Capstone sponsor meeting 2/19/16:

Demo of cylindrical object data.

Demo of bounding box for same cylindrical objects.

* Advised to consider a plane that is above the height of the objects that we are looking at to help remove noise and unnecessary data points.

Video of the Paraview PCL Tool.

* They liked the idea of us using this tool to validate our algorithms.
* A good high level goal would be to get our algorithm working and simulate it using Paraview for demo and verification purposes.

Discussed developing a coordinate system that would be helpful to robotics developers.

* Advised not to spend too much time developing the coordinate system and algorithms for robotics because it may take too much effort away from the main project.
* Advised to use Rectified mode in order to reduce data noise.

Showed a PCL RealSense API that was found on Github.

* Advised that the RealSense functionality there is for a Windows operating system, so it will not be very useful to us directly. It still may be useful for finding a good approach to a Linux version.

Showed our requirements document.

* Advised to add specifics, such as minimum performance expectations.
* Advised to use the term “as measured by”.
* We should coordinate with the other team to determine the format of our deliverables.
* The NUC needs to be loaded with Linux 14.04.03 to allow it to use the camera and have OpenCL support.

For next meeting: We should have a contract that documents how our team’s work will interface with the other team’s work.