

Sprint Report #2

This sprint report is to inform you of the backlog completed during Sprint 2. During this sprint, our team continued to meet bi-weekly to discuss our plans in further detail as well as to work on a few adjustments to our robot. One of the small accomplishments of this sprint was an adjustment to the telecommunication code. The team requested a mining mode for the robot to allow it to drive slower while mining. This update worked with with all sides of our telecommunication code. We had to map a new button on our controller, as well as update our code on our PCDuino to receive the new signal from the xbox controller. Our motor controller code needed to be updated as well, and some rewiring was required on those motor controllers in order to allow another signal to be sent to it.

We also continued to work on our visual odometry. During this sprint, it was found out that the Landing Pad senior design team has an AR Tag visual odometry package written in ROS. We plan on working with the Landing Pad team to obtain this and begin working with and learning ROS.

The team also ordered an Odroid XU4 during this sprint, which we plan on using to run our autonomy code, as the PCDuino was ruled out as an effective device to do so.

Deliverables:

Began to learn ROS, as well as decided on all of the hardware required for the project.