Funky Town Fancy Pandas Budget Proposal 1.0.0-2014

(Revision October 7, 2014)

**Budget Proposal**

**for Autonomous Panda System**

Sponsor:

The Department of Electrical, Computer, Software & Systems Engineering at Embry-Riddle Aeronautical University

Released:

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Funky Town Fancy Pandas Development Team

**Abstract:** The budget proposal and functional design is contained in this document in conjunction with the preliminary budget, justifications, and decisions for each of the major components.

# Revision History

Table 1 contains the information regarding the version control for this document, including version, date, and description.

|  |  |  |
| --- | --- | --- |
| **Version** | **Date** | **Description** |
| 0.1.0 | Sept. 28, 2014 | Initial draft of the document |
| 0.2.0 | Sept. 30, 2014 | Continuation of budget proposal |
| 0.3.0 | Oct. 1, 2014 | Formatting |
| 0.4.0 | Oct. 2, 2014 | Continuation of budget proposal |
| 0.5.0 | Oct. 4, 2014 | Adding matrices and continue formatting |
| 0.6.0 | Oct. 5, 2014 | Continuation of budget proposal |
| 0.7.0 | Oct 6, 2014 | Continuation of budget proposal |

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# Introduction

The introduction of this document defines the purpose, scope, and team information for the project.

## Purpose

The purpose of this document is to identify the preliminary budget for the Autonomous Panda System (APS). It is intended to provide the customers of the APS with justifications for major item decisions. These justifications include decision matrices, risk analysis, and fulfillment of requirements.

## Scope

This document is intended to provide the customers of APS with a list of parts with justification and pricing information. In this list of parts, only major components were considered. These major components are those with prices above $20 [**citation**] and are essential to the early prototyping of the APS. This document also contains a high-level breakdown of the APS to provide an overview of the initial design of the system.

## Team Information

Table 2 contains the team member names and their corresponding roles.

|  |  |
| --- | --- |
| **Name** | **Role** |
| Kurt Pedrosa | Team Leader/Scrum Master |
| Merissa Roth | Software Leader |
| Mary Luongo | Hardware Leader/Product Owner |
| Luis Bogran | Development Leader |
| Kok Peng Tan | Developer |

Table 2. Team Information

# Functional Decomposition System

The APS contains two subsystems that communicate through a system bus. The system bus connects the two subsystems allowing data to be transferred between them. The subsystems are the navigational and operations systems.



Figure 1. Graphical representation of the APS that depicts both subsystems.

The two subsystems shown in Figure 1 overlap to represent a flow of data between them. This flow of data will be performed by software communication. The subsystems will exchange data to perform the tasks during the competition. The operational system will execute all the functionality needed for the interaction between the objects and the APS. The navigational system is in charge of line following, movement, positioning and other related functionalities.

## Decomposition of Vehicle Hardware Layer

The APS is decomposed into five major hardware parts. Figure 2 shows these parts and the flow of data between them. The data flow between the parts is depicted by the use of arrows showing the direction of flow.

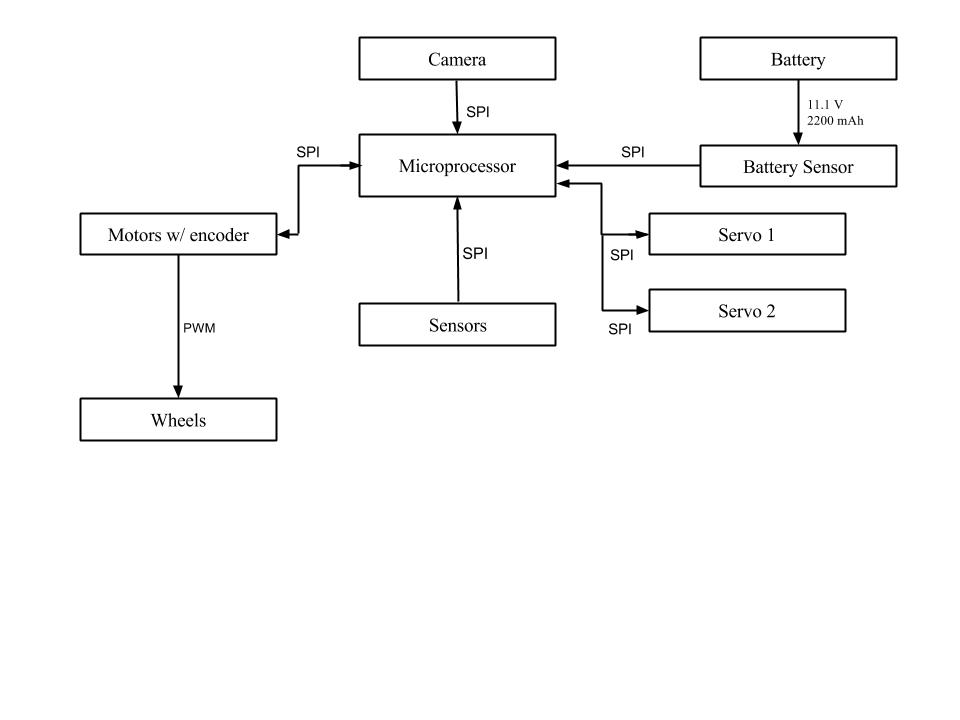


Figure 2. The hardware decomposition with each major hardware part and the flow of data between them.

Each of the five parts work together to accomplish the requirements set forth by the systems requirements specifications (SRS). Communication between each part is paramount, some parts depends on data processed by another part. Figure 2 shows the data transfer between each hardware as well as the means of communications.

The camera will be programed to identify items of interest and relay their position to the microcontroller. Sensors will provide support data to the microcontroller to help reduce positioning, proximity, and other types of error. This data will be analyzed by software, and the result transmitted to the dedicated hardware that will place the system at the desired state. The camera will process the image and relay the information to the system. The system is then able to check that information by comparing it to the sensor data. This comparison is expected to reduce the possibility of error when attempting to interact with the objects and the course during the competition.

The current design calls for a single movable robotic claw that will interact with the objects during the competition. This claw will be controlled by the microprocessor which will be receiving constant data from other hardware components. This data be transfer via serial peripheral interface (SPI) communication, and will determine where to position the robotic claw. The development team speculates the use of multiple claws to be an unnecessary increase of system complexity as well as increase of probability of malfunction. For that reason, the development team agreed to develop a system with a single claw. Because of lack of data, the development team is moving forward with this decision until more information can be collected during prototyping and testing.

Reasons behind the design decisions were to reduce complexity of the system, remain within budget without decreasing the quality of the system, and executing all tasks during the competition. The APS will have a feedback loop concept controlling the dynamic data.

## Decomposition of Communication Hardware Layer

Figure 3 shows the communication between hardware. The flow of data is depicted by the arrows. Data will be transferred between the microcontroller and its internal subsystems. The subsystem will compute that data and control the hardware responsible for the desire action.

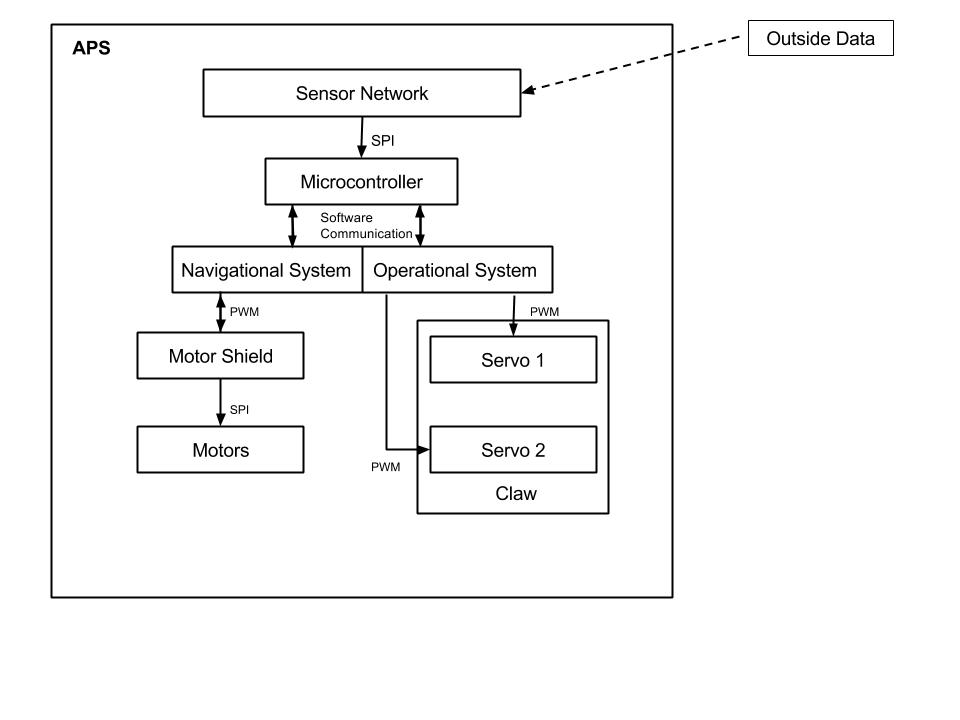


Figure 3. The communication flow between the major components of the APS.

As show on Figure 3, the sensors will received information from outside the APS. This information will be analyzed by the microcontroller and distributed between the subsystems. The development team will implement physical connections between each hardware part, such as wires, as well as software communications, such as function calls, interrupts and other methods. No wireless communication will be necessary.

# Budget Decision Matrices and Justifications

This section of the document contains the reasoning behind the selection of the major components. The use of decision matrices was a main method for selecting all the components to be used for the APS. These matrices show the important characteristics of the components and indexed each of them with a weighted score. The Funky Town Fancy Pandas (FTFP) development team scored the characteristic of each component and the average score is calculated. The total score was gathered and the item with the highest total score was selected as the most desirable component for the system.

## Microcontroller

The microcontrollers considered and descriptions of the decision process are detailed in the following content. The process was tailored to provide the APS with the optimal microcontroller to control all of the subsystems.

### Items under Consideration

The following items were considered as the microcontroller used to operate the subsystems of the APS. All of the items have been characterized in Table 3 by item identification name/ item ID, vendor, and a description.

|  |  |  |
| --- | --- | --- |
| **Item ID** | **Vendor** | **Description** |
| Arduino Due | Amazon | A microcontroller based on the ARM Cortex-M3 chip. Contains 54 general-purpose input/output (GPIO) pins. It run at a clock speed of 84 MHz. Contains 96 KB of RAM (Random Access Memory) and 512 KB of flash memory. It is a popular microcontroller for novice and expert developers. |
| Raspberry Pi Modle B+ | Amazon | A microcontroller with a Broadcom BCM2835 chipset, Micro SD storage, and 40 GPIO pins. Contains 512 MB of RAM and a processor speed of 700 MHz. It has gained popularity between the novice and experience developers. |
| UDOO Quad | Udoo | A microcontroller based on an ARM Cortex-A9 chip with a clock speed of 1 GHz. On-board integration with the Arduino Due Cortex-M3 chip set. It contains 76 fully available GPIO pins, and two micro USB storage slots. It is not a popular microprocessor within the developer community but has promising features that may satisfy most novice and expert developers. |
| BeagleBone Black | Amazon | A low-cost development platform with running an ARM Cortex – A8 chip. It runs at a clock speed of 1 GHz, contains 512 MB of RAM and 4 GB of on board flash memory. It contains 92 GPIO pins and runs a Linux operating system. It is popular with developers who have some experience. |

Table 3. Items under consideration for the microcontroller

### Decision Matrix

Table 4 depicts the decision matrix used to compare and select the microcontroller. The matrix considers the price, speed of the processor, RAM, memory, GPIO pins, operating system (OS) or integrated development environment (IDE), and ease of use. The decision matrix describes the specifications of each item considered and computes a total by multiplying the score by a weighted factor for the category being analyzed. The score given to each category was determined by the development team, and the

|  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- |
| **Product** | **Price** | **Speed** | **RAM** | **Memory** | **GPIO** | **OS/IDE** |  |
| Arduino Due | $40.22 | 84 MHz | 96 KB | 512 KB | 54 | Arduino IDE |  |
| Raspberry Pi Model B+ | $38.89 | 700 MHz | 512 MB | SD Card | 40 | Linux |  |
| UDOO Quad | $135 | 1 GHz | 1 GB | SD Card/SATA | 76 | Linux/Aduino IDE |  |
| BeagleBone Black | $65.90 | 1 GHz | 512 MB | 4 GB | 65 | Linux |  |
|  |  |  |  |  |  |  |  |
| **Product Weight** | **Price** | **Speed** | **RAM** | **Memory** | **GPIO** | **OS/IDE** |  |
| Arduino Due | 8 | 1 | 1 | 1 | 6 | 1 |  |
| Raspberry Pi Model B+ | 9 | 6 | 5 | 8 | 1 | 8 |  |
| UDOO Quad | 1 | 9 | 9 | 9 | 9 | 9 |  |
| BeagleBone Black | 5 | 9 | 5 | 5 | 8 | 8 |  |
|  |  |  |  |  |  |  |  |
| **Weighted** | 0.2 | 0.25 | 0.15 | 0.25 | 0.05 | 0.1 |  |
|  |  |  |  |  |  |  |  |
| **Product Total** | **Price** | **Speed** | **RAM** | **Memory** | **GPIO** | **OS/IDE** | **Total** |
| Arduino Due | 1.6 | 0.25 | 0.15 | 0.25 | 0.3 | 0.1 | 2.65 |
| Raspberry Pi Model B+ | 1.8 | 1.5 | 0.75 | 2 | 0.05 | 0.8 | 6.9 |
| UDOO Quad | 0.2 | 2.25 | 1.35 | 2.25 | 0.45 | 0.9 | 7.4 |
| BeagleBone Black | 1 | 2.25 | 0.75 | 1.25 | 0.4 | 0.8 | 6.45 |

Table 4. Decision matrix for the microcontroller

### Justification

The categories under consideration in the decision matrix of the microcontroller were the price, the speed of the CPU, the amount of RAM available, the amount of memory available, the number of GPIO pins, the operating system, and how easy it is to use the device. Each categories was given a score between 1 – 9, one being the worse and nine being the best. This score was determine by ranking each item and their specifications. Each category was given a weighted score which determined its importance. Using the score and the weighted score, the best microcontroller was found for the APS.

**Price**

The price of each microcontroller was considered to be the most important factor. The goal is to remain under budget, therefore the item price had more importance than other factors. The most expensive item was the UDOO Quad, costing $135.00, therefore it got a score of nine. The cheapest item was the Raspberry Pi costing $38.89, therefore it got a score of one. The equations used to calculate the score of the Arduino Due and the BeagleBone was, where *x* is the price being compared and $38.99 is the best price between all of the items being considered. The Arudino Due costs $40.22, which yield a score of 8.7. That score was rounded down to eight, a valid score. The reason for rounding down was due to the fact that the Arduino Due is slightly more expensive and did not deserve a score of nine, to be rounded up instead of down. The Beaglebone received a score of 5.3 rounding down to a five.

**Clock Speed**

The speed in which the microprocessor operated was considered to be as important as the price. Both the UDOO Quad and the BeagleBone Black had faster speed then the other items considered. For this reason, both UDOO Quad and the BeagelBone Black were given a score of nine. The Arduino Due was given a score of one due to its clock speed being 84 MHz, the slowest speed among the items being considered. The Raspberry Pi received a score of 6.3 rounded to six. The equation used to calculate the Raspberry Pi was, the ratio between the Raspberry Pi’s clock speed and the highest speed multiplied by a factor of nine to normalize the number. A common method of comparing speed of a microprocessor is by analyzing clock cycles per instruction (CPI) and millions of instructions per second (MIPS). These method are used when comparing multiple microprocessors of the same architecture. They were not used for this comparison because not all microprocessors have the same architecture, therefor any measurements done using CPI and MIPS would not be a valid comparison.

**RAM**

The amount of RAM was considered to be the third most important characteristic. The RAM correlates to usable space for data during execution of instructions. Microprocessors with larger amount of RAM are less likely to use clock cycles to manage memory instead of using those clock cycle for the execution of instructions. Before execution, the microprocessors moves the data from memory into RAM. This allows for faster execution and avoids constant fetching from memory. The UDOO Quad came out on top with 1 GB of RAM, receiving a score of nine. The Arduino Due had the smallest amount, 96 KB of RAM, and received a score of one. The Raspberry Pi and the BeagleBone Black both had the same amount of RAM, 512 MB. The equation used to calculate their value was and the result was rounded to 5.

**Memory**

The amount of memory was considered to be the second most important characteristic of the items. Memory is where the operating system, executable instructions, and any other files essential to the system are stored. Normally the item with the largest amount of memory would get a score of 9 but two of the microcontrollers have the options of secure digital (SD) card and serial advanced technical attachment (SATA) port. These two memory options gives the developer the choice of memory size. Because the UDOO Quad has the option of either a SD Card or a SATA port it received a score of 9. The Raspberry Pi, having only the option of a SD card, received a score of 8. For comparison, an 8 GB SD Card was chosen. The equation used to attain scores for the Arduino Due and the BeagleBone Black was where “x” is the amount of memory of the item being considered. The Arduino Due got a score of 0.000576 rounded to 1. The BeagleBone Black received a score of 4.5 rounded to 5.

**GPIO**

The number of GPIO pins was considered to be the fith most important characteristic. The quantity of pins translates to how many input/output (I/0) external devices the microcontroller can interact with. The microcontroller with the most number of GPIO pins was UDOO Quad, therefor received a score of 9. The Raspberry Pi had the least number of GPIO pins, therefore received a score of 1. The equation use to calculate the score for the BeagleBone Black and the Arduino Uno was where “x” is the number of GPIO pins being compared. The Arduino Due received a score of 6.3 rounded to 6. The BeagleBone Black received a score of 7.6 rounded to an 8.

**OS/IDE**

## Sensors

The following tables list the categories, in which the sensors were compared and the weight given to each category. This decision-making process consists of a decision matrix, requirements traceability, requirements fulfillment, and a risk analysis to decide which part will be used.

### Items under Consideration

The following items listed in Table 5 were considered as the possible sensors for the APS. Each item has a unique ID number and its corresponding vendor. The categories each item will be scored on are: availability, price, frames per second (FPS), and resolution. The Pixy Cam became very attractive to the group because of its image detection capabilities, and the speed at which it does it. The CMUcam4 is an earlier version of the Pixy Cam, making it a suitable candidate. The Raspberry Pi camera has also been used in several similar tasks, such as in aiding the turn of a Rubik’s Cube, capturing the team’s attention. The Minoru 3D webcam was also considered in aims of trying to implement the image processing with OpenCV.

|  |  |  |
| --- | --- | --- |
| **Sensors** | **ID** | **Vendor** |
| Pixy Cam | B00IUYUA80 | Amazon |
| CMUcam4 Robot Vision | RB-Sea-05 | Robotshop |
| Raspberry Pi | RB- Ras-01 | Robotshop |
| Minoru 3D webcam | Rb-Pul-01 | Robotshop |

Table 5. Items under consideration for the sensor

### Decision Matrix

Table 6 describes the decision for the camera sensors under consideration.

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| **Product** | **Availability** | **Price** | **FPS** | **Resolution** |  |
| Pixy Cam | Available | $0 | 50 | (640 x 400) |  |
| CMUcam4 Robot Vision | Not available | $116.24 | 30 | VGA (640 x 840) |  |
| Raspberry Pi | Not available | $29.95 | 30 | (1920 x 1080) |  |
| Minoru 3D webcam | Not available | $37.99 | 30 | (320 x 240) |  |
|  |  |  |  |  |  |
| **Product Weight** | **Availability** | **Price** | **FPS** | **Resolution** |  |
| Pixy Cam | 9 | 9 | 9 | 3 |  |
| CMucam4 Robot Vision | 5 | 1 | 5 | 4 |  |
| Raspberry Pi | 5 | 8 | 5 | 9 |  |
| Minoru 3D webcam | 5 | 7 | 5 | 1 |  |
|  |  |  |  |  |  |
| **Weighted** | 0.20 | 0.30 | 0.25 | 0.25 |  |
|  |  |  |  |  |  |
| **Product Total** | **Availability** | **Price** | **FPS** | **Resolution** | **Total** |
| Pixy Cam | 1.8 | 2.7 | 2.25 | 0.75 | 7.50 |
| CMucam4 Robot Vision | 1.0 | 0.3 | 1.25 | 1.0 | 3.55 |
| Raspberry Pi | 1.0 | 2.4 | 1.25 | 2.25 | 6.90 |
| Minoru 3D webcam | 1.0 | 1.4 | 1.25 | 0.25 | 3.90 |

Table 6. Decision matrix for the sensors

### Justification

The following describes the process used to justify our decisions over what parts would be used and the reasoning behind those decisions.

**Availability**

The availability score for each item was determined by scoring the items readily available to the FTFP with a score of nine, the highest possible score. The items that had to be ordered and shipped to the FTFP were given a score of five. The availability category has a weighted value of 20%.

**Price**

The values for the score of the prices of each item was obtained by setting the least expensive item to have the highest score of nine and the most expensive item to have the lowest score of one. Once the minimum and maximum were determined, the scores for the remaining items were calculated by subtracting the price of the item from the price of the most expensive item, dividing it by the most expensive item price, multiplying that by the highest score possible, nine, and adding one to the answer. The one is added taking in consideration that the lowest possible value is one, and the answers are rounded up or down accordingly. Table 7 shows the calculations behind the scores for the price category, with the price category having a weighted value of 30%. The scores for the following items were calculated using the following equation:

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| B00IUYUA80 | Least expensive item (free) | 9 |
| RB-Sea-05 | Most expensive item ($116.24) | 1 |
| RB- Ras-01 |  | 8 |
| Rb-Pul-01 |  | 7 |

Table 7. Calculations for the scores of the price of the sensors

**FPS**

The frame rate, or frame frequency or frames per second, is the frequency at which the sensor produces unique consecutive images called frames [**reference**]. The values for the score of the FPS category of each item were obtained by giving the item with the highest frame rate the highest possible score of nine. A minimum value could not be set because the rest of the items have the same frame rate. Once the maximum value was determined, the scores for the remaining items were calculated by subtracting the FPS value of the item from the highest scoring item, then multiplying by the highest score possible of nine, and adding one to the answer. The one is added taking in consideration that the lowest possible value is one, with the answers being rounded up or down accordingly. The FPS category has a weighted value of 25%. Table 8 shows the calculations performed to obtain the scores.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| B00IUYUA80 | Highest FPS (50) | 9 |
| RB-Sea-05 |  | 5 |
| RB- Ras-01 |  | 5 |
| Rb-Pul-01 |  | 5 |

Table 8. Calculations for the score of the FPS

**Resolution**

The resolution of the sensors is very important to the performance of the sensors. The values for the score of the resolution category of each item were obtained by giving the item with the highest resolution the highest possible score of nine. The item with the lowest resolution was given the lowest possible score of one. Once the maximum and minimum values were determined, the scores for the rest of the items were calculated by subtracting the resolution value from the highest resolution value, dividing it by the highest resolution value, multiplying it by nine, the highest possible score, and adding one to the answer. The one is added considering that the lowest possible value is one, with the answered being rounded up or down accordingly. The resolution category has a weighted value of 25%.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| B00IUYUA80 | 2.8 3 | 3 |
| RB-Sea-05 | 4.12 4 | 4 |
| RB- Ras-01 | Highest resolution (1080) | 9 |
| Rb-Pul-01 | Lowest resolution (320 x240) | 1 |

Table 9. Calculations for the score of the resolutions

**Language**

A programming language category was considered to rate the sensors too. The previous knowledge and experience of the software engineers at hand will be very important when the code starts to be written. For example, the development team has experience working with Arduino boards and writing and implementing code for Arduino, so using an Arduino board would require C/C++ knowledge. The added learning curve of a new programming language would delay the team and the development of software; however, it was not included in the decision matrices because all of the sensors under consideration are compatible with the microcontrollers under consideration, and because it would depend entirely on the microcontroller chosen, not on the sensor.

## Motors

The motors are an essential part of the movement of the APS. Without motors, the APS would not be able to move to complete the tasks. The following provides the process that was used to determine the motor that would be used in the APS.

### Items under Consideration

Table 10 contains the items under consideration for the battery. The items under consideration have been listed below and contain the product ID and the vendor.

|  |  |  |
| --- | --- | --- |
| **Motors** | **ID** | **Vendor** |
| Standard Gearmotor | ROB-12399 | Sparkfun |
| Precision Gearmotor | ROB-12497 | Sparkfun |
| 154:1 Metal Gearmotor 20 D x 44 L mm. | Pololu item #: 1109 | Pololu |
| 100:1 Metal Gearmotor 37 D x 57 L mm. | Pololu item #: 1106 | Pololu |

Table 10. Items under consideration for the motor

### Decision Matrix

Table 11 contains the decision matrix for the motor. The motors considered were broken down into categories that were essential for the decision making process. The categories include the price, revolutions per minute (RPM), stall torque, stall current and weight of the motor.

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
| **Product** | **Price** | **RPM** | **Stall Torque (Ncm)** | **Stall Current (A)** | **Weight (g)** |
| Standard Gearmotor | $24.95 | 101 | 32.2 | 0.5 | 119.07 |
| Precision Gearmotor | $34.95 | 90 | 98.01 | 1 | 240.97 |
| 154:1 Metal Gearmotor 20 D x 44 L mm. | $19.95 | 90 | 84.73 | 3.3 | 32.6 |
| 100:1 Metal Gearmotor 37 D x 57 L mm. | $24.95 | 100 | 155.35 | 5 | 201.28 |
|  |  |  |  |  |  |
| **Product Weight** | **Price** | **RPM** | **Stall Torque** | **Stall Current** | **Weight** |
| Standard Gearmotor | 4 | 6 | 2 | 9 | 6 |
| Precision Gearmotor | 1 | 5 | 6 | 8 | 1 |
| 154:1 Metal Gearmotor 20 D x 44 L mm. | 5 | 5 | 5 | 4 | 9 |
| 100:1 Metal Gearmotor 37 D x 57 L mm. | 4 | 6 | 9 | 1 | 3 |
|  |  |  |  |  |  |
| **Weighted** | 0.15 | 0.05 | 0.4 | 0.35 | 0.05 |
|  |  |  |  |  |  |
| **Product Total** | **Price** | **RPM** | **Stall Torque** | **Stall Current** | **Weight** | **Total** |
| Standard Gearmotor | 0.60 | 0.30 | 0.80 | 3.15 | 0.30 | 5.15 |
| Precision Gearmotor | 0.15 | 0.25 | 2.40 | 2.80 | 0.05 | 5.65 |
| 154:1 Metal Gearmotor 20 D x 44 L mm. | 0.75 | 0.25 | 2.00 | 1.40 | 0.45 | 4.85 |
| 100:1 Metal Gearmotor 37 D x 57 L mm. | 0.60 | 0.30 | 3.6 | 0.35 | 0.15 | 5.00 |

Table 11. Decision matrix for the motors

### Justification

The following describes the process used for obtaining the scores for the various categories used to rate the motors under consideration in the decision matrix. The data for the motors under consideration was obtained from Sparkfun and Pololu.

**Price**

Table 12 contains the price category scores for the prices of the motors. The score for the price was obtained by normalizing the price and multiplying the normalized values by the maximum score of 9 and adding 1. The price category was weighted at 15%. The equation below is an example to show how the price score was calculated.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| ROB-12399 |  | 4 |
| ROB-12497 |  | 1 |
| Pololu item #: 1109 |  | 5 |
| Pololu item #: 1106 |  | 4 |

Table 12. Calculations for the price of the motor

**RPM**

Table 13 contains the RPM category scores for the RPM of the motors. The motors chosen were approximately 90 RPM. This is used to determine the differences in the torque of the different motors. The motors for each item may have a different RPM, but the torque should scale in a similar manner with the change in RPM of the different motors. The score for this is determined by dividing the RPM value by 90 and multiplying by 5, as 90 RPM was the arbitrary choice. The RPM category was weighted at 5%. The equation below is an example to show how the RPM score was calculated.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| ROB-12399 |  | 6 |
| ROB-12497 |  | 5 |
| Pololu item #: 1109 |  | 5 |
| Pololu item #: 1106 |  | 6 |

Table 13. Calculations for the RPM of the motor

**Stall Torque**

Table 14 contains the stall torque category scores for the motors. This determines the amount of load the APS would be able to move. If the load of the APS was above the limit, defined by the stall torque, the motor would enter a stall state in which it would be unable to move. The equation to determine the stall torque was derived by calculating the normalized stall torque values multiplied by 9 and subtracting the result from 9, which is the maximum score. The stall torque category was weighted at 35%. The equation below is an example to show how the stall torque score was calculated.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| ROB-12399 |  | 2 |
| ROB-12497 |  | 6 |
| Pololu item #: 1109 |  | 5 |
| Pololu item #: 1106 |  | 9 |

Table 14. Calculations for the stall torque of the motor

**Stall Current**

Table 15 contains the stall current category scores, the maximum current the APS needs to supply the motors when they enter a stall state. The equation used to determine the scores was derived by normalizing the stall current values, multiplying them by nine, and adding one. The stall current category was weighted at 30%. The equation below is an example to show how the stall current score was calculated.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| ROB-12399 |  | 9 |
| ROB-12497 |  | 8 |
| Pololu item #: 1109 |  | 4 |
| Pololu item #: 1106 |  | 1 |

Table 15. Calculations for the stall current of the motor

**Weight**

Table 16 contains the weight category calculations for the weights of the different motors. The scores for this category were determined by normalizing the weights of the motors, multiplying it by nine, and adding one. The weight category was weighted at 5%. The equation below is an example to show how the weight score was calculated.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| ROB-12399 |  | 6 |
| ROB-12497 |  | 1 |
| Pololu item #: 1109 |  | 9 |
| Pololu item #: 1106 |  | 3 |

Table 16. Calculations for the weight of the motor

## Claw

The claw is a crucial part of the APS, as without it, the robot would not be able to complete any of the tasks required. The categories below describe the items under consideration, the decision matrix, and the justification of the decision made.

### Items under Consideration

Table 17 contains the items under consideration for the claw. The items under consideration have been listed below and contain the product ID and the vendor.

|  |  |  |
| --- | --- | --- |
| **Product** | **ID** | **Vendor** |
| OWI-535 Robotic Arm Edge | OWI-535 | Amazon |
| Stacker 2WD Mobile Robot | RB-Sct-154 | RobotShop |
| AX-12 Dual Robotic Gripper | AX12DUAL\_GRIP | CrustCrawler |
| AL5D Arm Hardware Only - Kit | AL5D-NS | Lynxmotion |

Table 17. Items under consideration for the claw

### Decision Matrix

Table 18 contains the decision matrix for the claw. Every item under consideration has been evaluated and broken down into different categories. The claw size is how wide the claw will open. The DOF category is the degrees of freedom and how the claw will be able to move.

|  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- |
| **Product** | **Claw Size (in.)** | **Weight (lbs.)** | **Price** | **DOF** | **Controlled** |  | |
| OWI-535 Robotic Arm Edge | 2-3 | 1.45 | $44.29 | 5 | RC |  |
| Stacker 2WD Mobile Robot | 4.25 | 3 | $139.99 | 2 | RC/autonomous |  |
| AX-12 Dual Robotic Gripper | 9 | 2 | $69.00 | 6 | Autonomous |  |
| AL5D Arm Hardware Only - Kit | 1.3 | 0.6 | $143.88 | 4 | Autonomous |  |
|  |  |  |  |  |  |  |
| **Product Weight** | **Claw Size** | **Weight** | **Price** | **DOF** | **Controlled** |  |
| OWI-535 Robotic Arm Edge | 4 | 9 | 10 | 8 | 1 |  |
| Stacker 2WD Mobile Robot | 7 | 5 | 4 | 3 | 7 |  |
| AX-12 Dual Robotic Gripper | 10 | 6 | 9 | 9 | 9 |  |
| AL5D Arm Hardware Only - Kit | 2 | 9 | 4 | 6 | 9 |  |
|  |  |  |  |  |  |  |
| **Weighted** | 0.25 | 0.15 | 0.15 | 0.25 | 0.2 |  |
|  |  |  |  |  |  |  |
| **Product Total** | **Claw Size** | **Weight** | **Price** | **DOF** | **Controlled** | **Total** |
| OWI-535 Robotic Arm Edge | 1.0 | 1.35 | 1.5 | 2.0 | 0.2 | 6.05 |
| Stacker 2WD Mobile Robot | 1.75 | 0.75 | 0.6 | 0.75 | 1.4 | 5.25 |
| AX-12 Dual Robotic Gripper | 2.5 | 0.9 | 1.35 | 2.25 | 1.8 | 8.8 |
| AL5D Arm Hardware Only - Kit | 0.5 | 1.35 | 0.6 | 1.5 | 1.8 | 5.75 |

Table 18. Decision matrix for the claw

### Justification

The following categories justify the decision of choosing the AX-12 Dual Robotic Gripper. This also describes why certain parts were chosen over others.

**Claw Size**

The claw size was a major component of the decision matrix. The claw must open a minimum of 3 in. to meet the requirement of twisting one row of the Rubik’s Cube 180 degrees. A Rubik’s Cube is 3 in. in length, width, and height. A claw that opened less than 3 in. was still considered under the assumption the width would be fabricated later in the term. However, a claw already having an opening of 3 in. or more was given a better score than one that did not. The weighted value of the claw size category is 25% because of the importance to play all of the games using the same claw.

**Price**

The price of the claw had a weighted value of 15%. The least expensive claw, OWI-535 Robotic Arm Edge, was given the best score of nine. The most expensive item was AL5D Arm Hardware Only – Kit, which has the lowest score of one. For the Stacker 2WD Mobile Robot and the AC-12 Dual Robotic Gripper, the most expensive item was subtracted by the item’s price. The difference of the two prices was divided by the most expensive item. The highest score of nine was multiplied by the ratio and then one was added to the result. Table 19 shows the calculations of the price. The formula used is also shown below.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| OWI-535 Robotic Arm Edge | Least expensive item ($44.29) | 9 |
| Stacker 2WD Mobile Robot |  | 1 |
| AX-12 Dual Robotic Gripper |  | 5 |
| AL5D Arm Hardware Only - Kit | Most expensive item ($143.88) | 1 |

Table 19. Calculations for the price of the claw

**Weight**

The weight of the claw had a weighted value of 15%. The lower the score number meant the claw was the heaviest. The higher the score number meant the claw was lighter. The other two values were determined by subtracting the heaviest weight by the weight of the item being evaluated. The heaviest weight was divided by the difference of the two weights. The highest score of nine was multiplied by the ratio and then one was added to the answer. Table 20 depicts these calculations. The formula used is shown below.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculations** | **Score** |
| OWI-535 Robotic Arm Edge |  | 5 |
| Stacker 2WD Mobile Robot | Heaviest weight (3 lbs.) | 1 |
| AX-12 Dual Robotic Gripper |  | 4 |
| AL5D Arm Hardware Only - Kit | Lightest weight (0.6) | 9 |

Table 20. Calculations for the weight of the claw

**Controlled**

As stated by the IEEE SoutheastCon 2015 Hardware Competition, the robot must move autonomously at all times. Having a claw that was remote controlled (RC) would not be eligible for this competition. How the claw was controlled was scored higher if it was autonomous, lower if it was an RC, and in the middle if it was both autonomous and RC. The weighted value of the controlled category was 25%.

## Wheels

The wheels support the body of the APS and give the system movement. The following is a description of the decision-making process used to select wheels for the APS. The process included analytical, qualitative, and quantitative methods and is shown with the reasoning behind these methods.

### Items under Consideration

The items in Table 21 are considered as different options for the wheels for the APS.

|  |  |  |
| --- | --- | --- |
| **Wheels** | **ID** | **Vendor** |
| Vex Robotics Omni (4 in.) | 217-2584 | Amazon |
| Vex Robotics Mecanum (4 in.) | 217-3644, Right (217-3645, Left) | Amazon |
| Fingertech Mecanum (4 in.) | ROB-11578 | SparkFun |
| Pololu Wheels (42 mm. x 19 mm) | ROB-0889 | SparkFun |

Table 21. Items under consideration for the wheels

### Decision Matrix

The decision matrix displays the characteristics of the wheels considered for the APS. Table 22 contains the description matrix, which shows the price, weight, load rating, and holonomic ability for each wheel under consideration. The highlighted item is the final choice by the FTFP team. The decision matrix gave two top choices and as per research the team chose the second choice, the omni wheels. The team chose the omni wheels, for the prototype, for their reputation of stability and precision.

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| **Product** | **Price** | **Weight (lbs.)** | **Load Rating (lbs.)** | **Holonomic** |
| Vex Robotics Omni | $12.50 | 0.42 | 200 | Yes |
| Vex Robotics Mecanum | $15.00 | 0.55 | 200 | Yes |
| Fingertech Mecanum | $18.75 | 0.1325 | 30 | Yes |
| Pololu Wheels | $3.50 | 0.08 | Not Found | No |
|  |  |  |  |  |
| **Product Weight** | **Price** | **Weight** | **Load Rating** | **Holonomic** |
| Vex Robotics Omni | 4 | 7 | 9 | 9 |
| Vex Robotics Mecanum | 3 | 9 | 9 | 9 |
| Fingertech Mecanum | 1 | 2 | 5 | 9 |
| Pololu Wheels | 8 | 1 | 1 | 1 |
|  |  |  |  |  |
| **Weighted** | 0.25 | 0.25 | 0.2 | 0.3 |
|  |  |  |  |  |
| **Product Total** | **Price** | **Weight** | **Load Rating** | **Holonomic** | **Total** |
| Vex Robotics Omni | 1.0 | 1.75 | 1.8 | 2.7 | 7.25 |
| Vex Robotics Mecanum | 0.75 | 2.25 | 1.8 | 2.7 | 7.5 |
| Fingertech Mecanum | 0.25 | 0.5 | 1.0 | 2.7 | 4.45 |
| Pololu Wheels | 2.0 | 0.25 | 0.2 | 0.3 | 2.75 |

Table 22. Decision matrix for the wheels

### Justification

The process for the decisions are described in the next paragraphs. The data for these items are found on the websites of Amazon, SparkFun, and Vex Robotics. The wheels are judged based on price, weight, load rating, and the wheels holonomic ability.

**Price**

The price of the wheels have a weighted valued of 25% of the decision. The wheels are sold by the vendors in multiple pack styles. The Vex Robotics Omni wheels are sold for $24.99, with two wheels per package. The Vex Robotics Mecanum wheels are sold for $59.99, with four wheels per package. The Fingertech Mecanum wheels are sold for $74.95, containing four wheels per package. The Pololu Wheel wheels are sold for $6.95, containing two wheels per package. For the decision matrix, the prices are divided by the number of items sold to find the price per each item. The prices are normalized by comparing each price to the greatest price. The range of scores possible goes from one to nine. The normalized prices are multiplied by nine and added to one, as shown in Table 23.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| Vex Robotics Omni |  | 4 |
| Vex Robotics Mecanum |  | 3 |
| Fingertech Mecanum |  | 1 |
| Pololu Wheels |  | 8 |

Table 23. Calculation for the price of the wheels

**Weight**

The weight of the wheels have a weighted valued of 25%. The APS has a maximum weight limit of 50 lbs. Therefore, the weight of each wheel is important in choosing the wheels for the APS. The wheels support the entire body of the APS; consequently the point values were reversed to have the heavier wheels to be rated higher than the low weight wheels. Table 24 shows the calculation to find the score for the weight of each type of wheel. The weight of each type of wheel is normalized to the greatest weight. The score is multiplied by nine and added to one. The final score is subtracted from ten to yield the heavier wheels having a higher rating.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| Vex Robotics Omni |  | 7 |
| Vex Robotics Mecanum |  | 9 |
| Fingertech Mecanum |  | 2 |
| Pololu Wheels |  | 1 |

Table 24. Calculation for the weight of the wheels

**Load Rating**

The APS has a maximum weight limit of 50 lbs., thus the load rating was valued at 20% of the decision. Two types of wheels have equivalent load ratings of 200 lbs. and have the point value of nine as they have the best rating value. One wheel type, Pololu Wheels, has no load rating available for it, so it has the lowest value possible of one. The last wheel, the Fingertech Mecanum, has the lowest rated value, but larger than the unknown value. Consequently, the value for the Fingertech Mecanum is given as the mid-range value, five.

**Holonomic**

Each wheel type is judged based on whether it has holonomic ability or not. Each wheel is given either a nine, for yes, or a one, for a no. The team made a collective decision to utilize wheels having holonomic abilities. The weighted value of the holonomic category is 30%.

## Battery

The battery will provide the power that the APS needs. The following provides the process that was used to determine the battery that would be used in the APS.

### Battery Types

Lithium polymer (LiPo), Nickel Cadmium (NiCad), and Nickel Metal Hydrate (NiMH) batteries are some of the most common types of rechargeable batteries used in robotics and remote control vehicles. There are different benefits for each of the different battery types. Table 25 contains general features of the different battery types

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| **Battery** | **Cost** | **Memory Effect** | **Weight** | **Capacity** |
| LiPo | Low | No | Very Light | High |
| NiCad | Low | Yes | Light | Low |
| NiMH | High | Yes | Heavy | High |

Table 25. Features of Different Battery Types

Due to the general features of the LiPo Batteries listed above, it would be clear that LiPo batteries would be the ideal choice as the battery for the APS.

### Items under Consideration

Table 26 contains the items under consideration for the battery. The items under consideration have been listed below and contain the product ID and the vendor.

|  |  |  |
| --- | --- | --- |
| **Battery** | **ID** | **Vendor** |
| Polymer Lithium Ion Battery-2200 mAh 7. 4 V | PRT-11856 | Sparkfun |
| Turnigy 2200 mAh 3 S 20 C Lipo Pack | T2200.3S.20 | Hobbyking |
| Turnigy 2200 mAh 3 S 25C Lipo Pack | T2200.3S.25 | Hobbyking |
| Turnigy 2200 mAh 3 S 30 C Lipo Pack | T2200.3S.30 | Hobbyking |

Table 26. The items under consideration for the batteries

### Decision Matrix

Table 27 contains the decision matrix of the battery. The batteries considered are broken down into categories that are essential for the decision making process. The categories include the price, capacity discharge rate, and weight of the battery.

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| **Product** | **Price** | **Capacity (mAH)** | **Discharge Rate (C)** | **Weight (lbs.)** |
| Polymer Lithium Ion Battery-2200 mAh 7.4 V | $13.95 | 2200 | 30 | 0.45 |
| Turnigy 2200 mAh 3 S 20 C Lipo Pack | $8.50 | 2200 | 20 | 0.41 |
| Turnigy 2200 mAh 3 S 25 C Lipo Pack | $10.60 | 2200 | 25 | 0.41 |
| Turnigy 2200 mAh 3 S 30 C Lipo Pack | $13.50 | 2200 | 30 | 0.43 |
|  |  |  |  |  |
| **Product Weight** | **Price** | **Capacity** | **Discharge Rate** | **Weight** |
| Polymer Lithium Ion Battery-2200 mAh 7.4 V | 1 | 5 | 9 | 1 |
| Turnigy 2200 mAh 3 S 20 C Lipo Pack | 5 | 5 | 6 | 2 |
| Turnigy 2200 mAh 3 S 25 C Lipo Pack | 3 | 5 | 8 | 2 |
| Turnigy 2200 mAh 3 S 30 C Lipo Pack | 1 | 5 | 9 | 1 |
|  |  |  |  |  |
| **Weighted** | 0.15 | 0.25 | 0.5 | 0.1 |
|  |  |  |  |  |
| **Product Total** | **Price** | **Capacity** | **Discharge Rate** | **Weight** | **Total** |
| Polymer Lithium Ion Battery-2200mAh 7.4V | 0.15 | 1.25 | 4.5 | 0.1 | 6 |
| Turnigy 2200 mAh 3S 20C Lipo Pack | 0.75 | 1.25 | 3 | 0.2 | 5.2 |
| Turnigy 2200 mAh 3S 25C Lipo Pack | 0.45 | 1.25 | 4 | 0.2 | 5.9 |
| Turnigy 2200 mAh 3S 30 C Lipo Pack | 0.15 | 1.25 | 4.5 | 0.1 | 6 |

Table 27. Decision matrix for the batteries

### Justification

The following describes the process used to obtain the scores for the various categories used to rate the batteries under consideration in the decision matrix. The data for the batteries under consideration was found from Sparkfun and Hobbyking.

**Price**

The score for the price was obtained by normalizing the price and multiplying the normalized valued by the maximum score of 9 and adding 1. The price category was weighted at 15%. Table 28 contains the calculations for the price of the battery.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| PRT-11856 |  | 1 |
| T2200.3S.20 |  | 5 |
| T2200.3S.25 |  | 3 |
| T2200.3S.30 |  | 1 |

Table 28. Calculations for the price of the batteries

**Capacity**

The capacity category scores the different capacities of the batteries. As the capacities of the four different batteries were 2200 mAh. A score of 5 was given to all the batteries. The capacity category was weighted at 25%.

**Discharge Rate**

The discharge rate, C rating, of the batteries scores the discharge relative to the battery capacity, a 100 mAh capacity at a 5 C rate will have a total capacity of 500 mA. The equation to determine the score was derived by normalizing the C rating multiplied by nine and subtracting it from nine, which is the maximum score. The discharge rate category was weighted at 30%. Table 29 contains the calculations for the discharge rate.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| PRT-11856 |  | 9 |
| T2200.3S.20 |  | 6 |
| T2200.3S.25 |  | 8 |
| T2200.3S.30 |  | 9 |

Table 29. Calculations for the discharge rate of the batteries

**Weight**

Table 30 contains the weight category to determine the weight of the different batteries. The scores for this category are determined by normalizing the weights of the motors multiplied by 9 and adding 1. The weight category was weighted at 5%.

|  |  |  |
| --- | --- | --- |
| **Item** | **Calculation** | **Score** |
| PRT-11856 |  | 1 |
| T2200.3S.20 |  | 2 |
| T2200.3S.25 |  | 2 |
| T2200.3S.30 |  | 1 |

Table 30. Calculations for the weight of the batteries

# Requirements Traceability

The following items describe how each requirement in the FTFP’s System Requirement Specification (SRS) traces to the parts needed to build the APS. The following tables will refer to the IEEE SoutheastCon 2015 Hardware Competition (SHC) rules for requirements traceability purposes.

## Microcontroller

Table 31 contains the requirements related to the microcontroller and how each requirement will be fulfilled.

|  |  |  |
| --- | --- | --- |
| **ID** | **Requirement Text** | **Fulfillment** |
|  |  |  |

Table 31. Requirements traceability for the microcontroller

## Sensors

Table 32 contains the requirements related to the sensors and how each requirement will be fulfilled.

|  |  |  |  |
| --- | --- | --- | --- |
| **ID** | **Requirement Text** | **SHC Rules Traceability** | **Fulfillment** |
| 4.1.3 | The APS shall monitor the red LED on the floor. | Once the signal in shut off the timer is started and the round begins. | The Pixy Cam uses hue and saturation as its primary means of images detection. |
| 4.1.5 | The APS shall follow the line on the floor. | Drive on the white line (must cover the line all of the time). | The image detection capabilities of the Pixy Cam will be utilized to fulfill this requirement. |
| 4.1.6 | The APS shall remain within the playing board. | The competition round will end if any part of the robot leaves the playing board. | The image detection capabilities will keep the robot on the line to ensure it does not leave the playing board. |
| 4.1.7.1 | The APS shall identify the game station. | Each toy will be placed in a white block. | The image detection capabilities of the Pixy Cam will be utilized to identify the game station. |
| 4.1.8 | The APS shall stop moving once the finish line is crossed. | The competition round will end when the robot crosses the finish line. | The image detection capabilities of the Pixy Cam will be utilized to detect the finish line and stop the APS once it has been crossed. |
| 4.2.2 | The APS shall play with the Simon Carabiner for 15 seconds. | Play Simon for 15 seconds. Correctly match the lights and sounds. | The image detection capabilities of the Pixy Cam will allow the APS to identify the Simon Carabiner, with the ability to store and identify up to seven (7) different objects. |
| 4.2.3 | The APS shall rotate one (1) row of the Rubik’s Cube 180 degrees. | Twist one row 180 degrees on the Rubik’s Cube. | The image detection capabilities of the Pixy Cam will allow the APS to identify the Rubik’s Cube. |
| 4.2.8 | The APS shall pick up one (1) playing card from the stack of cards. | Pick up one card from the deck and hold it to cross the finish line. | The image detection capabilities of the Pixy Cam will allow the APS to identify a playing card. |

Table 32. Requirements traceability for the sensors

## Motors

Table 33 contains the requirements related to the motor and how each requirement will be fulfilled.

|  |  |  |  |
| --- | --- | --- | --- |
| **ID** | **Requirement Text** | **SHC Rules Traceability** | **Fulfillment** |
| 4.1.4 | The APS shall start moving when the red LED powers off. | Once the signal in shut off the timer is started and the vehicle will have a maximum of five minutes navigate and play each of the games. | The motors chosen have a stall torque of 98.01 Ncm each, providing the necessary torque needed to move the APS. |
| 4.1.6 | The APS shall remain within the playing board. | The competition round will end if any part of the robot leaves the playing board. | The sensor data received will be used to control the speed of the wheels to respond to deviations from the line. |
| 4.1.8 | The APS shall stop moving once the finish line is crossed. | The competition round will end when the robot crosses the finish line. | The sensor data received will be used to stop the APS when the finish line is crossed. |

Table 33. Requirements traceability for the motors

## Claw

Table 34 contains the requirements related to the arm and how each requirement will be fulfilled.

|  |  |  |  |
| --- | --- | --- | --- |
| **ID** | **Requirement Text** | **SHC Rules Traceability** | **Fulfillment** |
| 4.2.1 | The APS shall press the middle button on the Simon Carabiner to start playing. | The timer starts and points are earned when the robot presses the center button on Simon. | The AX-12 Dual Robotic Gripper will close completely to push the middle button on the Simon Carabiner. |
| 4.2.2 | The APS shall play with the Simon Carabiner for 15 seconds. | Play Simon for 15 seconds. | The sensor data received will be used to identify the correct button to push on the Simon Carabiner. The AX-12 Dual Robotic Gripper will close completely to fulfill this requirement. |
| 4.2.3 | The APS shall rotate one (1) row of the Rubik’s Cube 180 degrees. | Twist one row 180 degrees on the Rubik's Cube. | The AX-12 Dual Robotic Gripper has 6 DOF allowing it to rotate the row 180 degrees. |
| 4.2.6 | The APS shall draw “IEEE” on the Etch-a-Sketch using the knobs located on the Etch-a-Sketch. | Draw “IEEE” on the Etch-a-Sketch. | The AX-12 Dual Robotic Gripper will clamp to one knob at a time to fulfill this requirement. |
| 4.2.8 | The APS shall pick up one (1) playing card from the stack of cards. | Pick up one card from the deck. | The AX-12 Dual Robotic Gripper has 6 DOF allowing it to fulfill this requirement. |

Table 34. Requirements traceability for the claw

## Frame

Table 35 contains the requirements related to the frame and how each requirement will be fulfilled

|  |  |  |  |
| --- | --- | --- | --- |
| **ID** | **Requirement Text** | **SHC Rules Traceability** | **Fulfillment** |
| 5.2/5.3 | The APS shall fit within a 1 ft. x 1 ft. x 1 ft. area before and after the competition begins. | The vehicle must fit in a 1 ft. x 1 ft. square and may not be taller than 1 ft. | The frame will be constructed in one piece within the size parameters specified. |

Table 35. Requirements traceability for the frame

## Battery

Table 36 contains the requirements related to the battery and how each requirement will be fulfilled.

|  |  |  |  |
| --- | --- | --- | --- |
| **ID** | **Requirement Text** | **SHC Rules Traceability** | **Fulfillment** |
| 4.1.1 | The APS shall receive power from an independent, on-board, battery. | It must be self-propelled, autonomous and may not be remotely controlled in any manner. | The specifications for the T2200.3S.25 battery specify that the device outputs a voltage of 11.1 V, allowing it to fulfill this requirement. |

Table 36. Requirements traceability for the batteries

# Risk Analysis

Each component has a certain amount of risk associated with the regular use of the APS. This section details some of the risks associated with each component used as part of the APS. The quantitative value of each risk was determined by personal experience and research of each component. The chance that the risk could occur is rated in a range of one to nine. One is the least likely for that risk to occur and nine being the most likely to occur. The severity of each is risk is rated in the same scale of one to nine; one being the least severe and nine is the most severe.

Multiple components are at risk for physical damage to each component and the possibility of pieces falling off the APS. Tools will be kept available during operation of the APS. The team will perform maintenance on the APS as required to keep it in physical shape for performance. Extra hardware, bolts, nuts, and screws will be purchased and kept available for maintenance on the APS.

## Microcontroller

Most issues with the microcontroller become massive problems as the microcontroller controls the APS and its abilities to perform tasks. The team will perform functional tests of the APS prior to its operation alleviate risks to the APS and its components. Table 37 details the risks associated with the microcontrollers.

|  |  |  |  |
| --- | --- | --- | --- |
| **Risk** | **Probability** | **Severity** | **Risk Mitigation** |
| Microcontroller fails | 3 | 9 | Functional tests will be performed before each use. |
| Microcontroller fails to start | 3 | 9 | The team will perform a visual inspection of the connections to the microcontroller. |
| Microcontroller overheats | 4 | 9 | A visual inspection will be performed to verify if the microcontroller is still useable. Connections and the battery will be inspected. |

Table 37. Risks and alleviations associated with the microcontrollers

## Sensors

Sensors function as the APS input sources. Without the APS being able to detect objects around it the APS would be unable to complete the tasks. The team will purchase extra sensors, when the option is available, to mitigate the risk and keep them available when the APS operates. The team will perform visual inspections of the sensors after each use of the APS. Table 38 details the risks associated with the sensors.

|  |  |  |  |
| --- | --- | --- | --- |
| **Risk** | **Probability** | **Severity** | **Risk Mitigation** |
| Sensor fails to start | 3 | 9 | Perform visual inspection on the connections to the sensor. Functional tests will be performed before each use. Extra sensors will be purchased and kept available. |
| Sensor gives APS false readings | 5 | 8 | Some issues will not give a visual identification of a problem and the team will have to troubleshoot if the APS performs in a random fashion. |

Table 38. Risks and alleviations associated with the sensors

## Motors

There will be four motors on the APS. Each motor will be attached to a wheel and will provide motion to the APS. Should there be issues with the motors the APS will become a stationary robot instead of an autonomous robot. The team shall perform a visual inspection on the motors prior to the use of the APS. Table 39 details the risks associated with the motors.

|  |  |  |  |
| --- | --- | --- | --- |
| **Risk** | **Probability** | **Severity** | **Risk Mitigation** |
| Motor burns out | 5 | 9 | Visual inspections will be performed after each use of the APS. Extra motors will be purchased and kept available. |
| Motor skips a step | 6 | 8 | Encoders will be used to mitigate this risk. Having feedback from each wheel and motor will give the APS proper control over its movements. |

Table 39. Risks and alleviations associated with the motors

## Claw

The APS utilizes one claw component to perform tasks. The team shall perform visual inspections on the claw prior to each use of the APS. The team will have an extra claw available as a back-up option. Table 40 details the risks associated with the claw.

|  |  |  |  |
| --- | --- | --- | --- |
| **Risk** | **Probability** | **Severity** | **Risk Mitigation** |
| Claw falling off | 3 | 9 | Maintenance will be performed as necessary. Visual inspections will be performed after each use of the APS. The claw will be replaced if the original is no longer able to function. |
| Damage to claw | 4 | 8 | Visual inspections will be performed after each use of the APS. Maintenance will be performed as necessary. |

Table 40. Risks and alleviations associated with the claw

## Wheels

The wheels provide support and movement capability to the APS. The risks associated with the wheels could cause it to become stationary. Visual inspections shall be performed after each use of the APS to identify any issues with the physical state of the wheels. Table 41 details the risks associated with the wheels.

|  |  |  |  |
| --- | --- | --- | --- |
| **Risk** | **Probability** | **Severity** | **Risk Mitigation** |
| Damage to the wheels | 5 | 8 | Wear and tear will occur as the APS is continually used. Visual inspections will be performed after each use of the APS. |
| Loss of a wheel | 4 | 9 | Extra wheels will be purchased and kept available. |
| Loss of a roller | 3 | 9 | Extra hardware will be purchased and kept available. |

Table 41. Risks and alleviations associated with the wheels

## Frame

The frame provides structure and support for the APS. Visual inspections shall be performed before and after each use of the APS. Table 42 details the risks associated with the frames.

|  |  |  |  |
| --- | --- | --- | --- |
| **Risk** | **Probability** | **Severity** | **Risk Mitigation** |
| Frame falling apart | 3 | 9 | Equipment will be kept available to perform maintenance as required. |
| Bolts falling off | 5 | 7 | Extra hardware will be purchased and kept available. |

Table 42. Risks and alleviations associated with the frame

## Battery

The battery will be a lithium-ion polymer battery and this provides risks to the APS. The lithium-ion battery is fragile and must be kept protected. The lithium-ion polymer battery is more sturdy and safer and its use will lower some of the risks associated with batteries. Table 43 details the risks associated with the battery.

|  |  |  |  |
| --- | --- | --- | --- |
| **Risk** | **Probability** | **Severity** | **Risk Mitigation** |
| Battery unable to hold charge | 3 | 6 | Ensure that the battery is charged in the correct manner. The team shall remove the battery from the charger when the charger indicates that it is done charging. |
| Battery catches fire | 2 | 9 | The team will perform visual inspections on the battery after each use. The team will only use proper safety precautions to mitigate damaging the battery. |

Table 43. Risks and alleviations associated with the battery

# Total System Budget

Table 44 details the total system budget required for the APS. The items in this table were determined by the decision matrix for the different components listed above.

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| **Component** | **Item** | **Item ID** | **Vendor** | **Unit Cost** | **Quantity** | **Cost** |
| Microcontroller | UDOO Quad | UDOO Quad | Udoo | $135.00 | 1 | $135.00 |
| SD Card | Kingston 8 GB microSDHC Class 4 Flash Memory Card SDC4/8GB | B00200K1TS | Amazon | $5.93 | 1 | $5.93 |
| Sensor | Pixy Cam | B00IUYUA80 | Amazon | $0.00 | 1 | $0 .00 |
| Motor | Precision Gearmotor | ROB-12497 | Sparkfun | $34.95 | 4 | $139.80 |
| Claw | AX-12 Dual Robotic Gripper | AX12DUAL\_GRIP | CrustCrawler | $69.00 | 1 | $69.00 |
| Wheel | Vex Robotics Omni (4 in.) | 217-2584 | Amazon | $24.99 | 2 | $49.98 |
| Battery | Turnigy 2200mAh 3S 30C Lipo Pack | T2200.3S.30 | Hobbyking | $13.50 | 1 | $13.50 |
|  |  |  | Total |  |  | $ 413.21 |

Table 44. Total system budget breakdown of APS

# Appendix A: Glossary

|  |  |  |
| --- | --- | --- |
| **Entry** | **Definition** | **Aliases** |
| \* | At any time throughout a use case. |  |
| Autonomous | Behavior independent of any outside commands or authority. Moves and performs tasks by itself without human interaction past powering the APS on. |  |
| Edges | The boundaries of the playing board. |  |
| Error Margin | The range of suboptimal data for a specific set of data. |  |
| Etch-a-Sketch | Small, travel version of the toy, Etch-a-Sketch.  By: Ohio Art – “R” Web# 636061, SKU: FD79DD3F, UPC/EAN/ISBN: 026511051508 [1]. |  |
| Finish Line | A line signifying the end of the course. |  |
| Game Station | White box, 1 ft. x 1 ft. in size, on the playing boards where the objects are sitting. |  |
| Holonomic | Freedom of movement in three axes. |  |
| Line | White lines painted on the playing board defined by painter’s tape.  Scotch Blue 0.94 in. x 60 yds. Painter’s Tape; Home depot: Model# 2090-1J Store SKU # 958999 [1]. |  |
| Middle Button | On the Simon Carabiner, there are three (3) round buttons that control the game setting, the round button in the middle is referred to as the middle button. |  |
| Navigational System | A subsystem controlling direction, speed, and maneuvering of the APS. |  |
| Object | The game as per IEEE SoutheastCon 2015 Hardware Competition rules [1]. |  |
| One Playing Card | A single card from the standard 52-card deck. |  |
| Operational System | A subsystem controlling all functions related with the interaction of the APS with each of the objects. |  |
| Pattern | The random sequence of lights to be repeated by pressing the corresponding buttons on the Simon Carabiner. |  |
| Play Simon Says | Game that challenges the user to repeat a pattern of flashing lights and sounds using the Simon Carabiner. |  |
| Playing Board | A 5/8 in. x 4 ft. x 8 ft. sanded pine plywood surface as defined by IEEE SoutheastCon 2015 Hardware Competition rules [1]. |  |
| Position | A location within the playing board. |  |
| Power Off | A state in which no current or voltage is being supplied to the system. |  |
| Power On | A state in which current and voltage is being supplied to the system. |  |
| Real-Time events | Any event that requires a system response bound by time. |  |
| Rubik’s Cube | “R” Web# 374846, SKU: DAD09D9E, UPC/EAN/ISBN: 714043050273 [1]. |  |
| Sensory System | A complex collection of input/output (I/O) devices. |  |
| Simon Carabiner | Small, travel version of the game Simon Says.  “R” Web# 351215, SKU: 226CE810, UPC/EAN/ISBN: 014397018500 [1]. |  |
| Stack of Cards | Multiple playing cards stacked on top of each other from the standard 52-card deck. |  |
| Standard 52-Card Deck | Toys “R” Us# (TBD) [1]. |  |
| System | A collection of parts that make up one (1) single unit. |  |
| Task | Specified interaction mandated by rules defined by IEEE SoutheastCon 2015 Hardware Competition [1]. |  |
| Two-Man Lift Rule | 50 pounds or more must be carried by two (2) people as per the Occupational Safety and Health Administration (OSHA) materials handling regulations [3]. |  |

Table 45. Listing of terms and definitions used throughout this document

# Acronyms & Abbreviations

|  |  |
| --- | --- |
| **Entry** | **Expanded Phrase** |
| APS | Autonomous Panda System |
| CPI | Cycles per Instruction |
| DOF | Degrees of Freedom |
| FPS | Frames per Second |
| FTFP | Funky Town Fancy Pandas |
| GPIO | General-Purpose Input/output |
| ID | Identification |
| IDE | Integrated development environment |
| IEEE | [The] Institute of Electrical and Electronics Engineers |
| LED | Light-emitted Diode |
| MIPS | Millions of Instructions per Second |
| OS | Operating System |
| OSHA | Occupational Safety and Health Administration |
| RAM | Random Access Memory |
| RC | Remote Control |
| RPM | Revolutions per Minute |
| SD | Secure Data |
| SHC | SoutheastCon 2015 Hardware Competition |
| SRS | System Requirement Specification |

Table 46. The acronyms and abbreviations used throughout this budget proposal

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