Progress:

Mount the camera and turn it on

Detect blobs on the pad, need to improve and finetune it

Able to isolate the pad and find blobs of stuff on it

Constraints:

lighting/shadows - not sure if night vision through IR will help

viewing angle of the camera

testing material

Detecting the dog - possible motion sensor, or some other algorithm with the current camera

upcoming goals:

improving mount design - play with different viewing angles or mounting locations

integrate area of pad to determine the actual soil level of the pad

warp the area of the pad to a perfect square

use a “control” (maybe like 50% dirtiness) to determine how accurate our algorithm is

interface with brilliant pad (alan sent instructions for communicating over UART)

* test different algorithms
* test different camera configurations
* talk to alan about next steps
* use IR for detection?