

October, 15-21 Weekly Report

1 Progress

- General folder structure is initialized for the Github repository in order for us to use Github more efficiently.
- Business Statement Report is finalized.
- Members started searching possible solutions for the projects.
- Started working on component. Common components are for all projects prioritized.
- Possible concepts that could be applied for the solution of the "Devices trying to extract the plan of their surroundings" project are:
 - A* Algorithm: A search algorithm that is one of the best and popular technique used in path-finding and graph traversals. This might be used to navigate the robot inside the walls.
 - Wavefront Mapping: A mapping technique that are used in robots to map-out the field they are placed in.
 - Holonomic or Non-Holonomic Motion: Holonomic motion provides the robot to move in any direction immediately. Non-Holonomic motion requires several attempts to move in any direction(like cars).
 - Bumping to objects and walls can be prevented by using sonar distance sensors.
 - Existence of an obstacle can be detected by using IR sensors.
- Possible concepts that could be applied for the solution of the "Vehicles chasing each other around a closed course with varying properties" project are:
 - Physical appearance of the vehicle should be allowing the flow of air like F1 cars.
 - The mass center should not be distributed evenly on front and back wheels as in F1 cars.
 - The main concept of the vehicle is similar to a line follower robot.
 - Besides color sensing, images can be captured with a camera for better turns. (might slow down the car, processing time)
 - Sonar sensors are to be placed on the back and front of the vehicle to obey 3 cm rule.
 - The most important task is to be able to drive the motors with high speed and sensitive to turns.



2 Plans

- Define problem, find solution methodology will be used on all project.
- Will be study on common components and basics of how to use them.
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3 Problems

- We were a little late on create problem-solve them step.
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