Project Evaluation - Questionnaire

Thank you for taking part in the evaluation! If you could please complete the following questions to the best of your ability.

What phone model did you use during the evaluation? *

Iphone SE

Intuitiveness and Ease of Use

This section will ask you questions regarding how easy the controller was to learn and use

How difficult did you find changing the settings on the robot?

This includes looking at the User Manual if needed

Very easy

- 1 (selected)
- 2
- 3
- 4
- 5
- 6
- 7
- 8
- 9
- 10

Very difficult

How difficult did you find connecting to the robot?

This includes looking at the User Manual if needed

Very easy

- 1 ○
- 2 ○
- 3 ○
- 4 ◉
- 5 ○
- 6 ○
- 7 ○
- 8 ○
- 9 ○
- 10 ○

Very difficult

How difficult did you find setting up the Virtual Lead feature?

This includes looking at the User Manual if needed

Very easy

- 1 ○
- 2 ○
- 3 ○
- 4 ○
- 5 ○
- 6 ○
- 7 ◉
- 8 ○
- 9 ○
- 10 ○

Very difficult

Overall, how intuitive did you find the controller to use (i.e. was it easy to learn **without** the user manual)?

Not intuitive at all

- 1 ○
- 2 ○
- 3 ○
- 4 ○
- 5 ○
- 6 ○
- 7 ◉
- 8 ○
- 9 ○
- 10 ○

Very intuitive

How often did you have to consult the user manual?

- ○ Not at all
- ◉ A couple of times
- ○ Quite often
- ○ A lot

If you used it, how helpful was the user manual in teaching you what to do?

Not very helpful

- 1 ○
- 2 ○
- 3 ○
- 4 ○
- 5 ◉
- 6 ○
- 7 ○
- 8 ○
- 9 ○
- 10 ○

Very helpful

Any other feedback regarding intuitiveness of the controller or the user manual?

With better latency the camera controller would potentially be more usable !

Functionality and Responsiveness

This question will ask you questions regarding the responsiveness and functionality of the controller

Which angle-motor mapping did you prefer the best

- ○ Tight
- ◉ Loose

How difficult did you find it to navigate the robot around an **object** using either mapping on the **joystick**?

Very easy

- 1 ○
- 2 ○
- 3 ○
- 4 ○
- 5 ○
- 6 ◉
- 7 ○
- 8 ○
- 9 ○
- 10 ○

Very difficult

How difficult did you find it to navigate the robot through the **slalom** using either mapping on the **joystick**?

Very easy

- 1 ○
- 2 ○
- 3 ○
- 4 ○
- 5 ○
- 6 ◉
- 7 ○
- 8 ○
- 9 ○
- 10 ○

Very difficult

How difficult did you find navigating the robot around the **object** using the **Virtual Lead** feature?

Very easy

- 1 ○
- 2 ○
- 3 ○
- 4 ○
- 5 ○
- 6 ○
- 7 ○
- 8 ○
- 9 ◉
- 10 ○

Very difficult

How responsive did you find the joystick to use?

Did it start and stop when you wanted it to? Did it respond well to movements of the joystick?

Not very responsive

- 1 ○
- 2 ○
- 3 ○
- 4 ○
- 5 ○
- 6 ○
- 7 ○
- 8 ◉
- 9 ○
- 10 ○

Very responsive

How responsive did you find the Virtual Lead feature to use?

Did it start and stop when you wanted it to? Did it respond well to movements of the camera?

Not very responsive

- 1 (selected)
- 2
- 3
- 4
- 5
- 6
- 7
- 8
- 9
- 10

Very responsive

Competition Website

This section will ask you questions regarding the website for the competition

What is your understanding of what the competition is?

A competition to measure robotic self driving coding ability for a track

Were the rules easy to find and clear to read?

Yes

Would you be interested in entering such a competition?

If I knew about the techology more then maybe

Final Feedback

This section is for any final feedback regarding the controller and competition website.

Did you experience any problems while using the **controller**? If so please detail then below

Just adjusting to the controls but after a bit it became easier to control using the joystick. The leed however was harder to use.

Do you have any more feedback to provide about the **controller**?

This can include any features you wished the controller had or any improvements to its design or functionality

I think there should be a clearer indication whether the robot has been connected or not

Do you have any more feedback to provide about the **competition website**?

This can include any features you wished the controller had or any improvements to its design or functionality