Team 3 Consolidation Report

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Structure

The following modules were consolidated on the bases of (1)**Completness** of functionality. (2)The **approach** to the underlying problem (3)**Implementation** (simple and understandable code).

1. Omni Velocity Controller
2. Wallfollower
3. Bug Brain

Omni Velocity Controller

Completeness:

Task	**Ali**	**Morillo**
Vehicle drives in a straight line to goal	Yes	Curve Path
Combination of linear and angular motion	Yes	Yes
Robot decreases speed when its near the goal	Yes	based on distance(not good)

Approach:

Morillo approch achives all tasks.

Implementation:

Morillo has good documentation and understandable code.

Wall Follower

Completeness:

Task	**Ali**	**Morillo**
Robot is able to follow a straight wall	Yes	Yes
Robot can also handle convex and concave curves	No	Yes
Variable distance to wall	No	Yes
Switchable right/left wallfollowing mode	Yes	Yes

Approach:

Morillo approch achives all tasks.

Implementation:

Morillo's implementation does not fail in test scenarios.

Bug Brain

Completeness:

Task	**Ali**	**Morillo**
Avoids simple obstacles	Yes	Yes
Avoids advanced obstacles	Yes	Yes
Detects if goal is unreachable	Yes	Yes
Checks on which side of the wall the obstacle is	Yes	Yes

Approach:

Morillo's and Ali's approch achives all tasks.

Implementation:

Ali's implementation does not fail in any test scenarios and has a simpler implementation.