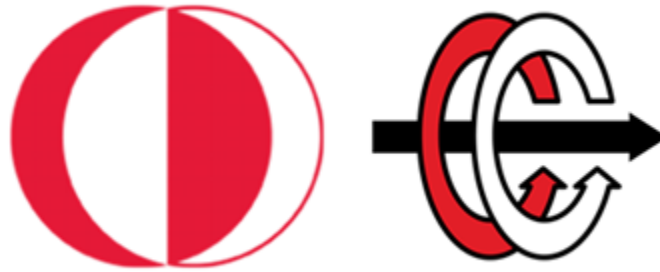


**MIDDLE EAST TECHNICAL UNIVERSITY
DEPARTMENT OF ELECTRICAL & ELECTRONICS
ENGINEERING**



**TROY TECH
WEEKLY REPORT #8
05.04.2019-09.04.2019**

Section : 7

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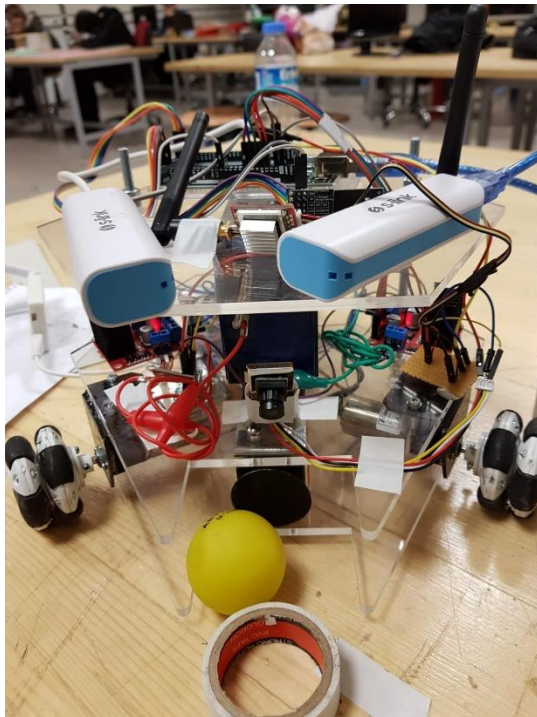
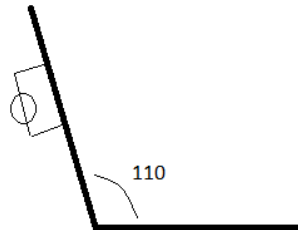
Mert KAYIŞ – 2030997

Progresses for Previous Week:

- We made communication tests after implemented the all the subsystems to the body. We tested it at D-building. We had approximately 60 m range for both command and video transfer.



- We used an L-shape metal in order to mount the camera to the body. We located this connection piece just above the solenoid and in front of the accumulator. We bended the L-shape metal and changed its angle to 115 degree in order to have the best camera view.



- Also, we made tests for camera angle and view. Our camera can view 2m-wide line which is 30 cm away from the position of our robot. It is approximately 160 degree.

- We purchased six pieces of 30cm * 75cm walls of the playfield as mentioned in the standard committee report. They are 8mm MDF plates. We also bought hinges in order to merge the walls.



- We changed the pin connection between the motor drivers and the arduino in order to have a neat cable array.

Plans for Next Week:

- Setting the playfield.
- Improving movement system
- Discussing and reassigning the buttons of joystick
- Communication tests at different locations (both indoor and outdoor)
- Designing the plates which will cover the robot and printing them out from the 3D printer.
- Power and cost analysis.