Minutes Session **C** – Friday 3rd February 2017 – **14:00** PM

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

**Goals**

1. **Understand and discuss the purpose of all sensors to be installed and its application to the challenge requirements.**
2. **Design and draw build 1.0.1 with sensors.**
3. **Install sensors onto EV3\_Vers\_1.0.**

**Achievements**

1. **After 15 minutes of a sit-down discussion, each member of the team presented their ideas on the application of the sensors to the robot and how each sensor will be used to achieve a challenge requirement.** 
   1. **Jack discussed with the team the purpose of the colour sensor and how this will be used to identify the colour inside the tunnel.**
   2. **Jamie discussed with the team the purpose of the gyro sensor and how this will be used to determine the change of, and resultant, direction.**
   3. **Zehra discussed with the team the purpose of the touch sensor and how this will be used to know when the robot encounters the end of the tunnel (measuring impact readings).**
   4. **As a group, we agreed that the light sensor will be used to record and store colour readings from inside the tunnel.**
2. **A 3D model drawing was designed by the team and drawn out by Jamie as an initial blue-print for build 1.0.1 (build 1.0 with sensors).**

* **The blue-print included visual representation of sensors and EV3 brick (with wheels attached to motors shown in build 1.0).**
* **Reference BLU\_Print\_1.0.1.**

**A3. Successfully installed sensors onto the EV3\_Vers\_1.0 build, attempting to follow BLU\_Print\_1.0.1 as rigorously as possible.**

Further comments:

Next meeting Friday 10th February 2017. All team members should be present.

Gyroscope position meets blue-print but not explicitly shown in Vers\_1.0.1 photo. Positioned at the point of the centre of rotation.

Next version of build to be consolidated in next week session – to include wheels and cable management.

Research EV3 API regarding sensors and start planning design for Bayesian and Kalman implementation. Also prepare research for A\* planning discussion next week.