[Sprint 1- Endurance] Design Document

October 24, 2019

CS 104-03

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Fall 2019 Semester

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# 1. Executive Summary

## Project Overview

This software project is the first step of our software project. The entire project is to design software for our robot to complete a series of sprints; endurance, agility, and speed. The intended audience of this project is the CS 104 class and Professor Eckert, along with anyone else in the Monmouth University Computer Science Department.

## Purpose and Scope of this Specification

The purpose of this part of the project is to be able to complete the first sprint which is endurance. The intended audience of the first sprint is Professor Eckert, the CS 104 class, and any other person who is a part of the Computer Science and Software Engineering Department.

**In scope**

This document addresses requirements related to phase 1 of the Robot Project:

* modification of javascript code along with sphero plug in code in order for the robot to be able to beat the endurance test

**Out of Scope**

The following items in phase 2 and 3 of the Robot Project are out of scope:

* modification of javascript and plug sphero code to meet the expectations of the agility test.
* modification of javascript and plug sphero code to meet the expectations of the speed test.

(Phase 2 and 3 (agility and speed) will be considered in the development of the requirements for Phase 2 and 3, and these requirements will be documented separately.)

# Product/Service Description

The general factors that affect the endurance code for the Robot Project include the ability to write the code for the sprint, and the ability of the robot to complete the endurance track given to the class by the professor. The code for this level of the project should allow the robot to complete the endurance test.

## Product Context

This product relates to other products because for the next two sprints, we will be working on doing two more similar things with the robot, such as speed and agility. This product is independent, because it does not rely on the other tests in order to run and function and complete the course.This product relates to other products because it has to pass a test in order to run.

***User Characteristics***

* Anyone interested in learning or studying programming
* Ability to use Sypho program
* Use of basic computer block programming

## Assumptions

Equipment required for this project is a sphero robot, charging case, charging cable, robot cover, and robot case. Availability of Howard Hall 208 also affect the requirements of the project, since the course is in that room. Little to no user expertise required because it is a guess and check system using the angles of a protractor and course angles.

## Constraints

Describe any items that will constrain the design options, including

* Deadline October 29, 2019
* Access to campus after normal school hours
* Availability of Howard Hall 208
* Group availability

## Dependencies

* This new product will require a download of the program to the robot each time the code is changed in order to run it properly.
* Endurance program must be completed before the robot can run, and must be downloaded to the robot in order to run it.

# Requirements

## Functional Requirements

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| **Req#** | **Requirement** | **Comments** | **Priority** | **Date Rvwd** | **SME Reviewed / Approved** |
| ENDUR\_01 | Meet with group to discuss project and approach | Start of project process | 3 | 10/18/19 | Holly Bernich  Nolan Beagell  Anthony Berardis |
| ENDUR\_02 | Write the code for the endurance test | Starting to build main code of the program | 1 | 10/18/19 | Holly Bernich  Nolan Beagell  Anthony Berardis |
| ENDUR\_03 | Testing code for endurance run | Important procedure for proper run of program | 2 | 10/18/19 | Holly Bernich  Nolan Beagell  Anthony Berardis |
| ENDUR\_04 | Making adjustments to aim in the endurance code for the run, and adjusting the angle | Maintenance of code and project | 2 | 10/18/19 | Holly Bernich  Nolan Beagell  Anthony Berardis |
| ENDUR\_05 | Finalizing code and finishing touches of endurance test, along with algorithm, flow chart, gantt chart | Finish product | 1 | 10/18/19 | Holly Bernich  Nolan Beagell  Anthony Berardis |

## 

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## Security

### Protection

* Private code on our accounts
* Robots are sign out only
* Robots are locked up
* Silicone cover on the outside of the robot to protect against damages

### Authorization and Authentication

Username and passcode to login to Sphero to access code

## Portability

If portability is a requirement, specify attributes of the system that relate to the ease of porting the system to other host machines and/or operating systems. For example,

* Percentage of components with host-dependent code;
* Percentage of code that is host dependent;
* Use of a proven portable language;
* Use of a particular compiler or language subset;
* Use of a particular operating system;
* Use of specific Block code
* Use of specific java code from block code
* Use of a specific Application (Sphero)
* The need for environment-independence - the product must operate the same regardless of operating systems, networks, development or production environments.

# Requirements Confirmation/Stakeholder sign-off

Include documentation of the approval or confirmation of the requirements here. For example:

|  |  |  |
| --- | --- | --- |
| **Meeting Date** | **Attendees (name and role)** | **Comments** |
| 10/18/19 | Holly Bernich, Project Manager  Nolan Beagell, Code and Tester | Confirmed ENDUR\_01-ENDUR\_04 |
| 10/22/19 | Holly Bernich, Project Manager  Anthony Berardis, Document and Chart Manager | Worked on section 2 of Requirements Doc |
| 10/22/19 | Holly Bernich, Project Manager  Nolan Beagell, Code and Tester | Worked on Section 3 of Requirements Doc |

# System Design

## Algorithm

Develop and describe here an algorithm that will be used to provide the required performance of your software

1. Put robot on tape “x”
2. Using sphero appconnect to the robot via bluetooth
3. robot speaks “ready, set, go”(green light)
4. robot rolls forward @ max speed @0° for 4.6 sec
5. robot comes to stop in yellow corner
6. robot rolls forward @ 150 speed @90° for 4 sec
7. robot comes to stop at next yellow corner
8. robot rolls forward @ max speed @180° for 4.6 sec
9. robot comes to a stop at next yellow corner
10. robot rolls forward @150 speed @270° for 4 sec
11. robot comes to stop in last yellow corner
12. robot speaks “im done and I need water?”(red light)
13. robot has completted the ‘Endurance test’

## System Flow

Develop a flowchart (and show here) that accurately depicts how your software application will act to fulfill the algorithm

## Software

Sphero block code, javascript

## Hardware

Sphero robot, phone to run code, laptop computer to run code

## Test Plan

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| **Reason for Test Case** | **Test Date** | **Expected Output** | **Observed Output** | **Staff Name** | **Pass/Fail** |
| Testing angle 1 | 10/18/19 | Robot will perform 1st angle | Robot was slightly off angle | Holly Bernich | Fail |
| Testing angle 1 | 10/18/19 | Robot will perform 1st angle with the added adjustments of aim | Robot completed the first line of the endurance test | Nolan Beagell | Pass |
| Testing angle 2 | 10/18/19 | Robot will perform 2nd angle run | Robot was slightly off angle | Holly Bernich | Fail |
| Testing angle 2 | 10/18/19 | Robot will perform 2nd angle with the adjustments of aim for 2nd angle | Robot completed the second line of the endurance test | Nolan Beagell | Pass |
| Testing angle 3 | 10/18/19 | Robot will perform 3rd angle of endurance | Robot was slightly off angle | Holly Bernich | Fail |
| Testing angle 3 | 10/18/19 | Robot will perform 3rd angle with the adjustments of aim for 3rd angle | Robot completed the third line of the endurance project | Nolan Beagell | Pass |
| Testing angle 4 | 10/18/19 | Robot will perform 4th angle of endurance test and complete the stretch of the last turn | Robot was off aim when completing this last set. | Holly Bernich | Fail |
| Testing angle 4 | 10/18/19 | Robot will perform 4th angle with aim adjustments and speed adjustments | Robot completed the last line of the endurance test | Nolan Beagell | Pass |
| Testing speed of whole course | 10/18/19 | Testing robot speed while it is on aim and makes the angles of the course | Robot speed was a little off and went too far off course | Holly Bernich | Fail |
| Testing speed of whole course | 10/18/19 | Testing robot speed while on aim adjusted from previous speed | Robot speed is now acclimated to the angles of turn | Nolan Beagell | Pass |
| Completion of course | 10/18/19 | Testing angles and speed for whole course | Robot has completed the course | Nolan Beagell | Pass |

## Task List/Gantt Chart



## Staffing Plan

|  |  |  |  |
| --- | --- | --- | --- |
| **Name** | **Role** | **Responsibility** | **Reports To** |
| Holly Bernich | Project Manager  Code Tester | Code starter/implementer  Document writer  Calculate algorithms  Presenter | Professor Eckert |
| Anthony Berardis | Code Tester  Document Manager | Document leader  Code Tester  Adjust documents and gantt chart | Professor Eckert |
| Nolan Beagell | Code Tester  Document Manager | Figuring out aim  Writing document  Figuring out algorithms | Professor Eckert |