ENGR141 Grade Report: Proj3 PoC Spec Iteration 2

		Total Points Earned	4
Team	Team 59	**Total Points Possible**	6
Grader	Casey Schilling	**Percentage Earned**	66.67%

Grading System Message(s)	

Are specifications sufficiently describing	Pass	Part.	Fail
Incomplete header / wrong file name: PoC#_Spec_TeamXX.pdf	**0**	NA	-1
Task 1 - Mobility Demonstration	**1**	NA	0
Task 2 - Line Follow	**1**	NA	0
Task 3 - Obstacle Traversal	**1**	NA	0
Task 4 - Bin Drop-Off Location	1	NA	**0**
Task 5 - Lift, Transport, and Drop Bin	1	NA	**0**
Task 6 - Bin Identification	**1**	NA	0

	Subtotal	**4**	**of**	**6**

Total	**4 of 6**

Grader Comments

Task 2: Be careful with time constraints to find the line, because what if the robot gets super far off the line while accomplishing another task. You might fail the time constraint just while fulfilling all the others (including velocity) just because of how far away the robot started. You could add a qualifier, like <5 seconds to find the line while the robot is following the line. Just a suggestion.

Task 4: Should add some numbers in for the radius of the circle to finalize the design specification.

Task 5: I think you're super close with this block of design specifications. I think one of my biggests issues with this one is your reliability constraint for the bin orientation. Do you think reliable is the best way to measure this? How could you more precisely measure that the bin (and all delivered bins) are delivered with the proper orientation. Think about what you know about the bin shape/design and its proper orientation.

Task 6: It would be better if the bin type display was not a reliability constraint and rather a measurable constraint for everytime (i.e. it should do it right everytime, but how do you check that it is doing it right?).

Nice work! I would recommend in general, to start pushing towards being able to accomplish these tasks soon so that you have sometime to integrate the software and mechanics.