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| Project Status Report | Overall Status: **On Track** |

# Project Name: Extraterrestrial Robot Explorer and Environmental Logger

October 28, 2016

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| Status Code Legend |  |
| * On Track: Project is on schedule | * High Risk: At risk, with a high risk of going off track |
| * At Risk: Milestones missed but date intact | * Off Track: Date will be missed if action not taken |

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| The project is On Track the week of 10/10/2016 - 10/14/2016, due to the following: | * Integrated major system modules (Supervisor with joystick, Linux Box and Platform Controller) * Made significant progress on PI control |
| Issues: | * PI control is not consistent across all speeds (i.e., when the robot is straight at high speed, it leans to the right at slower speeds) * Changing the control mechanisms on the embedded board to work with the joystick is going to take more time than we thought. We are rusty on some of the implementation details for the stepper motor, so making changes is grueling and time consuming |
| Milestones accomplished the week of 10/10/2016 - 10/14/2016: | * Integrated major system modules and confirmed reliable communication of joystick events from supervisor to embedded board * Implemented PI control with some success – robot moves in straight line at high speeds |
| Milestones planned this week, but not achieved with variance: | * Environmental Sensor (THIS IS OKAY, it has low relative priority) |
| Milestones planned for next week: | * Finalize control method on the embedded board using joystick events * Get camera feed from the webcam and stream it to the Supervisor * Try to improve PI control * Do verification testing on joystick control and camera feed streaming |
| Areas/questions for discussion: | *Any suggestions for fixing the inconsistency in PI control?* |
| Last week’s issues forwarded to this week: | *None* |