| code | task | out | remarks | error | error_status | | | | |
|---|---|---|---|---|---|---|---|---|---|
| motor_ping_test_001 | basic movment forward | PASS | change mapping of M2 for getting clockwise rotation | | | | | | |
| motor_ping_test_001 | basic movment backward | PASS | NO | | | | | | |
| motor_rotation_test_001 | counter_clockwise(LEFT) | PASS | M1 -- FORAWARD M2 - BACKWARD | | | | | | |
| motor_rotation_test_001 | _clockwise(RIGHT) | PASS | M1 -- BACKWARD M2 - FORWARD | | | | | | |
| ultrasonic_test | test ultrasonic sensor | PASS | error = 2cm, delay (1second) | | | | | | |
| motor_ping_test_001 | for 90 degree rotation delay calculation | PASS | delay for 90 degree rotaion K = 2.5(2500) | | | | | | |
| Algoritham testing | | | | | | | | | |
| | | | | | | | | | |
| centro_001 | setting x coordinate | FAIL | | | | | | | |
| centro_002 | setting x coordinate | FAIL | | | | | | | |
| centro_003 | setting x coordinate | FAIL | | | | | | | |
| centro_004 | setting x coordinate | FAIL | | | | | | | |
| centro_005 | setting x coordinate | PASS | | | | | | | |
| centro_006 | setting x coordinate | PASS | add proper engine stop, change the condition of while with note operator ,add steb function throughout the process | delay weigth is not properly calculated | RESOLVED | | | | |
| | | | | motor shaft problem | NOT RESOLVED | | | | |
| centro_007 | resolve delay weigth issue | FAIL | | | | | | | |
| centro_007.1 | resolve delay weigth issue | PASS | change the equation of delay w to w + w0 | | | | | | |
| centro_006_MASTER_X_coordinate | setting x coordinate | PASS | | | | | | | |
| | | | | | | | | | |
| centro_y_002 | setting Y coordinate | FAIL | | | | | | | |
| centro_y_003 | setting Y coordinate | PASS | change mapping from tx and rx connection from board | | | | | | |
| centro_y_002.01 | setting Y coordinate | FAIL | | | | | | | |
| centro_y_002.02 | setting Y coordinate | PASS | change measuring code in both while loop | | | | | | |

| | | | | | | | | | |
|---|---|---|---|---|---|---|---|---|---|
| centro_y_002_MASTER_Y_coordinate | setting Y coordinate | PASS | NO | need to re design the delay weigth calculation | RESOLVED | | | | |
| | | | | | | | | | |
| steb002 | Sstebilization | FAIL | | | | | | fixing Algoritham | |
| steb004.01 | for caliberation test | PASS | | | | | | x_distance | PASS |
| steb004.02 | caibaration + fixing | FAIL | | | | | | Y_distance | PASS |
| steb004.03 | caibaration + fixing | FAIL | | | | | | break | PASS |
| steb004.04 | caibaration + fixing | FAIL | | | | | | delay w calculation | PASS |
| steb004.05 | caibaration + fixing | PENDING | partial output all conditions are not satisfied | need to re design some conditions in stebilization algorithm | RESOLVED | | | loop break | PASS |
| steb005 | fixing | FAIL | | | | | | | |
| steb006 | fixing | PENDING | partial out | | | | | | |
| steb007 | fixing | PENDING | partial out | | | | | | |
| steb008 | fixing | PASS | remove caliberation from stebilization algorith | re construct stebilization with new fixing method for LSH and RSH side | RESOLVED | | | | |
| steb009 | fixing | PASS | need improve | | | | | | |
| steb0010 | fixing | PASS | | | | | | | |
| steb0010.01 | fixing | PASS | | | | | | | |
| steb0010.02 | fixing | PASS | re designed all conditions in stebilization algorithm | | | | | | |
| stebilizer_module_001 | stebilizer | PASS | | | | | | | |
| stebilizer_module_002 | stebilizer | PASS | | | | | | | |
| stebilizer_module_003 | stebilizer | PASS | master | | | | | | |
| | | | BOT_STEBILIZER_V01 | | | | | | |
| | | | | | | | | | |
| corn001 | corner left | PASS | without stebilizer | | | | | | |
| | | | | | | | | | |
| stebilizer_module_004 | with poiter and ornt | FAIL | | | | | | | |
| stebilizer_module_005 | with poiter and ornt | FAIL | not compulsory but need a separete function test | | | | | | |
| stebilizer_module_003.01 | with orintation | PASS | stable version | | | | | | |
| | | | BOT_STEBILIZER_V02 | orientationerror | RESLOVED | | | | |
| stebilizer_module_003.02 | modification | PASS | | referance line error | RESLOVED | | | | |
| stebilizer_module_003.03 | modification | PASS | | | | | | | |

| | | | | | | | | | |
|---|---|---|---|---|---|---|---|---|---|
| corn002 | corner left with stebilization | FAIL | | | | | | | |
| corn003 | corner left with stebilization | PASS | | | | | | | |
| | | | | | | module | test case | out | remarks |
| sqr002 | sqr algorithm | PASS | need improvment | | | BOT_STEBILIZER_V03.01 | !(internal_y == GLOBEL_Y && internal_x == GLOBEL_X) | PASS | not expected out |
| sqr002.01 | sqr algorithm | PASS | | | | | !(internal_y <= GLOBEL_Y && internal_x == GLOBEL_X) | FAIL | |
| sqr003 | sqr algorithm | PASS | | | | | !(internal_y == GLOBEL_Y && internal_x <= GLOBEL_X | FAIL | |
| sqr003.01 | sqr algorithm | PASS | | | | | !(internal_y < GLOBEL_Y && internal_x < GLOBEL_X | FAIL | |
| sqr004 | sqr algorithm | PASS | | | | | !(internal_y <= GLOBEL_Y && internal_x <= GLOBEL_X) | FAIL | need to change the stebilization algoritham |
| sqr005 | sqr algorithm | PASS | | | | | | | |
| sqr005.01 | sqr algorithm | PASS | | | | | | | |
| sqr006 | sqr algorithm | PASS | | | | | | | |
| stebilizer_module_003.01 | stebilization_rror fixing | FAIL | | | | | | | |
| stebilizer_module_003.02 | stebilization_rror fixing | FAIL | | | | | | | |
| stebilizer_module_003.03 | stebilization_rror fixing | FAIL | | | | | | | |
| stebilizer_module_003.04 | stebilization_rror fixing | FAIL | | | | | | | |
| stebilizer_module_003.05 | stebilization_rror fixing | FAIL | | | | | | | |
| stebilizer_module_003.06 | stebilization_rror fixing | FAIL | | | | | | | |
| stebilizer_module_004 | stebilization_rror fixing | FAIL | | | | | | | |
| stebilizer_module_005 | stebilization_rror fixing | FAIL | drop common steblilizer concept | | | | | | |
| | | | | | | | | | |
| left_rotator | left rotaion with 90 degree | FAIL | | | | | | | |
| left_rotator001 | left rotaion with 90 degree | FAIL | | | | | | | |
| left_rotator002 | left rotaion with 90 degree | FAIL | | | | | | | |
| left_rotator003 | left rotaion with 90 degree | FAIL | | | | | | | |
| left_rotator004 | left rotaion with 90 degree | FAIL | | | | | | | |
| left_rotator004_ornt_1_conditio_corner | left rotaion with 90 degree | FAIL | | | | | | | |

| | | | | | | | | | |
|---|---|---|---|---|---|---|---|---|---|
| left_rotator004_ornt_1_conditio_side | left rotaion with 90 degree | FAIL | | | | | | | |
| right_rotator_corner_001 | l rotaion with 90 degreright | FAIL | issues happens in the part of corners so change or make a program to eliminate the corner internally | | | | | | |
| | | | | | | | | | |
| orner_eliminator001 | corner eliminaion | PASS | partial out | | | | | | |
| orner_eliminator001_left | corner eliminaion | PASS | partial out | | | | | | |
| orner_eliminator001_right | corner eliminaion | PASS | not appicable | | | | | | |
| | | | | | | | | | |
| angle_measurment | apply cose and cose angole measurment | FAIL | | | | | | | |
| sqrt | apply cose and cose angole measurment | FAIL | 0 is not calculatedd properly(invese trignomeric function not working propery in c++) | | | | | | |
| triagle_fix_method | usimg pythagorus princple | FAIL | | | | | | | |
| triagle_fix_method_A | usimg pythagorus princple | FAIL | | | | | | | |
| triagle_fix_method_angle_measurment | usimg pythagorus princple | FAIL | | | | | | | |
| triagle_fix_method_B | usimg pythagorus princple | FAIL | not working axis is changing with each measurments | strbilization not working | RESOLVED | | | | |
| | | | | | | | | | |
| h1 | normal delay | FAIL | we need athor input for make stebilization current method is not suted for the stebilization measurments | HIGH PRIORITY | | | | | |
| left_rotator | normal delay | FAIL | | | | | | | |
| left_rotator_gyro_001 | with MEMS | PASS | | | | | | | |
| left_rotator_gyro_002 | with MEMS | PASS | | | | | | | |
| left_rotator_gyro_003 | with MEMS | PASS | | | | | | | |
| left_rotator_gyro_004 | with MEMS | PASS | | | | | | | |
| left_rotator_no_fixer | with MEMS | PASS | | | | | | | |
| left_rotator_with_fixer | with MEMS | PASS | | | | | | | |
| org_left_rotator_001 | with MEMS | PASS | | | | | | | |
| org_left_rotator_002 | with MEMS | PASS | | | | | | | |
| | | | | | | | | | |
| gy0001 | caliberation with gyro | PASS | | | | | | | |

| | | | | | | | | | |
|---|---|---|---|---|---|---|---|---|---|
| gyro-1 | caliberation with gyro | PASS | | | | | | | |
| gyro-002 | caliberation with gyro | PASS | | | | | | | |
| new_01 | caliberation with gyro | PASS | | | | | | | |
| GYR0_001 | caliberation with gyro | PASS | | | | | | | |
| GYR0_002 | caliberation with gyro | PASS | | | | | | | |
| | | | | | | | | | |
| loader_001 | loader | PASS | integration of process sysytem with existing model | | | | | | |
| servo_testing_001 | sevo motor tesing | PASS | | | | | | | |
| | | | | | | | | | |
| mar_001 | margine fixer | PASS | | | | | | | |
| | | | | | | | | | |
| BOT_RIGHT_ROTATOR_V01 | | PASS | | | | | | | |
| BOT_RIGHT_ROTATOR_V02 | | PASS | | | | | | | |
| BOT_LEFT_ROTATOR_V01 | | PASS | | | | | | | |
| BOT_LEFT_ROTATOR_V02 | | PASS | | | | | | | |
| BOT_MARGIN_FIXER_V01 | | PASS | | | | | | | |
| BOT_LOADER_V01 | | PASS | | | | | | | |
| BOT_SQURE_WAVE_PROCESSOR_Beta_V01 | | PASS | | | | | | | |
| BOT_GYROSCOPE_V01 | | PASS | | | | | | | |
| BOT_CORNER_LEFT_FIXER_V01 | | PASS | | | | | | | |
| BOT_CENTRID_FINDER_V01 | | PASS | | | | | | | |
| | | | | | | | | | |
| intr_setup_001 | integartion of modules | PASS | | | | | | | |
| BOT_INTEGRATOR_V01 | | PASS | | | | | | | |
| BOT_INTEGRATOR_V02 | | PASS | | | | | | | |
| | | | | | | | | | |
| MASTER_CODE_ROVER_PRITHVI_V01 | FINAL CODE FOR ROVER | PASS | | | | | | | |