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| **Software Engineering and Project - Milestones to be demonstrated in week 9** | |
| **Group Number: 02** | |
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| **Features to be demonstrated** | **Features demonstrated**  **(Will be marked by the client/lecturer)** |
| 1. The Rover should be able to interpret sensor data. Specifically the colour sensor should be able to distinguish between No-Go Zones, boundary lines, craters, radiation, footsteps and rover trails. The gyro sensor, ultrasonic sensor, and touch sensor must be able to send data to the rover for use (can be demonstrated by simply displaying the value returned on LCD). |  |
| 2. The Rover should be able to respond to sensor data and adapt its movement in the following ways:   * It should avoid going outside the boundaries * It should attempt to go around obstacles (physical objects, No-Go zones, craters) * If the rover collides with an object and activates the touch sensor it should back off * If the rover detects a physical object with the ultrasonic sensor it should back off and go around |  |
| 3. The GUI should display information about areas the rover has tracked. This information includes no-go zone locations, physical object locations, current rover location, radiation detected, footsteps found, craters found, and boundary lines. |  |
| 4. The Rover should be able to move autonomously in our physical map obeying the rules specified by the above goals. |  |

**Signatures**

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