Additional Risks:

Meeting attendance/scheduling conflicts

When the entire group cannot meet at the same time, it will be difficult to synergize our efforts and avoid redundancy. Those who miss the meeting will also possibly miss out on work assigned to them or tasks completed at the meetings. To fix this, the group should schedule meetings far in advanced and make sure to find a time that is hopefully accessible for everyone, or at least the maximum number of people.

Time constraints

The later the group attempts to complete the project for the week, the risk of not being able to complete the project in time rises. Additionally, time constraints make it more difficult to meet, as it will be less likely to find a time that fits everyone’s schedule at a late notice. To address this risk, the group should attempt to start the work as early as possible.

Physical damage

There is risk in the operation of the robot in regards to its physical structure. High-velocity collisions may cause pieces of the robot to fall off or break. Additionally, simple stress on the structure of the robot due to it’s motors can lead to breakage without a collision in a poor design. Throwaway-prototype testing can address this risk, as well as having a good software implementation to detect collisions or minimize their effect with the robot’s behavior.

Dealing with terminating errors (software) while robot is running

There is a risk with software errors disrupting the ability of the robot. The robot could enter an “infinite loop” with improper code, or encounter an error handling a certain stimulus. Such errors can be dealt with by reporting them to the computer-based software, which should implement methods to solve or respond to errors that occur while the robot is running.