Minutes Session **B** – Friday 27th January 2017 - **13:06** PM

**Present members** – Jamie Izak Slome, Jack Galvin, Zehra Punjwani

**Goals**

1. **Discuss research on Kalman filter, Bayesian filter and self-localisation.**
2. **Discuss optimal sensor positions (fit-for-purpose).**
3. **Take initial steps to first version of EV3 robot.**

**Achievements**

1. **After 8 minutes of stand-up discussion, each member of the team presented findings on Kalman filter, Bayesian filter and self-localisation techniques. Definitions and purpose of methods reviewed (covariance and probabilistic methodology) – Monte Carlo localisation also considered.**
2. **All team members involved in decision as to the location and positioning of sensors.**

* **Color sensor mounted front-ways, facing downwards.**
* **Touch sensor mounted front-ways, facing forwards.**
* **Ultrasonic sensor (only rotational needs discussed).**

**A3. Successfully attached two motors to the underside of EV3 Control brick. Refer to EV3\_Vers\_1.0.**

Further comments:

Meeting on Friday 20th January 2017 cancelled. Weekly meetings now moved to Friday sessions.

Next meeting Friday 3rd February 2017. All team members should be present.

Gyroscope positioning still to be decided.

Next version of build to be consolidated in next week session.

Further research into relevant theory concerning self-localisation and Monte Carlo localisation techniques.