ENGR142 Grade Report: Proj3 PoC Spec Iteration 1

		Total Points Earned	-1
Team	Team 45	**Total Points Possible**	6
Grader	Peter Jones	**Percentage Earned**	-16.67%

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 - Linear Movement	1	NA	**0**
Task 2 - Autonomous Navigation	1	NA	**0**
Task 3 - Obstacle Traversal	1	NA	**0**
Task 4 - Locating Magnetic Beacon	1	NA	**0**
Task 5 - Transport & Drop Antenna	1	NA	**0**
Task 6 - GPS Software	1	NA	**0**
Subtotal	**-1**	**of**	**6**

Total	**-1 of 6**

Grader Comments

No heading with names was included. - For how long can the robot move? I could easily get to a target right next to my robot, but can it get within two inches of a marker in Indianapolis? In what conditions can the robot get this close to the marker? After it makes turns? Only when it's a straight line? What would keep it from doing this? - Autonomous navigation is much less about the GPS utilization and much more about the robot's ability to operate by itself relative to how you would want it to move if you were controlling it. If you tell it to go straight, is it going to go straight? How about turning? What then? If it runs into a wall, will it know what to do? If it comes to it's destination, is it going to stop? Will it know where it's headed? - If you're bypassing obstacles, that means you are avoiding them, in that case, why does it matter how tall the object is? What different variations of obstacles can the robot overcome? - Distance is maybe a better indicator of if the robot can find the beacon than time is. Will the robot let you know it found a beacon? - Orientation of the antenna is more about which side is facing up than where it is. Also, a dropped antenna is not good either. - The important part of the GPS is that the robot can recieve the coordinates.