Meeting Minutes 19/10/2022

In attendance: Dom, James, John, Saad.

Sorted out role assignment and commenced individual research stage.

**Why has this project come about?**

The problem has come about due to a need for automation of sorting of through hole resistors in electronics.

The process of sorting a mixed-up bag of through hole resistors is slow and cumbersome by hand and could easily be replaced by automation.

**Goals and aims**

Have a mixed bag of through hole resistors and sort them into individual boxes. The robot arm must be trainable to work in any environment.

**Problems to be solved**

Picking up resistors from flat surface (re design of pincer/gripper) in specific area.

Measuring the value of the resistor.

Placing the resistor in a pot specific to its value.

Kinematic calculations.

**Team Structure and responsibility**

Dom – Project Manager, 3D Assistance.

John - 3D Design manager.

Saad – Algorithmic and mathematical.

James – Electronic and Programming.

Work Breakdown Structure

**Work to be done for next meeting**

James – Embedded system options.

Saad – Kinematic Algorithms.

Dom – Work Breakdown flow chart, research grippers, kinematics and familiarisation of robot.

John - Gripper designs and 3d, general familiarisation with arm structure.