**MIDDLE EAST TECHNICAL UNIVERSITY**

**DEPARTMENT OF ELECTRICAL & ELECTRONICS ENGINEERING**



**TROY TECH**

**WEEKLY REPORT #8**

**05.04.2019-09.04.2019**

**Section :** 7

**Studio Coordinator:** Mustafa Mert ANKARALI

**Partners :**

Hasan ÖZKARA - 2031888

Kağan ÖZASLAN - 2031854

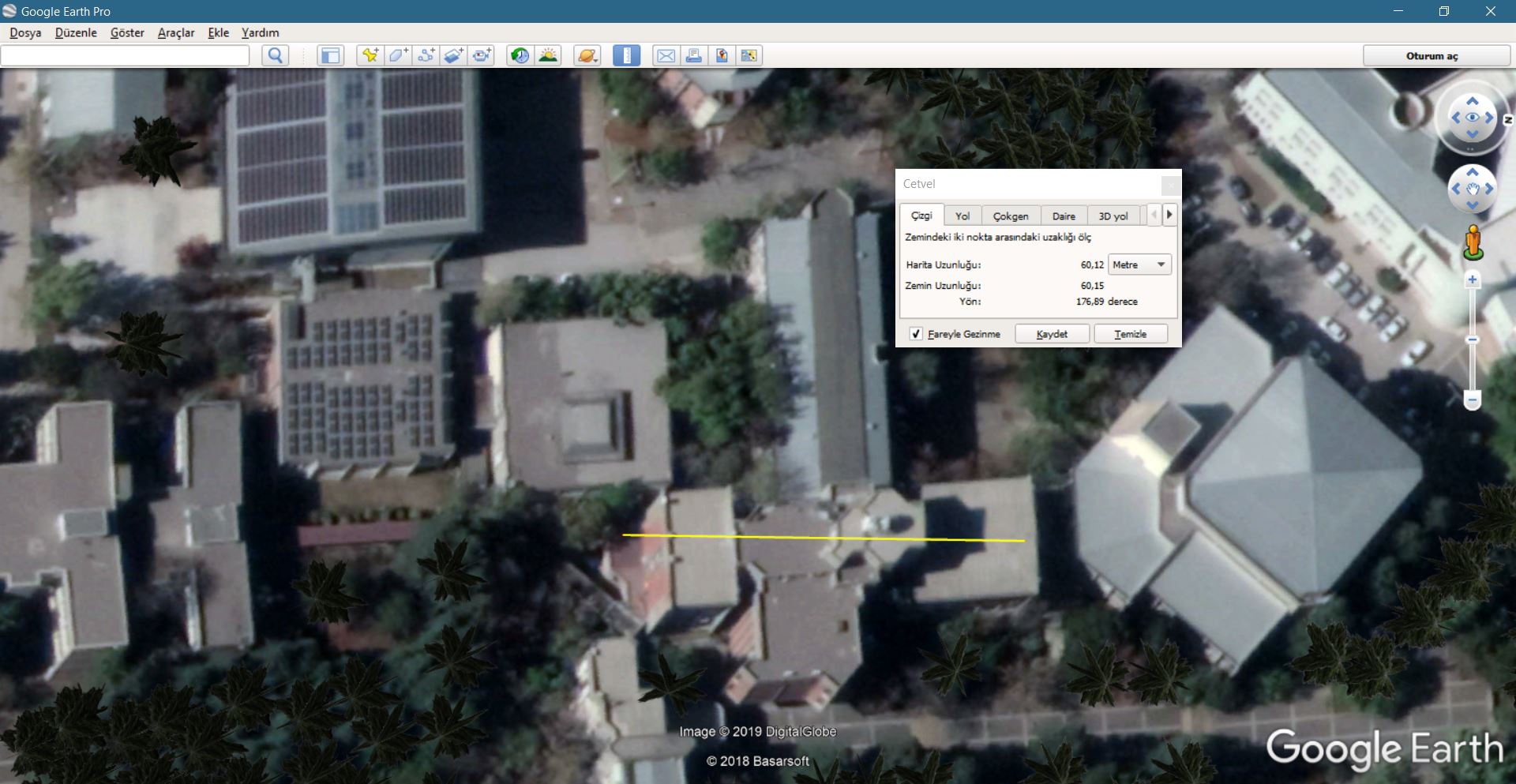
Caner POTUR - 2031250

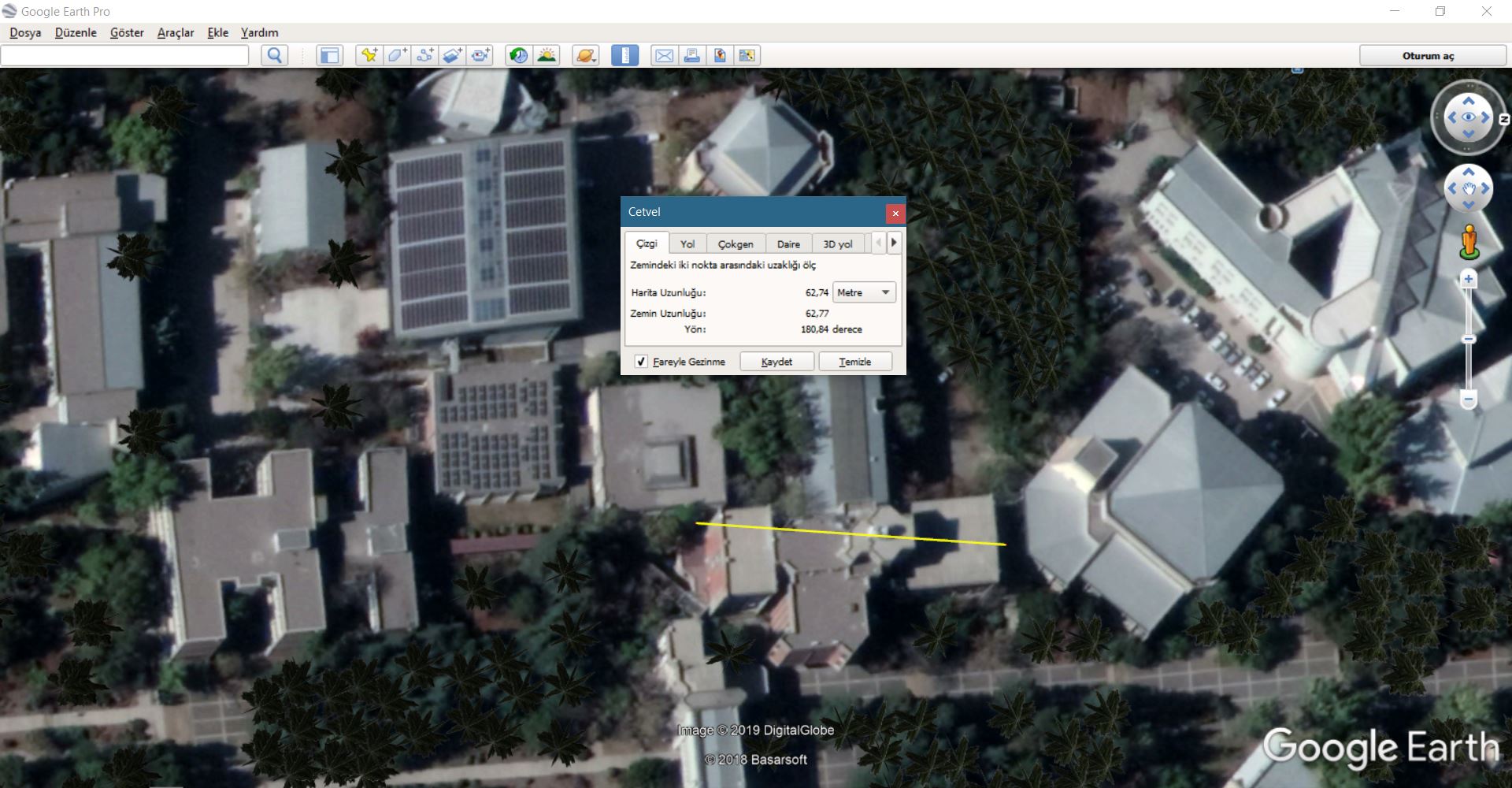
Mustafa Ercan OKATAN - 2031193

Mert KAYIŞ – 2030997

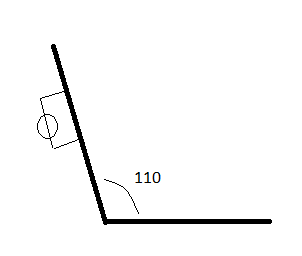
**Progresses for Previous Week:**

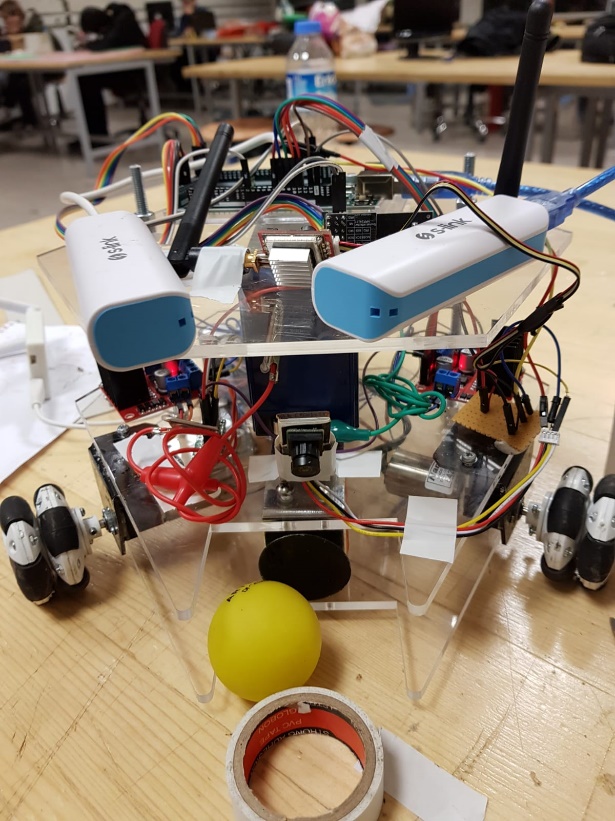
* We made communication tests after implemented the all the subsystems to the body. We tested it at D-building. We had approximately 60 m range for both command and video transfer.





* 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.