McGILL UNIVERSITY

ECSE 211: Final Design Project

Testing Document

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supervised by

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1 SUMMARY

This document is intended to indicate the objective and the methodology of testing of our project as well as discussing the result of testing.

CONTENTS

2 TASKS

Project: Design Principles and Methods Final Project: Capture the Flag - Team 15
Task: Design an autonomous robot that can play a one-on-one version of the Capture the Flag while navigating through an obstacle course.

3 EDIT HISTORY

Document Version Number

0.0.1: Version presented to Prof. Ferrie on the 2017/10/27

0.0.2: Version presented to Prof Ferrie on the 2017/11/03

0.0.3: Version presented to Prof Ferrie on the 2017/11/10

0.0.4: Version presented to Prof Ferrie on the 2017/11/17

Edit History

1. Charles Huang, 2017/10/25 (4.30pm) - Created the document, designed the tests of the project
2. Aliah Mohd Nazarudin, 2017/10/26 (1230pm) - Change the format of the document
3. Charles Huang, 2017/10/29 (2.30pm) - Update hardware and software testing
4. Aliah Mohd Nazarudin, 2017/11/2 (1.50pm) - Add conclusions and further actions taken for every test
5. Charles Huang, 2017/11/02 (2.30pm) - Update colored block testing
6. Aliah Mohd Nazarudin, 2017/11/08 (5.12pm) - Mounting the zip line test
7. Charles Huang, 2017/11/09 (12.15pm) - Unit Test and Integration Test
8. Aliah Mohd Nazarudin, 2017/11/09 (3.00pm) - Update the content list
9. Charles Huang, 2017/11/16 (3.00pm) – Update the integration test

4 HARDWARE TESTING

4.1 Test 1: Large Motor vs NXT Motor

Hardware Version: 01
Software Version: Lab 4 code
Date: October 20 to 23

Objective: The LeJOS library provides several motor classes for controlling the EV3 motor, Large Motor and NXT Motor. This experiment was conducted with the hope of discovering which motor performed better for use in the navigation.

Methodology:
The robot will be made to navigate from a distance of 6 tiles using the Large Motor first and then the NXT motor. Ten trial runs will be conducted. The robot will be place at origin (0.0) and navigate to (0,6). During the experiment, record the behavior of two motors as well as the final angle error.

Results:
The results showed that the Large Motor performed better than NXT Motor. The robot with Large Motors is able to go straight with a final angle error smaller than 2 degrees. The NXT Motor, unlike the Large Motor, even though the speed of the left motor and right motor are set to same, the robot with NXT Motor is not able to go straight. The left motor of NXT Motor is always slow than the right Motor.

Conclusion & Action:
Since the Large Motor performed better than NXT Motor. Our team decide to use Large Motor for the wheel of the robot.

4.2 Test 2: Traversing Zip Line (Dismounting Angle)

Hardware Version: 01
Software Version: Lab 5 code
Date: October 20 to 23

Objective: This experiment was conducted with the hope of discovering what is dismounting angle when the robot dismount from the zip line.

Methodology:
The robot will be made to travel zip line by using Lab 5 code. Five trial runs will be conducted.We will measure the dismounting angle after the robot dismount from the zip line.

Results:
The results showed that our robot is not balanced during the zip line traveling. The dismounting angle is always large 20 degree. The left wheel always touches the board first and the right wheel touches the board after when the robot dismounts from the zip line. It makes the dismount angle large.

Conclusion & Action:
The robot is not balanced during the zip line traveling which makes the dismount angle large. This test report should be send to the hardware team to review the hardware design of the robot especially the balance of the robot during the zip line traveling.

4.3 Test 3: Traversing Zip Line (Mounting Angle)

Hardware Version: 01
Software Version: Lab 5 code
Date: Nov 3 to 9

Objective: This experiment was conducted to discover the angle that allows the robot to perfectly mount the zip line.

Methodology:
The robot will be made to travel zip line by using Lab 5 code. Ten trial runs will be conducted. We will measure the mounting angle, or the angle error that is allowed for the robot to successfully mount the zip line.

Results:
Based on Table 1, it shows that the heading orientation of the robot needs to be between 0 degree to 2 degree angle error for it to successfully mount the zip line.

Trial No.	Angle Error (deg)	Status
1	0.0	SUCCESSFUL
2	1.0	SUCCESSFUL
3	2.0	SUCCESSFUL
4	3.0	UNSUCCESSFUL
5	2.3	UNSUCCESSFUL
6	2.8	UNSUCCESSFUL
7	2.4	UNSUCCESSFUL
8	2.5	UNSUCCESSFUL
9	2.6	UNSUCCESSFUL
10	2.7	UNSUCCESSFUL

Table 1: Mounting the zip line

Conclusion & Action:
The robot needs to have a perfect heading orientation to mount the zipline. This test report is sent to the hardware team to review the hardware design. The robot should be able to correct itself as it mounts the zipline.

5 SENSOR CHARACTERIZATION TESTING

5.1 Test 4: Tests of the detection range of ultrasonic sensor

Hardware Version: 01
Software Version: Testing code 01
Date: October 27 to 30

Objective: The objective of the tests is to determine the detection range of ultrasonic sensor.

Methodology:

1. Write a program to fetch the data from the robot.
2. Place the robot at a fix position.
3. Place a block perpendicular to the ultrasonic sensor at certain distance, however, the ultrasonic sensor should not detect the block
4. Move the block slowly and perpendicular to the ultrasonic sensor
5. Record the angle when the ultrasonic sensor detects the wall.
6. Repeat steps 3-5 with different block starting position

Results:
The result shows that the detection range of ultrasonic sensor is like a cone. The ultrasonic sensor is able to detect a block provided the block surface is facing the robot within 10 degrees.

Conclusion & Action: The result shows that it the block is within 10 degree angle range to where the ultrasonic sensor is facing, the ultrasonic sensor can detect the block almost accurately. If the block is placed perpendicular to the sensor, the values returned by the sensors are nearly flawless. This test report should be sent to the software team so they can write the code accordingly.

5.2 Test 5: Tests of accuracy with ultrasonic sensor

Hardware Version: 01
Software Version: Testing code 02
Date: October 27 to 30

Objective: The objective of the tests is to test the accuracy of the three ultrasonic sensor and determine which ultrasonic sensor is most accurate so that we can use it for the final project.

Methodology:

1. Write a program to get ultrasonic sensor data from three different ultrasonic sensors.
2. Mount three different ultrasonic sensors in parallel on the robot.
3. Place a block 5 cm in front of the ultrasonic sensors.
4. Record each ultrasonic sensor's data from the program
5. Increase the distance between the ultrasonic sensors and the block to 10 cm
6. Record new data from each ultrasonic sensor
7. Repeat steps 5 and 6 and increase the distance between the ultrasonic sensors to 15 cm

Results:

Expected reading(cm)	**Actual reading of Ultrasonic sensor 1 (cm)**	**Actual reading of Ultrasonic sensor 2 (cm)**	**Actual reading of Ultrasonic sensor 3 (cm)**
5	**5**	**4.9**	**4.9**
10	**10**	**9.9**	**10.1**
15	**15**	**14.8**	**14.9**

Table 2: Reading of ultrasonic sensor

Conclusion & Action: Different sensors tend to have different sensitivity level. Based on this experiment, ultrasonic sensor 1 is the most sensitive sensor we have, so the hardware of the robot is changed by placing ultrasonic sensor 1 to the robot.

5.3 Test 6: Gridline detection tests with light sensor

Hardware Version: 01
Software Version: Testing code 03
Date: October 27 to 30

Objective: The objective of the tests is to determine the changes of light intensity detected by light sensor when it detect the gridline.

Methodology:

1. Write a program to rotate the robot 360 degree and record the data from the light sensor.
2. The robot will be place on an open field.
3. The centre of rotation of the robot will be place at an intersection of grid line.
4. The robot will rotate 360 degree while continuously recording the value detected by the light sensor after a simple differential filter is applied.

Results:

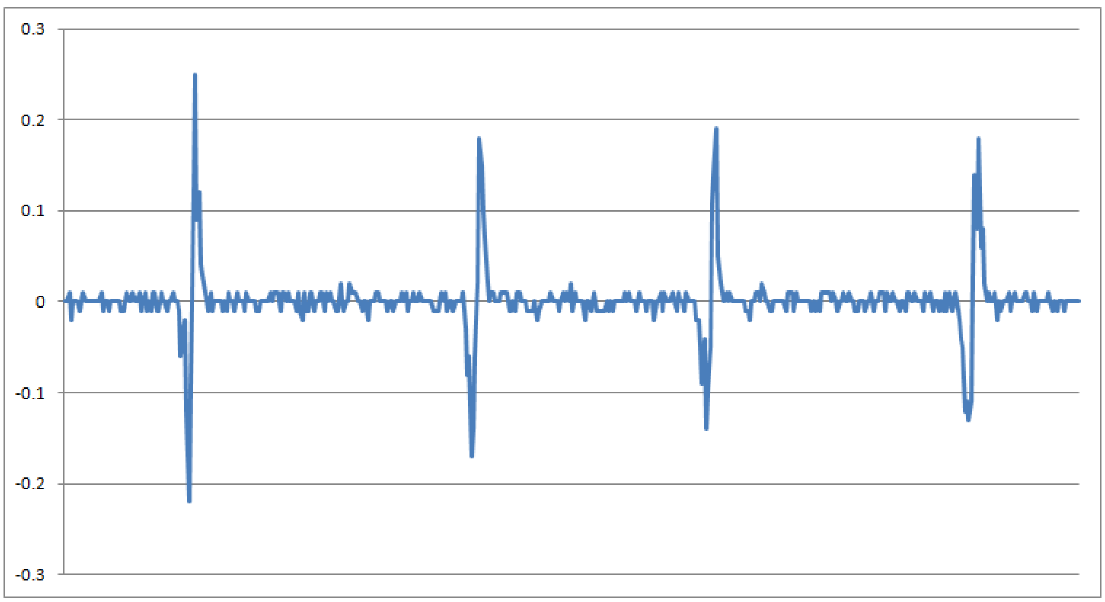

Figure 1: Gridline detection test data

Conclusion & Action: The differential filter used in this experiment shows that when the result is more than 0.1, it shows that the sensor is detecting the black line. This result is then been informed to the software team, for them to write the code accordingly.

5.4 Test 7: Colour block detection tests with light sensor

Hardware Version: 01
Software Version: Testing code 04
Date: October 27 to 30

Objective: The objective of the tests is to determine the changes of light intensity detected by light sensor when it detect different colored blocks at different distances.

Methodology: For the purpose of testing, the light sensor is placed at the left side of the robot.The test robot will be placed on an open field. The robot is programmed to pass by the four blocks.

1. The light sensor mode is set to RGB mode.
2. The four different colored blocks are arranged at the left side of the robot.
3. The order of the colored blocks is white, yellow, red and blue.
4. The distance between the blocks is made constant, which is 10 cm away from each other.
5. The distance between the light sensor and the colored blocks is set to 5 cm.
6. The experiment is repeated by setting the distance between light sensor and the colored blocks to 2 cm.

Results:

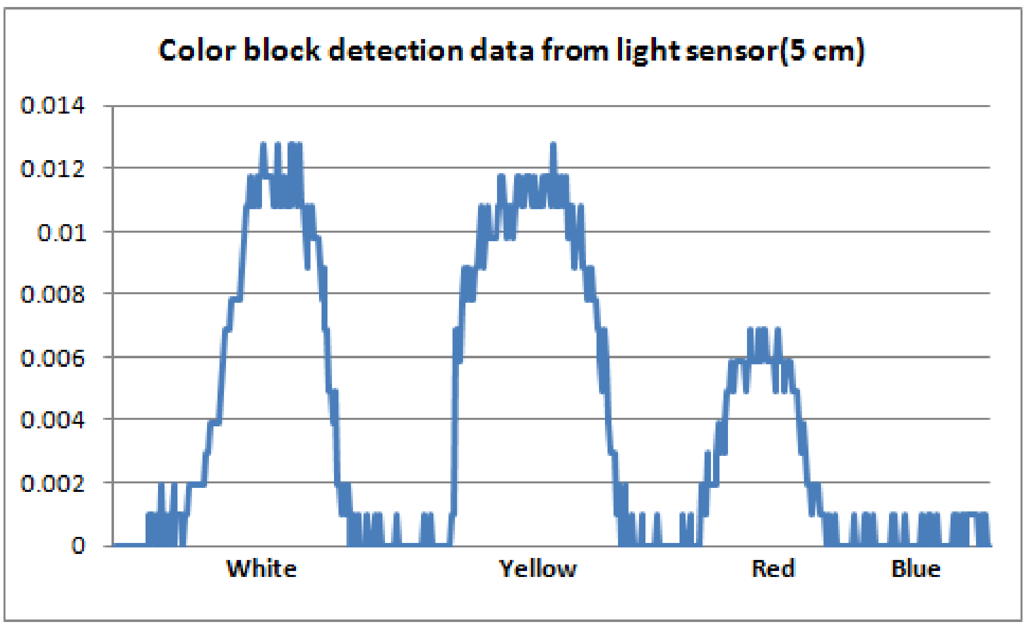

Figure 2: Color block detection data from light sensor with 5 cm difference from the light sensor and the colored block

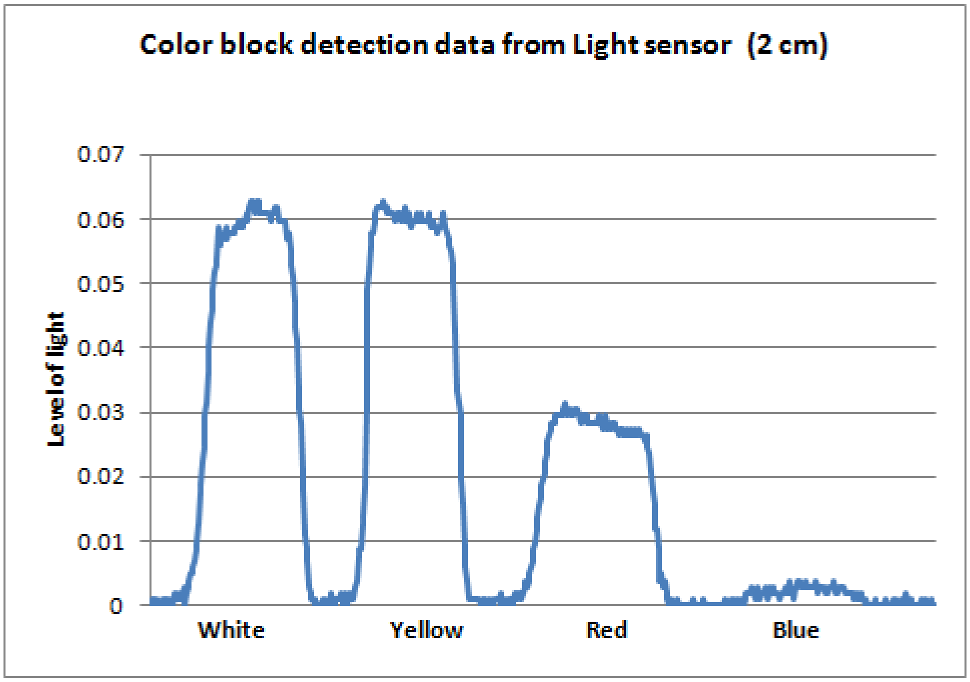

Figure 3: Color block detection data from light sensor with 5 cm difference from the light sensor and the colored block

Conclusion & Action:

Figure 2 shows that the level of light changes according to different colored blocks. Since the blue colored block can absorb the most light, therefore, the level of light does not really change when the light sensor detects it.

When the light sensor detects the white colored block and yellow colored block, the behavior of the change of light intensity is similar. The test team may need to do more test for these two-colored blocks.

According to the Figure 2 and Figure 3, the behavior of change of light intensity is similar for different colored blocks. However, the value of light intensity for different colored blocks are different when the distance between the light sensor and the blocks differ. The result shows that the light sensor is more accurate when the its distance with the blocks are minimal.

More tests need to be done by varying the distances between light sensor and the blocks to get most accurate color intensity. This result is then informed to the software team, for them to write colored block detection code accordingly.

5.5 Test 8: Colour block detection tests with light sensor with Color ID mode

Hardware Version: 01
Software Version: Testing code 04
Date: November 3 to 9

Objective: The objective of the tests is to determine the Color ID detected by light sensor when it detect different colored blocks at different distances.

Methodology: For the purpose of testing, the light sensor is placed at the left side of the robot.The test robot will be placed on an open field. The robot is programmed to pass by the four blocks.

1. The light sensor mode is set to Color ID mode.
2. The four different colored blocks are arranged at the left side of the robot.
3. The order of the colored blocks is white, yellow, red and blue.
4. The distance between the blocks is made constant, which is 10 cm away from each other.
5. The distance between the light sensor and the colored blocks is set to 1 cm.
6. The experiment is repeated by setting the distance between light sensor and the colored blocks to 1.5 cm and 2 cm.

Result:

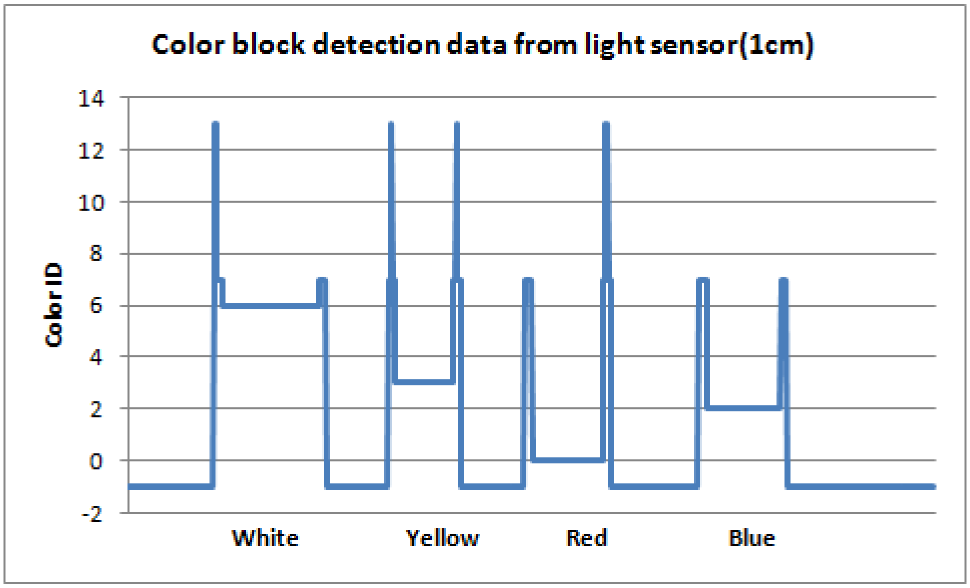

Figure 4: Color block detection data from light sensor with 1 cm difference from the light sensor and the colored block

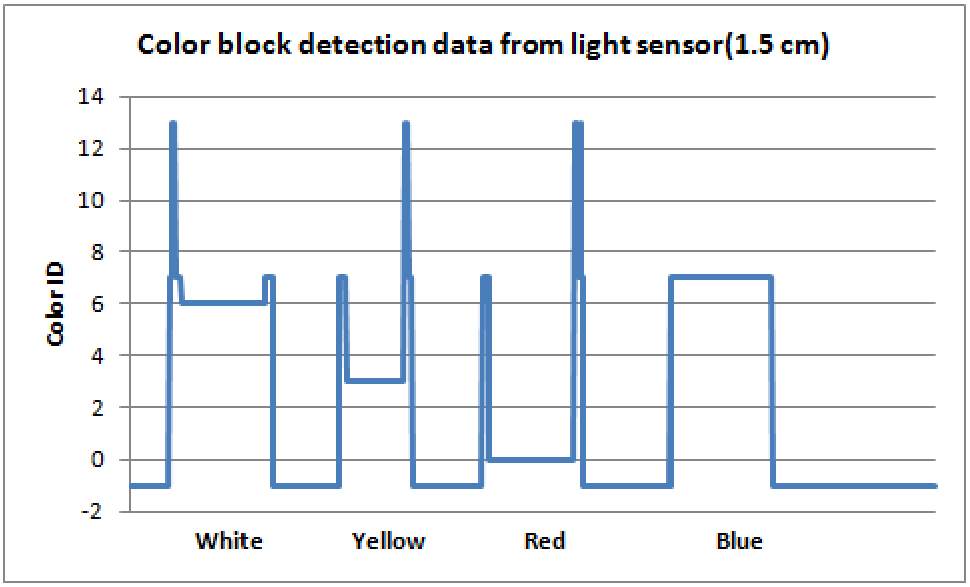

Figure 5: Color block detection data from light sensor with 1.5 cm difference from the light sensor and the colored block

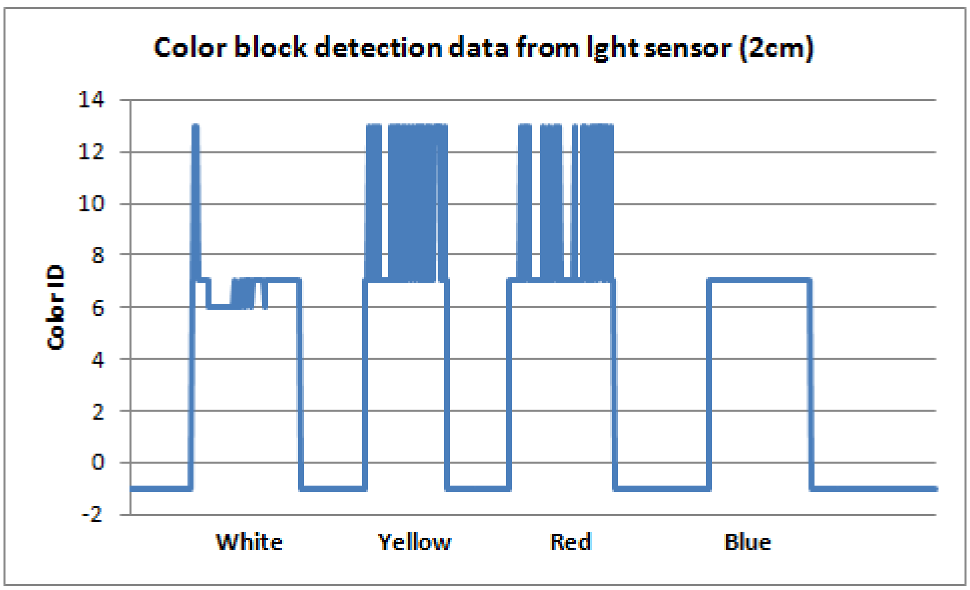

Figure 6: Color block detection data from light sensor with 2 cm difference from the light sensor and the colored block

Conclusion & Action:

From the instruction of Color ID sensor mode, the Color ID of white is 6, the Color ID of yellow is 3, the Color ID of red is 5 and the Color ID of blue is 2.

From the Table 4, the sensor is able to detect different color block with respect Color ID. However, the Color ID of red that the sensor detected is 0 instead of 5. As the distance between the sensor and the block increases, the data becomes less accurate. When the distance is 1.5 cm, the sensor receives a different Color ID for blue. When the distance is

2 cm, the sensor is not able to distinguish different color blocks. In addition to that, the noise may influence the reading from the light sensor. This result is then informed to the software team, for them to write colored block detection code accordingly.

5.6 Test 9: Ultrasonic sensor behavior Test

Hardware Version: 01
Software Version: Testing code 05
Date: November 3 to 9

Objective: The objective of the test is to test the behavior of ultrasonic sensor when it detect a block.

Methodology:

1. The robot is placed on open field
2. Place a foam block inclined at 0 degrees from the robot.
3. Move the robot towards the block
4. Record data from ultrasonicc sensor
5. Repeat the experiment with the block inclined at 15 degrees and 45 degrees from the robot.

Result:

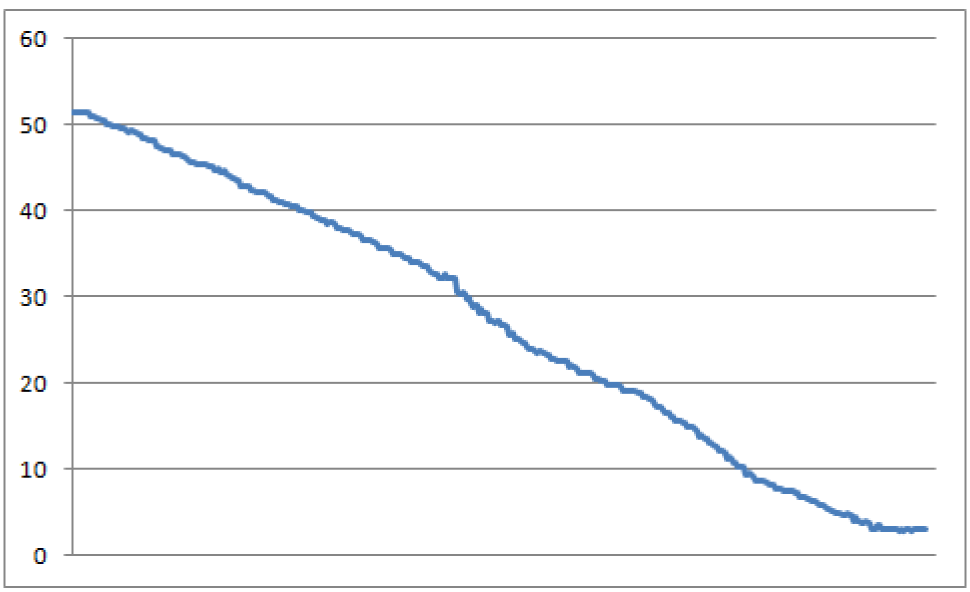

Figure 7: Ultrasonic data when the block is facing the robot (0 degrees)

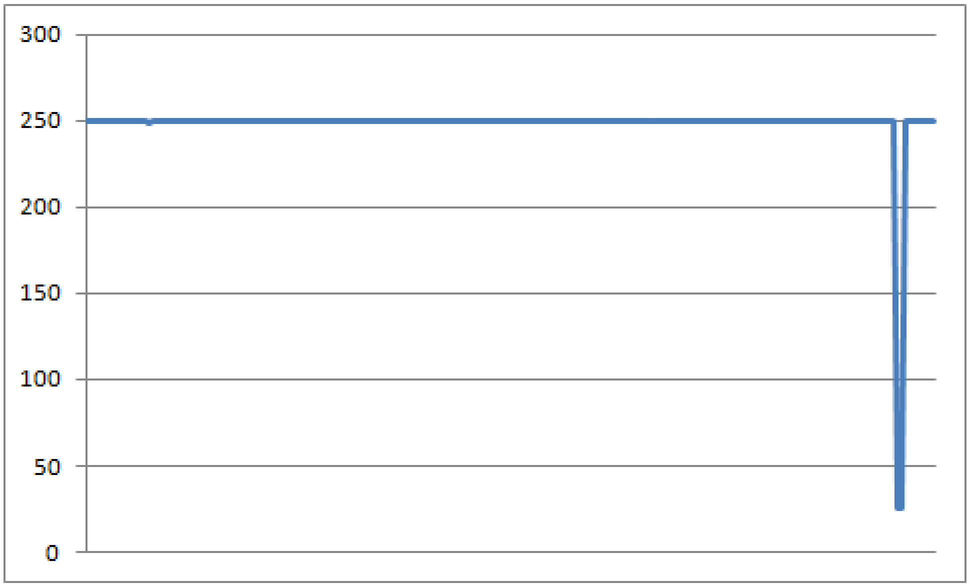

Figure 8: Ultrasonic data when the block is facing the robot (15 degrees)

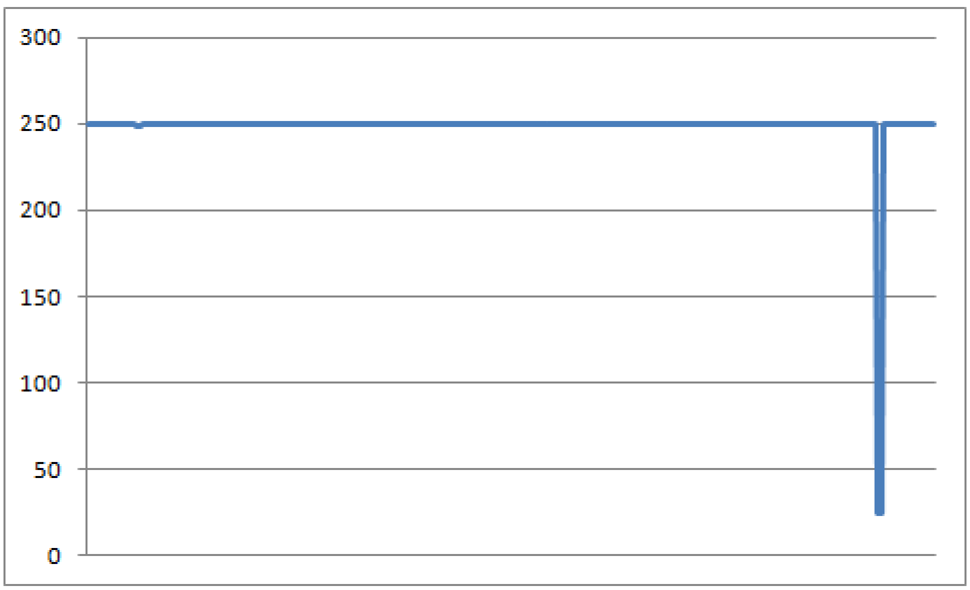

Figure 9: Ultrasonic data when the block is facing the robot(45 degrees)

Conclusion & Action: From the experiment, the ultrasonic sensor is able to detect a block that is facing the robot within the range of 10 degrees. This show that the ultrasonic sensor can only receive a few values to show the existence of the block if its line of sight is not perpendicular to the surface of the block. However, if the line of sight of ultrasonic sensor is perpendicular to the surface of the block, the data from ultrasonic sensor is almost accurate.

6. UNIT TEST

6.1 Test 10 : Ultrasonic localization test

Hardware Version: 0.0.2
Software Version: 0.0.1
Date: November 3 to 9

Objective: Since we implement both falling edge and raising edge ultrasonic localization, in this experiment, we will test both ultrasonic localization and note their accuracy and behaviors.

Methodology:

In this experiment, test team will place the robot at a random corner on the board. Then, the robot will run falling edge ultrasonic localization code and raising edge ultrasonic localization code respectively. The test team will note the behavior of the robot and record the final angle error according to the origin after localizing. The test will run 10 trials for each ultrasonic localization. So, total of 20 trials will be conducted.

Conclusion & Action:

By comparing two ultrasonic localizations, the falling edge ultrasonic localization has better behavior and accuracy. The average of final angle error of falling edge ultrasonic localization is less than 2 degrees. Unlike the falling edge localization, the raising edge localization has an average of final angle error more than 3 degrees. Moreover, during the 10 trials of falling edge ultrasonic localization, all trials are successful, which means that the robot can successfully detect the wall and turn back to origin. However, during the 10 trials of raising edge ultrasonic localization, 9 trails succeed and 1 trial failed. The reason of failure is that the robot detected one wall twice. As a consequence, the robot is not able to turn back to origin for that trail. The result will send to software team to improve the code.

6.2 Test 11: Light sensor localization test

Hardware Version: 0.0.2
Software Version: 0.0.1
Date: November 3 to 9

Objective: The objective of this test is to test the accuracy of light localization.

Methodology:
In this experiment, test team will place the robot at along the 45 degrees line face on the 0 degrees corresponding to origin. Then, the robot will run light localization. We will note the behavior of light sensor localization and the final angle error between the odometer reading and the robot actual angle. Total of ten trials will be conducted.

Conclusion & Action:
From ten trials of experiment, the behavior of the light sensor localization is not ideal. There is one trial that the robot is not able to detect the last black line. Thus, the robot can not sometimes localize properly. However, if the robot detect all four lines, the final angle error between the odometer reading and the robot actual angle is less than 3 degrees. The result will send to software team to improve light sensor localization code.

6.3 Test 12: Navigation test

Hardware Version: 0.0.2
Software Version: 0.0.1
Date: November 3 to 9

Objective: The objective of this test is to test the accuracy of navigation.

Methodology:
In this experiment, test team will place the robot at a random coordinate which means the interaction of black lines. The robot is faced to 0 degrees. Then, the robot will be ask to navigation at random coordinate. We will note the behavior of navigation and record the final position error between the the robot actual position and destination coordinate and final position . Total of ten trials will be conducted.

Conclusion & Action:
From ten trials of experiment, the behavior of navigation is ideal. The robot is able to turn properly and successfully navigate to the destination coordinate. The final position error depends on the battery and the distance of navigation. If the battery is low, the final position error will increase. Moreover, if navigation distance increases, the final position error will increase too. The average final position error is less than 5 cm. The result will sent to software team to improve the navigation code.

6.4 Test 13: Zip line mouting test (Hardware)

Hardware Version: 0.0.3
Software Version: 0.0.1
Date: November 3 to 9

Objective: This experiment was conducted to discover the angle and position that allows the robot to perfectly mount the zip line with Hardware Version 0.0.3.

Methodology:
The robot will be placed on the different angle and different position from the zipline. The test time will record the range of position and angle that allow the robot to properly mount the zipline.

Conclusion & Action:
From the experiment, if the range of the angle error right before mounting zipline is around [-10 ,30] degrees, the robot can successfully mount to zipline. If the range of the position error right before mounting zipline is around [-3,2] cm, the robot can successfully mount to zipline. The result will send to hardware team and software team to improve the hardware design and zipline traveling code, respectively.

7. INTEGRATION TEST

7.1 Test 14: Navigate to end point of zip line

Hardware Version: 0.0.3
Software Version: 0.0.1
Date: November 3 to 9

Objective: This experiment was conducted to discover the behavior and accuracy of robot to navigating to the end point of zip line.

Methodology:
The robot will be place at random starting corner. Then the robot will receive corresponding information from wifi(include starting corner and coordinate of end point of zip line). Then the robot will start ultrasonic localization, light localization and navigate to the end point of zip line. Test team will record the behavior of robot during the test. Five trials will be conducted.

Conclusion & Action:
From the experiment, the robot can successfully do the ultrasonic localization and light localization. However, after light localization, the robot have problems to navigate the indicated coordinate. The odometer is very off. Therefore, the final position error between end point of zip line and the robot actual position is large. This experiment indicate that the robot is not able to navigate destination position after light localization. The result will send to software team to improve the code.

7.2 Test 15: Navigate to the zipline other point 2

Hardware Version: 0.0.3
Software Version: 0.0.2
Date: November 10 to 14

Objective: This experiment was conducted to discover the behavior and accuracy of robot to navigating to the end point of zip line after the improvement of software.

Methodology:
We first set our team as green team.The robot will be place at different starting corner(corner 0 to 3). Then the robot will receive corresponding information from wifi (include starting corner and coordinate of green zone zipline other (3,1) etc.). Then the robot will start ultrasonic localization, light localization and navigate to the green zone zipline other point.Test team will record the behavior of robot during the test. Four trials will be conducted for different corner.

Conclusion & Action:
From the experiment, the robot can successfully navigate to the green zone zipline endpoint except for corner 2. The ultrasonic localization and light localization perform well. However, the corner 2 is farthest corner to the green zone zipline other point. Therefore, the robot need to navigate very long distance to arrive the green zone zipline other point. During the navigation, the robot is not able to keep moving straightly, the angle error increases when the navigation distance increases. Therefore, after the robot finishes the navigation to the green zone zipline other point, the angle error is very large. In conclusion, the robot is not able to accurately navigate the zipline other point if the starting corner is very far. The result will send to software team and hardware team in order to improve the behavior of the robot.

7.3 Test 16: Zip line Traversing (mount, cross and dismount)

Hardware Version: 03
Software Version: 0.0.2
Date: November 10 to 14

Objective: This experiment was conducted to discover whether the robot can successfully mount, cross and dismount the zipline after navigating to green zone other zipline other point.

Methodology:
We first set our team as green team.The robot will be place at different starting corner(corner 0 to 3). Then the robot will receive corresponding information from wifi (include starting corner, coordinate of green zone zipline other (3,1),coordinate of green zone zipline endpoint (3,2) and coordinate of red zone zipline endpoint(3,6) etc.). Then the robot will do ultrasonic localization, light localization navigate to the green zone zipline other point. Then, it will localize again and cross the zip and dismount.Test team will record the behavior of robot during the test. Four trials will be conducted for different starting corner.

Conclusion & Action:
From the experiment, the robot can successfully mount, cross and dismount the zipline except for starting corner 2. Since if the starting corner is corner 2, the robot is not able to accurately navigate to green zone zipline other point. The reason is same as Test 15. The ultrasonic localization and light localization perform well. However, the corner 2 is farthest corner to the green zone zipline other point. Therefore, the angle error after the robot navigates to the green zone zipline other point is very large. Even though the robot is able to localize again at the green zone zipline other point. It is not able to accurately mount to zipline if the starting corner is corner 2. However, when the starting corner is corner 0, corner 1 or corner 3. The robot can successfully mount, cross and dismount the zipline after navigating to green zone zipline other point. The result will send to software team and hardware team in order to improve the behavior of the robot.

7.4 Test 17: Navigate to the opponent’s flag location (after dismounting)

Hardware Version: 03
Software Version: 0.0.2
Date: November 10 to 14

Objective: This experiment was conducted to discover whether the robot can successfully navigate to the opponent's flag location.

Methodology:
We first set our team as green team.The robot will be place at different starting corner(corner 0 to 3). Then the robot will receive corresponding information from wifi (include starting corner, coordinate of green zone zipline other (3,1),coordinate of green zone zipline endpoint (3,2), coordinate of red zone zipline endpoint(3,6) and coordinate of upper right hand corner of search region in red zone (5,6) etc.). Then the robot will do ultrasonic localization, light localization navigate to the green zone zipline other point. Then, it will localize again and cross the zip and dismount. After the robot dismount from the zipline, it will localize again and navigate to the upper right hand corner of search region in red zone. Test team will record the behavior of robot during the test. Four trials will be conducted for different starting corner and for different opponent’s flag location.

Conclusion & Action:
From the experiment, the robot can successfully navigate to opponent’s flag location after dismounting from the zipline except for starting corner 2. Since starting corner 2 is farthest corner to the green zone zipline other point. Therefore, the robot is not able to navigate to the green zone zipline other point, so the robot is not able to mount to zipline. However, for other 3 corner, the robot is able to mount, cross and dismount from the zipline and successfully navigate upper right hand corner of search region in red zone. However, since our robot is not able to move straightly during navigation, if the opponent’s flag location is very far away from the dismounting point, the result becomes inaccurate. The result will send to software team and hardware team in order to improve the behavior of the robot.