<Ridill>

Use Case Report for Model *NAO_project*

UseCases

Detect

Documentation: Detect,
Making the NAO detect landmarks to react to.

Precondition:
1. Robot is on
2. Battery charged or connected to charger
3. Connected via wifi or network cable
4. Connected via proxy or choreographe
5. Landmarks exist

Post condition:
1. The NAO has or has not located landmarks within its visinity
2. Printed location of landmark in relation to NAO if located

Flow:
1. Make robot stand
2. Start scanning
3. Receive location of landmark if located

Duel

Documentation: Duel,
Making the NAO detect a landmark and then bases on that duel the landmark.

Precondition:
1. Robot is on
2. Battery charged or connected to charger
3. Connected via wifi or network cable
4. Connected via proxy or choreographe
5. Carrying nerf-gun
6. Landmark detected

Post condition:
1. The NAO has dueled the landmark
2. Nerf-gun has been fired

Flow:
1. Make robot stand
2. Make NAO pick-up gun
3. Detect specific landmark
4. Make the robot position himself in accordance to landmark
5. Turn around and walk away from landmark
6. Turn and face landmark
7. Shoot at landmark

playSound

Documentation: playSound,
Making the NAO play a Sound.

Precondition:
1. Robot is on
2. Battery charged or connected to charger
3. Connected via wifi or network cable
4. Connected via proxy or choreographe
5. Sound .wav added to NAO

Post condition:
1. The NAO has played .wav sound

Flow:
1. Start robot
2. Play sound

Position

Documentation: Position,
Making the NAO position himself to shoot at landmark.

Precondition:
1. Robot is on
2. Battery charged or connected to charger
3. Connected via wifi or network cable
4. Connected via proxy or choreographe
5. Carrying nerf-gun
6. Landmark detected

Post condition:
1. The NAO has positioned himself in relation to landmark

Flow:
1. Make robot stand
2. Detect landmark
3. Make the robot position himself in relation to landmark

Alternative flow:
AT 1:
1.1 Take nerf-gun
1.2 Detect landmark
1.3 Make the robot position himself in relation to robot

Shoot

Documentation: Shoot,
Making the NAO shoot at specific landmark.

Precondition:
1. Robot is on
2. Battery charged or connected to charger
3. Connected via wifi or network cable
4. Connected via proxy or choreographe
5. Carrying nerf-gun
6. Landmark detected

Post condition:
1. The NAO has shot at landmark

Flow:
1. Make robot stand
2. Detect landmark
3. Make the robot walk closer to landmark
4. Shoot landmark

takeGun

Documentation: takeGun,
Making the NAO take a nerf-gun from you.

Precondition:
1. Robot is on
2. Battery charged or connected to charger
3. Connected via wifi or network cable
4. Connected via proxy or choreographe
5. You have a nerf-gun

Post condition:
1. The NAO is carrying nerf-gun

Flow:
1. Make robot stand
2. Open NAO robots hand
3. Put nerf-gun in hand
4. Close NAO robots hand

Talk

Documentation: Talk,
Making the NAO Talk.

Precondition:
1. Robot is on
2. Battery charged or connected to charger
3. Connected via wifi or network cable
4. Connected via proxy or choreographe

Post condition:
1. The NAO has spoken

Flow:
1. Start robot
2. Speak command that has ben input

Walk

Documentation: Walk,
Making the NAO walk.

Precondition:
1. Robot is on
2. Battery charged or connected to charger
3. Connected via wifi or network cable
4. Connected via proxy or choreographe

Post condition:
1. The NAO has walked to specified position

Flow:
1. Make robot stand
2. Input steps you wish for the robot to take
3. Make the robot walk

UseCase Diagrams

Usecase_NAO