SDP Performance Review Report 1

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1   Summary

Building on Motiejus's code, the basis of the line tracking functionality, I tried to improve the steadiness and smoothness of its movement, and to prevent over-turns and wall collisions. I helped set up Bluetooth and integrated online code to send messages to the device at runtime, to simulate the robot's responses to the vision system. I also helped with builds of the robot.

2   High Points

- Adding code to stop the robot after a full circuit and to decide on its direction of travel based on its angle of boundary intersection

- Helping organise meet-up times and contributing ideas

3   Areas to improve

- Need to write more code and acquire a deeper understanding of how each of the components work, particularly vision and communications, and how they can each be integrated

4   Recommendations

- I suggest that I receive a 3.5 or a 4.

- I recommend that Mark is awarded a 5 because he has put a lot of time and effort into team coordination, initial code and re-factoring, repository set-up and robot design,

- I also suggest Paul receives a 4 because he has added a lot of code for the vision system and it seems to be working quite well.