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**Weekly Report (WEEK 7)**

**Company Name:** OJO **17/11/2017**

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**Introduction**

This week we we acquired components for our project and did some basic test on those components. Furthermore, we had some meetings to discuss our action plan. We also had a standards committee meeting this week so we prepared for it. We really wanted to have an edge in this project, so we felt that being able to set the standards would help us in that.

**Component Acquisition**

1. **Arduino Uno**
2. **Ultrasonic Sensor**
3. **Supporting Circuitry**

It is also discussed what to buy next. For the image processing, a camera and raspberry pi needs to be purchase. As discussed, we determined that the image processing will be one of the solutions for following the robot. Since it is an important submodule, we wanted to get a head start on it. In addition to these, it is decided that a chassis for the robot is going to be bought.

**Second Standards Committee**

We held a meeting within our group members to finalize what we will discuss in the second committee meeting. In the standards meeting, following decisions are made.

* For visibility markers, there will be a rectangle which is filled green and has dimensions of 14cm\*10cm. The center of gravity of the rectangle will be 20 cm above from the bottom end of the robot and in the middle of the horizontal edges.
* The maximum speed of the leading robot is 20 cm/s. Moreover, when a leaving signal is given to a follower, the leading cannot change its direction. In addition, there cannot be a leave signal if the leader is turning.
* The back side of the robot has to be a flat surface.
* The robots have to have the capability to leave the convoy from both left and right.

**Action Plan**

We devised our immediate action plan. We have decided to parallelize the next phase of the project, the testing and selection of components. There can be two subgroups, one subgroup can handle the chassis of the robot and the motor as well as the motor drivers while the other sub group can handle the sensors and transmitters. Since the two tasks are independent of each other we chose this strategy to maximize our efficiency.