	Category	Requirement	Functional/Non/Wish	Priority	Volitility	Time (hrs)	Classification (for doc)	Purpose				
NIK	***Robot monitoring process***	***Robot will stay a few (3) strides from person (~6-8 ft, pendin***	***functional***	***high***	***high***	***8.7***	***4***	***Close enough to monitor***				
		Robot will stay directly in front of person	***functional***	***high***	***med***	***21.5***	***4***	***Allows monitoring***				
		Robot will keep pace with person when walking	functional	med	med	***32.8***	4					
		Robot will go into stationary position when person is working	functional	low	low	***14.2***	4					
	Robot intervening process	***If person unsteady, robot will move to individual***	***functional***	***high***	***low***	***8.5***	***4***					
		Intervening robot stops at distance of ~0.5 m	***functional***	***high***	***med***	***2.6***	***4***					
		If person unsteady, arm will move to provide stability	***functional***	***high***	***low***	***26***	***4***					
	Post-fall response	If person falls, ask if is okay	functional	med	low	31.8	4					
		If person falls and is unresponsive issue a message	functional	med	low	33.8	4					
		If person falls robot will record person to send to responders	functional	med	med	28.3	4					
BEN	Data management	Robot will record all availible data to make informed decisions	functional	med	low	27.9	4		I've included this part in functional requirements			
		Robot will keep emergency contacts	non	med	low	30.8	5.2					
	Power management	Robot will notify user if battery will expire in 30 minutes	functional	low	med	25.4	4	Do Introduction	I'm going to add a battery protocol to functional requirements			
		Robot battery will be able to be swapped out	non	med	low	3.2	2.5	---				
		Robot will not turn off	non	med	low	19	2	---				
	Operating environment	***Indoor use***	***non***	***high***	***low***	***non***	***2.4***	***---***				
		Will not traverse stairs	***non***	***high***	***low***	***non***	***2.4***	***---***				
		Flat environment use	***non***	***high***	***low***	***non***	***2.4***	***---***				
		No hazardous conditions (wet, hot, uneven)	***non***	***high***	***low***	***non***	***2.4***	***---***				
JENNA	Physical attributes	Robot will be about the size of a shopping cart	non	high	low	non	2.5	X				
		Robot will be stable enough to be bumped into	non	high	low	non	2.5	X				
		Arm will have cusion/soft material	non	low	low	non	3.2 (3.1?)	X	3.2 in sample document is about the interface between hardware and software, not between the user and the hardware. Could this go under 3.1 (user interfaces), as that deals with interface between user and product (in doc, user and software product)	I think that makes more sense, yes		
		No part of the robot should pose a danger in a collision	non	high	low	non	5.2					
		Robot will have touch screen display ~10"	non	med	med	non	3	X				
		Robot will have a keyboard and touchscreen	non	med	low	non	3					
	Software Interface	Robot will only have one 'profile'	non	med	low	33.7	3					
	Operating constraints	Robot will not be pushed, or used as a walker	non	med	med	10.6	2.5	X	2.5 is design and implementation constraints-- should this go under 2.2 (product functions) or 2.3 (user classes; i.e. people wanting assistance in an instant (v.s. being pushed))? Or if it goes under 2.5, having it be that robot will only move of its own accord (user cannot push it)?	I think both 2.5 and 2.2 (ie mention it in both)		
		Robot operating noise will never be above normal conversation	non	med	med	15	2.5	X				
	Wishslist requirements (future work)	Robot can be put into a car for transport to store	wish				2					
		Robot will warn user if it sees they might run into something	wish				3					
		Robot will only cost as much as expensive walker	wish				2.5					
		Robot contact attempts will adapt to environment	wish									
		Robot will have multiple 'profiles'	wish				3					