Sprint 5 Retrospective Document

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Project acronym: ROBOCON-RT

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# Sprint 5 summary

|  |  |  |  |
| --- | --- | --- | --- |
| Item ID (from the previous retrospective doc) | Workpackage ID (from the Kick-off doc) | Status | Group’s comments |
| 1 | 1 | Dropped | We decided to continue with brushed motors |
| 2 | 6 | Dropped | We dropped this item so that we could replace it with more measurable and quantifiable small tasks. |
| 3 | 3 | Dropped | We dropped this because it was too ambiguous, so we are replacing it. |
| 4 | 4 | In progress | Motor experiments has been made by DriveWare Software. |

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# Sprint 6 plan

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| --- | --- | --- | --- |
| Item ID | Workpackage ID (from the Kick-off doc) | Description | Status |
| 4 | 4 | EtherCAT Master library: Write C code to directly control brushed motors | Leftover from Sprint 5 |
| 5 | 6 | Write custom Yocto module: Write a Yocto Linux module and compile and install it using BitBake | New |
| 6 | 8 | Sensors and Peripherals: Agree on and order peripheral types for the Demo Day | New |
| 7 | 4 | Motor Control: Design the EtherCAT motor drive control interface | New |
| 8 | 6 | Scenario Test: Test portability of RHexLib by installing it on UP2 computer | New |
| 9 | 6 | Reading Encoders: Improve the circuit to read encoders from motors to motor drive | New |
| 10 | 4 | Inspect the different implementations in RHexLib for motor control | New |

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# Overall progress

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
|  | Sprint 1 | Sprint 2 | Sprint 3 | Sprint 4 | Sprint 5 |
| MF1 | 0% | 5% | 15% | 25% | 25% |
| MF2 | 0% | 60% | 90% | 92% | 92% |
| MF3 | 66.67% | 73% | 84% | 100% | 100% |
| MF4 | 0% | 10% | 10% | 10% | 10% |
| MF5 | 16.6% | 45% | 76% | 80% | 82% |
| MF6 | 0% | 10% | 10% | 10% | 10% |
| MF7 | 0% | 0% | 0% | 0% | 0% |
| MF8 | 0% | 0% | 0% | 0% | 0% |
| MF9 | 13% | 14% | 15% | 20% | 25% |
| MF10 | 0% | 0% | 0% | 0% | 0% |
| MF11 | 100% | 100% | 100% | 100% | 100% |
| MF12 | 37% | 40% | 40% | 40% | 40% |