

PROJECT MANAGEMENT ACTIVITY & SCHEDULE BOARD					Hover for messages	
General overview of work assignment						
No	Work to be completed	Assignee				
1	Image processing	Alin				
2	RFID identification	Joanna				
3	UR10 robot actuation	Mohammed				
4	System integrations	All team members				
Schedule board						
Date of completion	Activity	Category	Result	Person		Legend
TBA	Tin metal material influence over the RFID tag when scanning	RFID identification	Scanning not possible. Metal tin shall not be used due to its metal composition	Joanna		Completed
13/03	Camera + Raspberry Pi data collection (Pi)	Image processing	Numpy array image data collected using opencv library	Alin		Due
TBA	Send robot movement messages using ROS (VM)	System integration	Canceled	Alin		Canceled
21/03	Skecthed the state machine sequence of the robotic systems	Documentation	understanding of the robotic system actions sequence	Joanna & Alin		
21/04	Research XMLRPC communication	Research		Johanna, Mohammed		
22/03	Translated the sketched state machine sequence into state machine table (sheets)	Documentation	Clear order of actions	Alin		
22/03	Added robotic system sketch (slides)	Documentation	Visual representation of the robotic system and understanding of data links	Alin		
22/03	Added simple state machine (slides)	Documentation	Initial state machine	Alin		
30/03	Detect empty tins using image processing and return XY coordinates (Pi)	Image processing	next empty tin data (xy coord, rotaion angle, dimensions available to be sent to UR10)	Alin		
31/03	Updated data layout diagra in slides (slide 7)	Documentation	Clear view towards integration	Alin		
01/04	Updated project repository documentation on GitLab	Documentation	Dcumentation available on project repository	Alin		
21/04	Camera calibration (OpenCV docs.opencv.org)	image processing	Frames are undistorted before extracting information	Alin	* save calibration and load calibration every time the program starts	
22/04	Pixel/Metters translation	image processing	empty tin data units are alligned with UR10 requirements	Alin		
27/04	Transform frames	system integration	robot moves to correct coordinates	Mohamed, Johanna		
28/04	Link UR10 send/request data	system Integration	UR10 receives tin coordinates	All team members		
21/04	Validate seal using image processing (Pi)	image processing	Tins are deemed as valid/not valid in relation to full, partial or missing coverage	Alin		
15/04	Make script run at Pi startup	General	Attempted but not succesfull	All team members		
22/04	Work object phisical representation	system integration/image recognition	facilitate px to mm conversion, facilitate integration with UR10	Alin, Mohammed		
28/04	Angle transformation. transform angle from camera output to UR10 wrist	system integration	wrist rotates correctly before opening the gripper to grab the tin	Alin		

28/04	Updated documentation	Documentation	coordinates and angle transformation for integration	Alin		
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