Meeting Minutes
Sunday, March 25 2007

Attendance: Patrick, Hamdi, Doug, Tyson
Duration: 30 mins.

Currently implemented:

- The caster wheel on the robot is to be replaced by a ball bearing wheel to improve the robot's ability to drive in a straight line, as well as pivot about a centralized axis.

- The new shipment of nodes has arrived including the Data Acquisition Board and second Base Station.

- Code for Imaging an object at the source and relaying it over the network to the base station is complete.

- Development of the project poster is underway.

- Bidirectional communication between the robot and mobile senor node using the I2C is functional.

- The group will be presenting the project accomplishments thus far in an interview with YFile on April 9th. The group is currently working on integrating all aspects of the project for the basic case of hole detection to be ready by the 9th.

Next to be implemented:

- Robot moving to a given x, y coordinate and ensuring that the movements are calibrated to specific distance – Tyson

- Localization using signal strength and distance – Patrick

- Implementation of Image transfer over the network and completion of the poster – Doug

- More complex algorithms for Hole determination using mobile robot – Hamdi