

	Subsystems	Writing	Communication	Locomotion	Localization	SDP	Mechanical Structure
Functional Requirements	FR1: Omnidirectional Motion			X			
	FR2: Autonomous			X	X	X	
	FR3: Localize Globally and Locally				X		
	FR4: Within Bounds			X	X		
	FR5: Insert Tool	X					
	FR6: Remove Tool	X					
	FR7: Replace Tool	X					
	FR8: Coordination					X	
	FR9: Drive Control			X			
	FR10: Turn on/off Tool	X					
	FR11: Input Plan		X			X	
	FR12: Know Progress		X		X	X	
	FR13: Kill Switch	X	X	X			
	FR14: User Interface		X			X	
Nonfunctional Requirements	NFR1: Documentation	X	X	X	X	X	X
	NFR2: Error Handling	X	X	X	X	X	X
	NFR3: Weight Restriction						X
	NFR4: Size Restriction						X
	NFR5: Efficiency					X	
	NFR6: Quality	X		X	X		
	NFR7: Battery Power	X		X			
	NFR8: Reliability	X	X	X	X	X	X
	NFR9: Reliable Communication		X				
	NFR10: Budget						X
	NFR11: Safe			X	X	X	X
	NFR12: Positional Accuracy			X	X		
	NFR13: Rotational Accuracy			X	X		
	NFR14: Tool Switching Duration	X					X