue sourcing for cheaper and more cost-effective components