Minutes of the Third Client Meeting

Coding Pharaohs (Group 2)

August 26 , 2013

Chair	Bowen Tao
Secretary	Jianqiu Li
Members	Yifei Pei
	Matthew Nestor
	Abdulaziz Alhulayfi
	Yu Hong
Apologies	None

1 Time and Place

The third client meeting for Software Engineering and Project was held in **Ingkarni Wardli, Room 462** at **2:30pm** on **Monday 26 August 2013**.

2 Quorum Announcement

Having determined that quorum was satisfied, the Chairman Mr. Bowen declared the meeting open.

3 Summary of Previous Meeting

Yu Hong and JianQiu Li make a description about the prototype of the robot. They explained the function of the prototype of the robot and provided the reason of constructing this prototype. Then, the other group members asked more questions in terms of the functional requirements, such as the the road closure and the information of the map.

4 Group Milestone: SRS presentation

4.1 Overview

JianQiu Li made a presenation about SRS document

4.2 SRS Detailed Presentation

- JianQiu Li summarised the information which from SRS document, this includes the user requirements and some other non-functional requirements. All these information contribute to the system features which are the manual control and the automatic mapping function.

5 Individual Milestone Report: GUI mockup

5.1 Overview

YiFei Pei showed the GUI to the client

5.2 GUI Detailed Presentation

- According to the milestone of Week 5, YiFei Pei introduced the GUI mockups. In the presentation, the function of GUI includes
  - The GUI contains an area to display the map
  - some buttons of robot movement controls
  - dangerous zone editing
  - The buttons of map loading and saving
  - The GUI can display the operator feedback
  - robot representation
  - Battery life and bluetooth signal representations on GUI

6 milestone negotiation for Week 9 and 10

The group submitted the milestone form for Week 9 and Week 10 to the client.

Milestone Form

Group Number: 2

Week

Features Being Demonstrated

No.	Planned Features	Featur Demo (tick if
1	GUI: depict the area explored by robot – real-time generation	
2	GUI map show: representation of different structures	
3	GUI map show: robot representation: location and face	
4	The ability of saving new map	
5	Communication: initiating connection	
6	ensure real-time control with connection	
7	show real-time messages on GUI	
8	manual mode of robot: move and rotate	
9	manual stop robot and mark road closure	
10	Safety: low movement speed (5cm/s)	
11	Map site testing: A1 sized map with basic features	
12	road closure marking on real map	
13		
14		
15		

Group Number: 2

Week

Features Being Demonstrated

No.	Planned Features	Featur Demo (tick if
1	GUI map display smaller full size view on side larger partial view in centre	
2	Show transversed path by the robot	
3	AI mode of robot : automatically follow road and explore	
4	obstacle and disater area avoidance	
5	automatically road closure marking	
6	after stop, ability to continue AI mode exploration	
7	Exit on AI mode after completion	
8	mechanism for mission completion control	
9	Communication: detect battery life & signal and show	
10	safety: when collision happen, stop	
11	low power: stop and warn operator	
12	lost of connection: stop, turn to manual mode once recover	
13	Once robot reaches edge of disaster zone, stop	
14	obstacles on real map and test	
15		

7 Requirements Elicitation

The majority of the meeting consisted of interviewing the client for project requirements. A paraphrased summary of the questions, and client answers, follows:

7.1 Functional Requirements

1. **Mr. Nestor:** From the DTD, the road are perpendicular to each other, Do they have constant turning angles or not?
   Client: There are many cases in real situtation, we should assume all the condition of the roads. Thus, the road can be any cases, and use line statement on XML.

2. **Mr. Bowen:** What is the physical shape of the obstacles and intersections ? how to distinguish them?
   Client: The physical shape of the obstacles should be a cycle and you can use different colours to distinguish them. The robot also need to detect the shape of obstacles and draw on the map

8 Meeting Feedback

The tutor gave the group some feedback for its performance in its third client meeting. The following is a summary of the key points.

- we should prepare details of milestone 9,10 next week that get the feedback

- we should add the speed button on the GUI which can control the speed of the robot. This is for the emergency cases which can make the robot get the emergency place quickly

- We should change the size of some buttons, for example the stop button, we need make it more visable

9 Adjournment

The next meeting is a group meeting to be held in the same place, namely Ingkarni Wardli, Room 462 at 2:30pm on Thursday 2 September 2013.
The meeting will close around 3:10pm.