# Table of Contents

- Motor controller
- Joystick

**Lessons learned**

- Todo & Advice
- Lessons Learned

**Archive**

- Previous Groups
- Research Archive
- Skylab Architecture
- Skylab
- Multi master
- WillyWRT
- Realisation
- Hardware
- Brain
- Design Guild
- Social interaction
- Speech
- Speech recognition
- IMU
- Human Detection
- Radeffect App

# Kinect

## 1. Development choices

When analysing Willy the group of 2019 Semester 1 came to the conclusion that there where problems with Willy detecting objects at certain heights. To come up with a soloution the group researched different sensors to find the right one for object detection on certain heights. As a result the Kinect was chosen as it suited the needs and was available to use.

## 2. Kinect Specs

The version of the Kinect is version 1. That is because it was available to use and meant no delays in the project while waiting for the product to arrive. In the future it might be a good idea to upgrade to a Kinect 2 as the Kinect 2 has better specs.

| Feature | Kinect 1 |
| --- | --- |
| Color Camera | 640 x 480 @30 fps |
| Depth Camera | 320 x 240 |
| Max Depth Distance | apr. 4.5 m |
| Min Depth Distance | 40 cm in near mode |
| Depth Horizontal Field of View | 57 degrees |
| Depth Vertical Field of View | 43 degrees |
| Tilt Motor | Yes |
| Skeleton Joints Defined | 20 joints |
| Full Skeletons Tracked | 2 |
| USB Standard | 2.0 |