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Mechatronic Camera Operator: Final Design Report

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TRINITY UNIVERSITY

Final Design Report

ENGR-4381

4/28/2009

Mechatronic Camera Operator

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Dr. Aminian, Advisor

Abstract:

A mechatronic system is designed, constructed, and tested to aid filmmakers in the movement and control of a video camera. The system design allows for 6-DOF camera movement (movement in all three spatial directions, pan, tilt, and roll). The system is controlled by a human operator, using an implementation of a gamepad controller, and the system is battery-powered; the theoretical range of the system is therefore limited only by the onboard battery power, and the operator's ability to keep within cord-length of the system as it moves.

A misallocation of time resources resulted in an incomplete physical design, but preliminary testing indicates that the design is sound, and that mechanical specifications are sufficiently robust for a working final system. Further time and resources would be used to complete physical construction and electronic implementation, and to implement a feedback system to allow for closed-loop actuator control and the function of repeatable motion.

Executive Summary

The system should be able to move a camera through the same paths of motion that a human camera-man can move it through. Project constraints include a \$2700 budget, a vertical camera elevation range of 2-6 ft and compatability with the filming environment. Design criteria include ease of set up, performance in a flat, closed room, silent system operation, ease of model development and physical construction, ease of setup and usage, mobility precision, mobility flexibility, and speed. The final implementation of the design is battery-powered and includes human-input through a gamepad controller to control each moving part, but does not employ any robotic features that allow for autonomous operation. The system fails in this respect by lacking the feature of repeatability and the ability to remember specific paths.

Mechanically, the base of the system consists of a plywood-laden steel frame built for structural robustness and is intended to make the system bottom-heavy to prevent tipping. Attached to the frame are two high-powered DC motors, each with an 8-inch diameter wheel, and a number of castor wheels for support.

The frame is two-tiered. On the lower tier electronics are safely housed; on the upper tier a turntable is attached to the base plywood. On the turntable a vertically-oriented threaded rod is mounted with two support rods all of which are connected with flat plates on top and bottom for structural support. A platform nut with a fixed horizontal orientation on the threaded rod changes elevation when the rod is rotated. Attached to the platform nut is a camera-head; this assembly is drived by a motor and results in changes of elevation for the camera.

Electrically and electronically, the motors are controlled by PIC microcontrollers. The PICs employ pulse-width-modulation and serial communication to control the different motors, and must communicate with each other to properly distribute commands from the PS2 controller. Implementing communication between the PICs is not completed and thus the final system is incomplete. Independently, each of the electronic subsystems works properly, with the exception of the portion that actuates the motor that turns the turntable.

Because the system is incomplete, limited testing has been performed. Mechanically, each system component works properly and exhibits structural soundness. Electronically, no failures are observed, but some components are incomplete. The threaded-rod motor makes use of the same microcontroller code as the wheel motors, so theoretically only a small barrier remains to make it functional. Additionally, finalizing PIC functionality to enable communication between chips should only require enabling built-in functionality and proper configuration, so this is also only a small barrier.

If further time and resources were allocated, they would be used to complete physical construction and electronic implementation, and to implement a feedback system to allow for closed-loop actuator control and the function of repeatable motion. There is every indication at this point that the design as it stands would be effective if completed.

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1 Introduction

The greatest art does not feel like art, but simply a natural extension of the human experience. A film is most powerful when it feels most vivid, and special effects and effective use of camera control are tools that have been used towards this end since the advent of film-making. The Robotic Camera Operator group is working in this subset of the film industry: precise camera control, and by application of that control, special effects.

Creative expression drives film-making however too often the creative expression of filmmakers is stifled by the limited feasibility of the camera shots that they can use. There are often time, cost, physical, and human limitations that make certain shots out of reach for a particular film. The ultimate goal of this project is to improve the tools available to the filmmaker in order to allow for improved expression of ideas, much like expanding the palate of a painter. Additionally, our final system should allow such shots to be made with a smaller investment of time, money and effort: the painter's palette is no more useful if it is larger but prohibitively expensive or inaccessible.

There are two main solutions available at this time, the first being the motion control camera. This system consists of a very large remotely operated vehicle that rides on a set of tracks, similar to those of a train. This system allows repeatability, making compositing effects possible, yet it is still extremely difficult to employ. The computer interface for the system is not intuitive, and requires a specialized operator. Additionally, the necessary setup of equipment is time consuming, and the sheer cost the equipment makes such a system impractical for many filmmakers.

Another system available is the Steadicam which is an apparatus that a camera operator wears. Using this system removes the unintentional nuances of handheld camera motion; essentially, it is a low-pass filter for motion, removing the shake of the operator's hand but leaving the intentional camera movement. This allows for camera movement limited only by the operator's agility, with no time wasted setting up track. Unfortunately, the system is still susceptible to human error, and the camera movements are not precisely repeatable (thereby removing the option of doing two-dimensional compositing).

1.1 Problem Description

The objective of the robotic camera operator is to facilitate creative freedom in filmmaking. This is done by providing a robotic system to move the video camera through a scene precisely, both in timing and position. The motion must be able to be repeated as many times as is necessary without error. This is currently not possible without using complicated setups that are not feasible at certain locations or with limited budgets. By allowing directors to sculpt the camera movement precisely, the system will allow them the ability to execute elaborate shots quickly and easily.

For this particular year of the project, a design is proposed to construct a system that will allow these functions with a lightweight (approximately three pound) consumer camcorder. For subsequent work the system is designed to be easily scalable so that a second-generation prototype could perform the same function with a much heavier digital or film camera.

1.2 Constraints

The design is bound to several constraints; it is important to identify and design within these constraints in order to design a satisfactory solution for the problem. The constraints also serve to filter out problematic solutions, and allow for the desired use of the system to be demonstrated. There are several factors to be considered in setting the constraints, such as the allotted budget and factors specific to the film industry.

1.2.1 Budget

One of the greatest and most influential constraints on the design is the budget that has been made available for the project.

A relatively small amount of money has been allotted for the project so low design costs are an important constraint. Moreover, low design costs will ensure low production costs, which is desirable if the system is ever to be sold or rented to low budget film makers. The total budget of \$2,700 includes \$1,200 from the Engineering Department and \$1,500 in grant money from IEEE Computer Society.

1.2.2 Performance

The camera should be able to film from altitudes ranging from 2 to 6 feet above the ground, as this approximates the range of the handheld camera operator that the design would ideally replace. In the event that the robotic camera operator is able to reach altitudes higher or lower, the constraint has been met and exceeded. This would simply serve to increase the value of the design as a creative tool. In the same vein it is also important that it can move a small camera similar to one a human operator would be able to control.

1.2.3 Environment

In the film industry, much of the filming is done in enclosed sound stages, which is the most probable location that the design will be used in. Therefore, it is imperative that the system be able to function in a small sound stage with a flat and level floor. For the purposes of this design, the sound stage size is minimized to 25 ft by 25 ft as the group has access to such a space which will prove helpful during testing.

1.2.4 Setup

It is important for the system to be simple to set up and use. This will allow the design to be feasible to the greatest amount of film-makers particularly those with tight time and budgetary constraints, such as small independent film makers. Moreover a system that is simple to set up and easy to use will lower production cost of the film, as less time is spent setting up each shot.

1.2.5 Sound

Finally, the proposed system must be relatively silent, as to not disturb filming. In essence the system should be inaudible to a microphone recording actors' dialogue; ideally the system would be completely silent.

1.3 Design Criteria

In order to select the most appropriate solution to the problem it is necessary to set working criteria. Although not as rigid as the constraints, the working criteria serve as a great mechanism in choosing a final solution. A more in-depth discussion of each criterion can be found below.

1.3.1 Development Requirements

It must be recognized that this project is not taking place in the professional field. The scope of project is large and the design team is relatively small with a limited amount of resources. For the greatest outcome, it is desirable to design regarding the abilities of the design team.

1.3.1.1 Model Development

This constraint deals with how simple the mathematical model of the movement of the system is to develop, which translates to a certain resource cost. A more simple mathematical model is more simple to develop, debug and implement. It will also limit the potential for human error in the design.

1.3.1.2 Construction

Construction is simply the complexity of the design and the skill it will take to build it. The simpler a system is to physically build, the more likely the prototype will be successful. This will also aid in keeping costs down if ever marketed, and the cost of employee resources needed.

1.3.2 Overall Ease of Use

To allow for film makers to easily adopt this new tool, it should not discourage an operator who may not be technically inclined. Moreover, the system should be able to withstand the environment in which it will be used.

1.3.2.1 Setup

This is based on how quickly a shot can be set up, as well as how quickly the system can be installed at a particular location. A design is considered sufficient if it has a setup time less than the comparable setup time for a track-and-dolly motion control camera; however, faster setup times are even more desirable because they result in less cost to the production. This leaves us with a target set up time of less than 1 hour^[1].

1.3.2.2 Usage

The system should be as easy to use as possibly so as to minimize the time it takes to train a new operator, and to encourage non-technically inclined filmmakers to use the system.

This is measured on the perceived complexity it will take to program a shot with the system as well as to operate the camera while filming.

1.3.2.3 Durability

If the system is to be used in film making, it will undoubtedly be subjected to an assortment of adverse conditions. Even if these conditions are avoided, it is assumed that the system is to be used for long periods of time. It is important that the system be able to withstand the stresses of continual use, otherwise, the system may break and require repair, costing both time and money.

1.3.3 Creative Freedom

The primary purpose of the design is to free a film maker to easily replicate camera movements or otherwise move a camera in a space. The fewer limitations imposed upon the abilities of the camera, the more versatile and thus desirable the design.

1.3.3.1 Precision

Precision is based on how accurately the system can follow a preprogrammed path repetitively. The more precise a design, the better it is for compositing work and other special effects processes.

1.3.3.2 Mobility

Mobility is based upon the overall need to be able to move the camera from one point to another as easily as possible. The camera should be able to move to between any two points within a 25 ft by 25 ft area, and between 2 to 6 ft in elevation. The greater the range of seemingly effortless motion and positioning, the better the mobility.

1.3.3.3 Speed

The faster the system can move a camera, the more options a film maker will have. Speed is the measure of how quickly the proposed design is able to move the camera from one point to another. The camera should be able to at least move as fast as the average cameraman could move a camera while maintaining a steady shot.

2 Design Overview

The design consists of four primary subsystems: the base, the tower, the camera head, and the control system. The base and tower are physically connected across a single interface, as are the tower and the camera head, and all three are utilized by a human operator through the control system.



Figure 1: Basic Design

2.1 Base

The function of the base is to support the weight of the entire design, and to provide a physical foundation for all subsystems. Additionally, the base provides spatial motion of the camera in two dimensions (the dimensions constrained by the ground plane) by moving the entire system across the ground.

The base is a two-tiered design; the first tier supports the batteries, both drive motors, and the control electronics, and the second tier supports the tower subsystem.

The base is framed in 1", 11-gauge square steel tubing welded together into one solid frame. Right-angles are utilized as much as possible to ease construction, except on the outside perimeter of the first tier; the perimeter of the first tier also uses 45° cuts, to implement an irregular octagonal shape. This shape is used to reduce the diagonal distance between opposing outside corners, which would otherwise require a larger surrounding free area for rotation of the base.



Figure 2: The rectangular base (a) requires a larger surrounding free area for rotation than an octagonal base (b) with equivalent length and width.

Each tier is also decked with a flat surface made of ³/₄" plywood. The plywood is bolted to the steel frame to ensure rigidity, and the addition of the plywood surfaces allows for easy installation of components with screws as well as providing lateral support to the steel frame. The deck of the first tier is made of two separate pieces that are bolted in separately; one solid piece would not be able to be removed because of the frame of the second tier, but because the division of the deck (lengthwise) is perpendicular to the supporting steel segments in the frame

(which are mounted across the width), no structural strength is sacrificed in the two-piece implementation. The top deck is a single piece of plywood, with a central hole cut to mimic the hole of the turntable (elaborated further in the next section).

The drive motors are bolted to two steel plates, each of which is welded directly to the steel frame. The placement of the plates and of the bolt holes are such that when secured, the respective axes of the two motors are aligned with the center of the base. This allows the base to rotate in place by driving the motors in opposing directions at an equivalent speed, and because of symmetry, it results in no theoretical difference in system control between driving forwards or backwards. The motors themselves (as opposed to the location of each drive axle on the attached gearbox) are consolidated to one end of the base, so that the remaining space under the second tier can more effectively be used to house the control electronics.



Figure 3: The basic construction of the base as well as location of wheel motors.

Finally, the base is mounted with a castor at either end, which is bolted to the underside of the first tier's plywood deck. The castors prevent the system from rotating about the axis created by the drive motors, and maintain both tiers parallel to the ground plane. By using a passive mechanical system of castors to accomplish this, there is no burden placed on the control system to balance the system, as there is with a Segway (which uses a similar drive system, but without the castor-balancing implementation).

2.2 Tower

The primary function of the tower is to facilitate camera movement perpendicular to the ground plane (changes in elevation), and to control camera orientation with three degrees of freedom.

The tower is bounded by two parallel discs, which are connected by an arrangement of three parallel rods (one threaded rod which turns, and two stationary support rods). The tower is connected to the second tier of the base through a turntable, which allows the entire tower to rotate independently from the base.



Figure 4: Tower Design

The turntable is the bottom of three layers which make up the lower tower disc. Above the turntable, a loop of chain is bounded by a perimeter of plywood to form the middle layer of the disc. The loop of chain is welded to a circular steel plate, which forms the top and final layer of the lower disc, and prevents the loop of chain from rotating within the plywood perimeter of the second layer. This construction is bounded together with bolts, and allows the turntable to be actuated by a motor-sprocket assembly; effectively, the bottom disc is a donut-shaped gear, with the gear teeth around the perimeter of the central hole. The chain is secured so that the inner diameter of the chain loop is approximately ¹/₄" smaller than the inner diameter of the rest of the assembly, so that the connecting sprocket can more easily connect with the chain.



Figure 5: Turn Table Assembly

The actuating motor for the turntable assembly is a drill motor which is attached to the first tier deck of the base. The motor, with a corresponding sprocket on its 7/8 inch keyed shaft, is mounted vertically within the inner perimeter of the turntable assembly and is used to actuate rotation of the turntable. The rotation of the turntable effectively is the "pan" control of the camera.

The lower disc also is the mounting location for the 450-watt elevation-control motor. A motor mount is constructed out of welded 11-gauge steel tubing, which raises the motor off the turntable high enough to allow the motor sprocket to spin freely. This sprocket is chained to a corresponding sprocket on the threaded rod on the other side of the turntable, connecting the motor with the desired target of actuation.



Figure 6: Motor Mount for Threaded Rod

The threaded rod is free to rotate along its axis, due to support from mounted bore bearings at either end of the rod, attached to the lower and upper disc assemblies. The threaded rod acts like a 5-foot-long worm gear, controlling the elevation of the attached platform nut (elaborated on further in the next section).

Additionally, two stationary support rods run in-between the lower and upper disc assemblies, and are connected at either end with threaded flanges. These support rods are intended to prevent torque on the top disc assembly, and to help distribute the weight supported by the top disc. The support rods also prevent the camera carriage from rotating about the threaded rod (which is explained in more depth in the next section).



Figure 7: Layout of Threaded Rod and Support Rods

The top disc assembly of the tower is simply a circular steel plate and a circular deck of plywood, to which is attached the bearing and both flanges corresponding to the threaded rod and both stationary rods, respectively.

2.3 Camera Head

The camera head assembly is attached to a carriage which rides a platform nut up and down the threaded rod as it turns. The carriage is a simple rectangular design made from welded segments of angle-iron; it is therefore very cheap, and very sturdy despite its low weight of only two pounds.



Figure 8: Carriage Construction

The carriage is bolted to the platform nut in four places, and has two 1" holes that allow the stationary rods to pass through the carriage; this prevents the carriage from rotating with the threaded rod (by the induced normal force against the carriage from both stationary rods), and insures that the rotation of the threaded rod results only in a change in camera elevation. The interior region of the camera carriage also serves as a supporting box in which to house the control electronics for the camera head.

The camera head is bolted in four places to the steel plate on the front of the camera carriage. The head has two servo actuators, which allow for control of the tilt and roll of the camera. The first servo ("roll") rotates a yoke which holds the second servo, and that servo ("tilt") rotates an embedded yoke that supports the camera. The entire camera head assembly,

except for the housing of the roll servo, is made of pre-cut plastic and held together with screws. The housing of the roll servo is constructed of prefabricated aluminum.

2.4 Control System

The function of the control system on the robotic camera operator is to process commands given by the user and translate them into movements of the various actuators. Commands are given to the system via the use of a gamepad borrowed from a consumer gaming system. The commands from the gamepad are interpreted and commands are passed along to the appropriate microcontrollers. These microcontrollers process the commands into the various methods of controls used by the actuators. It is a simple, open loop control system designed to provide basic functionality for the robot.

2.4.1 Construction

During the development phase of the control system, it is constructed on a breadboard that allows easy relocation and changing of components. However, once the design is finalized, a breadboard is not robust enough to construct reliable circuitry. Circuits on breadboards have a tendency to be unreliable when subjected to the vibrations associated with being on a robot. Therefore, all components are soldered to a prototyping board. This allows flexibility as components changes can still be made, while also eliminating problems with loose components caused by vibration.

2.4.2 Architecture

The architecture of the control system of the robot is a system of microcontrollers arranged in a tree structure. At the top is the master microcontroller that communicates with a gamepad using a variation of SPI (Serial Peripheral Interface). The microcontroller sends a polling command to the gamepad and the gamepad responds with a digital signal that indicates the status of all inputs. The inputs are then interpreted by the master microcontroller, and passed on to the two lower level microcontrollers via the same SPI interface used for the game pad. Each of these microcontrollers processes the commands from the master microcontroller and generates commands for their respective actuators. A schematic for the overall architecture can be seen in Figure 2.



Figure 9: The overall architecture of the control system.

2.4.3 Human Interface

There are two major components to the human interface of the robot. The first and most important is the dead man's switch. This switch is a commercial switch produced for the same purpose in the marine industry. It has a tether that attaches to the operator at one end, and a switch at the other. If the tether becomes detached from the switch at any point in time, the switch changes state. It is connected in such a way as to cut off power to the moving parts of the robot when the switch changes state. The need for this switch was decided upon when the destructive potential of the robot due to its weight and power was realized.

The second human interface device is the gamepad. This device is used to control the motions of the robot. It was chosen for three reasons. First of all, it has lots of buttons and two joysticks, allowing for many options in control of the robot, and for future expansion. Additionally, the protocol for this device is well documented ^[2] so it is not difficult to connect to the selected microcontrollers. Finally, it is a very intuitive interface to many people, which saves a considerable amount of time and money in designing an interface specific to this project.

2.4.4 Actuator Control

There are three main ways that actuators are controlled on the robot. The wheel motors and the motor for the threaded rod of the tower are controlled using commercially available motor drivers. The actuators on the camera head are standard hobby servos, and are controlled using the variation of PWM (Pulse Width Modulation) characteristic of that type of actuator. Finally, the motor that actuates the rotation of the turntable is controlled using an H-bridge and the PWM function of the microcontroller.

2.4.4.1 Wheel and Threaded Rod Driver

These drivers are designed to provide the large amount of power required for these actuators. This driver accepts input via a 7-bit, even parity serial (RS232) signal. The difficulty in setting up communications between the microcontrollers and the motor drivers drivers is that the microcontroller serial port is setup for 8 or 9 bits without parity by default, and no option for 7-bit communication. In order to achieve 7-bit serial communications with a microcontroller that defaults to 8-bit communication, some knowledge of serial communications and binary numbers is required. The most significant bit of the 8-bit serial signal is always zero when sending data between 0 and 127, or 0x00 and 0x7F in hexadecimal. Therefore, 7-bit serial communication can be used for data in this range. The addition of the parity bit to the 7-bit signal makes the sum of the number of bits for each piece of data sent 8-bits. The parity bit takes the place of the most significant bit in what would ordinarily be the 8-bit signal. This is done by counting the number of 1's in the transmission, and setting the parity bit (formerly the most significant bit of the 8 bit signal) to high if they are odd, or low if they are even. This effectively makes every transmission have an even number of bits. This is the only real change needed to send a 7-bit signal.

The commands sent to the motor drivers are sent as follows. First, a '!' character is sent, alerting the controller that a new command is coming. The next character is either an 'A' or a 'B'. This informs the controller which channel the command is for. If the character is lowercase, that channel is to be reversed. Next, two characters that are the hexadecimal representation of an unsigned 8-bit number that indicate the value the channel should be run at are sent. Finally, an ASCII carriage return character is sent, signaling the end of the command.

The motor drivers have several different modes of operation. In the case of the driver for the threaded rod motor, it only has a single channel and has none of the more advanced modes. The driver for the wheels, on the other hand, has two modes of operation that are relevant to this system. The first mode is that each channel (and therefore each wheel) is controlled independently. This is useful on a system that does not steer using a difference of speed between the wheels. The second mode is mixed mode, where the controller controls the two channels together. In this mode, channel A specifies the speed of both wheels, and channel B specifies the difference in speed between them. This makes it easy to implement steering on a system such as this one, and is the mode used in this design.

2.4.4.2 Servo PWM

The servos that actuate the camera head are controlled using a standard RC servo signal. This signal is a form of PWM, although it operates at a much slower frequency than the PWM used for an ordinary motor. This PWM generates a signal with a 20 millisecond period, and varies the high time of the signal between about 1 millisecond and 2 milliseconds. The high time of the signal is what tells the servo what position it should go to.

In order to produce a PWM signal appropriate for a hobby servo, the period of the signal is divided up into ticks. The length of each tick is determined by the clock frequency of the microcontroller. Next, the necessary pulse width is determined by correlating the length of the pulse to a number between 0 and 255 that corresponds to the desired position of the servo. Upon completion of that calculation, the output to the servo is set high and a timer is set to count off the number of ticks for the high portion of the signal. Once this counter reaches its highest possible value, it sets an interrupt. The handler for this interrupt calculates the number of ticks for the signal, and sets the output low and then sets the timer again.

2.4.4.3 Turntable PWM

The motor for the turntable is controlled using the PWM system built into the microcontroller. This system generates a PWM signal of desired frequency and duty cycle, which is then fed into an h-bridge, which provides the power necessary to drive the motor. The speed of the motor is controlled by varying the duty cycle of the PWM signal outputted the microcontroller. The larger the duty cycle, the more power the motor gets and the faster it spins.

2.4.5 Software

All software used on the microcontrollers is written in C. The compiler used for compilation of the C code is the Lite version of Hi Tech C.

3 Testing Methods

In order to determine how successful the design is, it needs to be subjected to a series of test that can determine its limits of operation, and prove that the system itself works.

3.1 Mechanical System

The testing of the mechanical system will ensure that everything moves as it should, when it should, and that the physical aspects of the system will not fail during operation.

3.1.1 Wheel and Threaded Rod Motors and Driver

The motor driver is supplied with power; the software package supplied with the driver is used to configure it. This software has ready-made testing features and even monitors and plots the magnitudes of the outputs to the two channels. To test the driver, it is connected to the serial port of the computer and observations are made to ensure that each channel achieves 90% of the maximum speed.

Before the motors themselves are mounted to the frame, it is important to check that they can be driven properly by voltages within their rated range, and more importantly, that the two motors produce the same results. A brief test is performed on each motor to ensure that between zero and the 90% of the maximum rated speed it does not exhibit unusual behavior such as overheating. This test is performed with a wheel attached to make the rotational behavior more visible. This test's success is dependent on the judgment of the tester and is essentially a check for defective behavior. The same tests are performed for the threaded-rod motor, as the driver is the same but one-channel.

3.1.2 Strength of the Base

When the motors and wheels are attached to the base, but before the tower is mounted, a test is performed to ensure that the base can support the weight of the tower. Weights in the amount of 200% of the tower weight are placed on the base and each motor is driven with a voltage that increases from zero until the entire system is moving at a swift walking pace, between 4 mph. This test is considered a success if no excessive stresses are apparent on the

frame itself, or on the connections between the motor and frame, and if the motors can move the system at the desired speed.

3.1.3 Driver for Turntable motor

The driver is supplied with power and a test command signal is given to it. The pulse width modulated (PWM) output of the driver is viewed on an oscilloscope and compared with the expected values. The signals checked are full reverse, half reverse, stopped, half forward, and full forward, to verify that the PWM output operates linearly with duty cycles of within 5% of their expected values, and to verify that the polarity is reversed between forwards and backwards.

3.1.4 Turntable System

The motor and driver are connected to the turntable through a sprocket. The turntable has the tower attached to the top and the camera carriage is positioned at its maximum height. On the carriage, extra weight is placed to verify that the rotation does not cause the robot to tip. The motor's speed is slowly increased to verify that the turntable does indeed rotate, and to find the maximum operating speed to ensure a stable rotation without tipping. The tester, from a standstill, and using the maximum operating speed, moves the tower one full rotation. If this happens in less than 4 seconds, the system is a success.

3.2 Control System

The control system is tested from the bottom up, one subsystem at a time. As subsystems are verified to be working, they are combined and then tested as a complete unit. This method allows easier debugging by isolating problems to as few candidates as possible.

3.2.1 Servos

In order to test the function of the servos, the microcontroller is programmed to output signals that move the servos through a specific and easy to watch series of motions. The servos are then connected to the microcontroller and the result is observed. If the observed movements are the desired movements, then servo control is working correctly.

3.2.2 Wheels and Threaded Rod

The wheels and the threaded rod are using controllers from the same family by the same manufacturer; the controllers have the same operation and can be tested using the same methods. The testing of the wheel related software is primarily a test of the communications between the microcontroller and motor drivers. First, the microcontroller is programmed to output a valid set of commands to its serial port. The microcontroller is then connected to a computer running the RoboRun software, which is designed to communicate directly with the motor drivers. It uses the same protocol as the motor driver, so it is a good place to check whether or not the commands being sent by the microcontroller are valid or not. The RoboRun software includes a serial console that prints out all commands that are received. If the microcontroller is sending the correct commands using the correct communication method, they are printed in the console. If the wrong commands are being sent (i.e., 7-bit serial is not working properly), the commands show as garbage in the serial console. Once the commands have been verified as correct, the microcontroller can then be connected to the motor drivers. The microcontroller is programmed to output a series of commands that command the motors to move in a specific manner that is easy to watch. If the movements of the wheel motors match those being commanded, the test is successful.

3.2.3 Turntable

The function of the PWM software is tested by connecting the PWM output of the microcontroller to an oscilloscope and measuring the frequency and duty cycle of the outputted signal. If this signal is the one that is desired, and the duty cycle varies correctly when commands are sent to the microcontroller, the turntable subsystem is in working condition.

3.2.4 Gamepad

The testing of the Gamepad is accomplished using a microcontroller, a personal computer, and a program called PuTTY. For this system, the microcontroller is programmed to read data from the gamepad, and then output the state of each button over RS232 serial to the computer. This generates output in the PuTTY program that can be easily read by the person doing the test. When all buttons are reading correctly and the readings of the joysticks respond in a reasonable manner, the gamepad is working correctly.

3.2.5 Microcontroller Communication

The communication between the various microcontrollers is tested in a fairly simple way. First, the master microcontroller is programmed to take input from two switches and then send commands to the two slave microcontrollers. Each of these microcontrollers is setup with an LED light on an output and change its state depending on commands sent from the master controller. When communications are working correctly, operating the two switches connected to the master microcontroller will change the states of the LED's connected to the slaves. When this is behaving as specified, microcontroller communication is said to be working.

4 Testing Results

An analysis of the testing results will determine how successful the design is. The constraint concerning the schedule resulting in a lack of applicable testing results. The system was unable to be completed in accordance to the design specifications thus complete testing was unable to be performed.

4.1 Wheel Motor Testing

The wheel motor driver achieves the desired speeds for each channel, which is verified qualitatively by observation and also quantitatively using the driver software package. The wheel motors themselves are observed to function properly and are not defective. The servos on the camera-head function properly out-of-box, and are controllable as desired through their PIC.

4.2 Durability Testing

Being made from 11-gauge square steel tubing, the frame of the robot is much stronger than required and an excessive weight in the amount of 300 lbs is placed on the frame, causing no visible deformities, and without affecting movement.

4.3 Other Motor Testing

Due to the turntable motor assembly being incomplete, neither the motor nor the driver are tested. This is also the case for the threaded-rod motor.

4.4 Control System Testing

The control system is not completely constructed due to time constraints, and cannot be completely tested. Of the components that are complete, the servos move exactly as they should when commanded to, and they do not move when they are not commanded to. The operation of the servo control is successful. The wheel system works correctly. It operates in mixed mode, and the speeds of the motors vary correctly with the commands sent to them. The motor and driver for the threaded rod are not tested, and the turntable system is not tested.

4.5 Game Pad Testing

The outputs of the game pad are correct, when a button is pressed on the pad, the correct button is shown as being pressed on the output to the computer. The joysticks also report values, but they do not work as expected. First, when the user releases the joysticks and they physically return to their center positions, it is not reflected in the output. Instead, the values of their last position are reported. The second issue is that the position of each joystick reported by the gamepad is not linear, which makes them undesirable for the intended use. The SPI communication of the microcontrollers is not complete, and so it is not tested.

5 Conclusions

Though the prototype was never fully completed, it was possible to arrive at some conclusions about the design and how it stacked up against what we planned to create at the beginning of the year, as well as how the project itself was managed.

5.1 Performance against constraints and criteria

Without the completion of the control system, it is difficult to acuratly gauge how well the design stands up to our criteria, however some aspects of the design can still be at least partially evaluated

5.1.1 Performance

Mechanically the system should meet the constraint of altitude range; the lower height of the tower is 2 feet above the ground and the highest point is at approximately 6 feet above the ground. The pan, tilt, roll, and rotation mechanisms of the system serve to simulate the movement a human operating a hand-held camera.

5.1.2 Sound

Though the whole system was never operated together, the individual motors had all been run independent of the system. Each of these motors made a significant amount of noise when they were being actuated. As there was no plan to put any form of sound dampening in place, it can be assumed that it would be equally as loud in the finished product. However, given the correct sound recording set up, it still should be quiet enough to film with under most conditions.

5.1.3 Set up

Assuming the battery is charged, the only setup required for a shot is to mount the camera, turn the system on and wait for the software to load. This is significantly shorter than most other systems and defiantly would be expected to be shorter than the one hour stated in the design criteria.

5.1.4 Mobility

As far as the mechanical design goes, there are no limiting factors that could hamper the system's ability to successfully and easily navigate a 25 by 25 foot sound stage, with the camera between 2 and 6 feet. However as this was never actually attempted due to an incomplete control system, this cannot be verified.

5.1.5 Durability

The entire system had been disassembled and reassembled completely on numerous occasions with no adverse effects. The only component to fail was the turntable motor, however this was due to a deviation from the original design that was forced by scheduling issues, and would not be expected to have occurred if it was assembled properly.

5.1.6 Usage, Precision, and Speed

These remaining criteria cannot be adequately compared to the system without completion of the control system. Upon completion of the control system the testing of these remaining criteria can be performed and the final system performance assessed more accurately.

5.2 Budget and Schedule

The total purchases fell within the allotted budget. Out of the \$2700.00 allotted to the project, purchases for the Robotic Camera Operator totaled \$2660.50. The design's most expensive purchases were the motors, the threaded rod and platform nut, and the motor controllers.

Time was perhaps the greatest setback for the group. Each task required a lot more time than was allotted in the original schedule. The time necessary for programming of the PICs was greatly underestimated; becoming familiar with the PICs and the PIC programming language proved more difficult than expected for the simple reason that no one had previous experience with them. Mis-orders and lost packages added further to the difficulties with scheduling.

5.3 Recommendations

If this project was to be continued, it would be desirable to complete the control system so that an operator could, using open loop control, easily navigate the robot around. Once this is completed, the encoders could be added to the system as well as some memory so that a teach and repeat system could be easily implemented.

6 Bibliography

- [1] <u>Motion Control Rigs, Cameras, Heads, Platforms, Pan Tilt Heads, Cranes, and the Home of Milo</u>. 26 Apr. 2009 <<u>http://www.mrmoco.com/></u>.
- [2] "Playstation controller interfacing -." <u>Hack a Day</u>. 26 Apr. 2009 http://hackaday.com/2008/03/07/playstation-controller-interfacing/.

A Control System Schematics

This section contains schematics for the control system. It should be noted that the items depicted in Figure C-1 are also included with all of the other microcontrollers, but are not shown on those schematics.



Figure A-1: Schematic for items attached to all microcontrollers.



Figure A-2: This schematic depicts the electrical setup of the Camera Head microcontroller.



Figure A-3: This schematic depicts the electrical setup of the Master microcontroller.



Figure A-4: This schematic depicts the electrical setup of the Tower Control microcontroller.



Figure A-5: This schematic depicts the electrical setup of the Wheel microcontroller.

B Code

This Appendix contains all of the C code for the system. It is to be compiled with HiTech C. Additional include files have been excluded.

Code For the Master microcontroller

(also includes wheel control algorithms)

```
/*Robot Camera Operator
* Master PIC
PIC Pin Connections:
SPI:
Pin 23 - SDI Gamepad Brown, SDO pin 24 on Slave PICS
Pin 24 - SDO - Gamepad Orange, SDI Pin 23 on Slave PICS
Pin 18 - SPI Clock - Blue Gamepad, Pin 18 on slave PICS
Serial:
Pin 25 - USART TX
Pin 26 - USART RX
Slave Select Lines
Pin 33/RB0 - Gamepad - Yellow - Attention
Pin 34/RB1 - TowerPIC Pin 7
Pin 35/RB2 - WheelPIC Pin 7
Pin 36/RB3 - HeadPIC Pin 7
Other Connections:
Gamepad - Grey - vibration motor power (7.2 - 9V?)
Gamepad - black - ground
Gamepad - red - power - 3.3 V, should work at 5V as well.
Gamepad - Green - acknowledge - unused (tells the playstation that the
controller is there)
Serial Settings:
9600 Baud, N,8,1, no flow control
*/
//----- INCLUDES ----- //
#include <htc.h>
#include "main.h"
#include <stdio.h>
#include <string.h>
#include <stdlib.h>
#include "usart.h"
//#include <delay.c>
//----- DEFINES ----- //
// this is a macro shortcut (this code will replace bitrev(c) at compile
                                 Page B-1
```

time) // for reversing the bit order #define bitrev(c) c = (c & 0x0F) << 4 | (c & 0xF0) >> 4; \ c = (c & 0x33) << 2 | (c & 0xCC) >> 2; \ c = (c & 0x55) << 1 | (c & 0xAA) >> 1; //----- CONFIG ----- // //Disable Watchdog Timer //Setup High Speed Crystal Oscillator //Disable Brownout REset //Unprotect memory? ___CONFIG(WDTDIS & HS & BORDIS & UNPROTECT); //Define Crystal Frequency #ifndef _XTAL_FREQ // Unless already defined assume 4MHz system frequency // This definition is required to calibrate __delay_us() and __delay_ms() #define _XTAL_FREQ 2000000 #endif /***** Ports *****/ #define pin_GP RB0 // slave select for the gamepad RB1 // slave select for Tower PIC #define pin_T #define pin W RB2 // slave select for the Wheel PIC RB3 // slave select for Head PIC #define pin_H //----- Prototypes ----- // void Init(void); void poll_controller(void); // send and receive a byte from the controller via SPI void ps2_txrx(unsigned char data_out,unsigned char *reg_in); void putsUART(char *data); void output buttons(); void process_commands(); void transmit_instructions(unsigned char data_out, unsigned char *reg_in, unsigned char uc); //Move to Wheel PIC void sevenbitsend(unsigned char byte); void send_command(char dir, char val1, char val2); void wheel_control(); int robo_abs(int number); unsigned int bitCount(unsigned char n); void wheel_control2(); //----- Global Variables ----- // int read_buf_index =0; unsigned char print_buf[80]; unsigned char print_buf_index = 0;

```
uint8 PS2_ID, MSG;
uint8 PS2_byte1, PS2_byte2, PS2_byte3, PS2_byte4, PS2_byte5, PS2_byte6;
uint8 PS2_prev_byte1, PS2_prev_byte2, PS2_prev_byte3, PS2_prev_byte4,
PS2_prev_byte5, PS2_prev_byte6;
unsigned char PS2_pressure[12];
int RJX, RJY, LJX, LJY;
int count=0;
int LJYloc = 0 , RJXloc = 0, LJXloc = 0 , RJYloc = 0;
// ----- utility functions ----- //
void ps2_txrx(unsigned char data_out,unsigned char *reg_in){
      bitrev(data_out); //bit reverse the data
      SSPBUF = (data_out); //write the data to the outgoing buffer
     while(!BF); //wait for incoming data to fill the incoming buffer
      *reg_in = SSPBUF; //write incoming data to *reg_in
      //bitrev(*reg_in); //reverse the bits of reg_in
}
void print_ascii_r(unsigned char t, unsigned char t2)
{
      // there's not enough time to send out serial RS-232 back to the
computer
     // in between every byte, so output is stored in a buffer until the end
     // of a packet.
     print_buf[2*print_buf_index] = t;
     print_buf[2*print_buf_index+1] = t2;
      if (print_buf_index < 38)</pre>
            print_buf_index++;
}
void putsUART( char *data)
{
  do
       // Transmit a byte
  {
   putch(*data);
  } while( *data++ );
}
void
main(void)
{
      Init(); //initialize communications, gamepad, etc.
     while(1)
      {
                                    //Get states of controls from controller
            poll_controller();
            //process_commands(); //decide where to send which, and do it
            wheel_control(); //test wheel control function, will be moved to
wheel pic
      }
}
```

```
void
Init(void)
{
      unsigned char response;
      //Setup Slave Select Line TRIS
      TRISB0=0; //Gamepad
      TRISB1=0; //Tower
      TRISB2=0; //Wheel
      TRISB3=0; //Head
      //Setup USART
      INTCON=1;
                //disable all interrupts
      init_comms(); //Initialize the USART
      //Setup SPI
      TRISC5 = 0; //Clear TRISC5 bit to enable SDO for SPI (p75)
      TRISC3 = 0; //SCK Master Mode
      TRISC4 = 1; //Slave Select enabled
      SSPSTAT = 0b0000000;
      SSPCON = 0b00110010;
      // Fosc = 20 MHz, so the SPI data rate is 312.5kHz.
      // CKP =1 (idle clock state is high, active low)
      // CKE=0
                 data is read when the clock transitions
      //from active to idle. This causes the clock
      //to start out going low, and then high mid-cycle.
      sevenbitsend('!'); //send out in seven bit serial glory.
      sevenbitsend('A');
      sevenbitsend('0');
      sevenbitsend('0');
      sevenbitsend(0x0D);
      //sevenbitsend(' ');
      /*sevenbitsend('!');
      sevenbitsend('B');
      sevenbitsend('0');
      sevenbitsend('0');
      sevenbitsend(0x0D);*/
      char hexnum[2];
      itoa(hexnum, 3, 16);
      send command('B', hexnum[0], hexnum[1]);
}
void poll_controller()
{
      unsigned char response;
      char buf[20];
      char t;
     RJX = 0;
     RJY = 0;
     LJY = 0;
     LJX = 0;
     for(int i=0; i <=100; i++)</pre>
      {
     pin_GP = 0;
                                           // pull ATT low to signal gamepad
     ps2_txrx(0x01, &response);
                                                             // send:
                                                                         Start
```

```
(0x01 LSBF (order flipped in ps2_tx)
     ps2_txrx(0x42, &PS2_ID.byte); // send: Request Data (0x42 LSBF)
     ps2_txrx(0x00, &MSG.byte);// receive gamepad ID:
                                                       should be '0x5A'
for 'ready to send'
     ps2_txrx(0x00, &PS2_byte1.byte);
                                                      // receive: 1st byte of
button states and set big (left) motor to Left arrow pressure
     ps2_txrx(0x00, &PS2_byte2.byte);
                                                     // receive: 2nd byte of
button states and turn on small (right) motor if Right arrow pressure = 0xFF
     ps2_txrx(0x00,&PS2_byte3.byte);
                                                     // receive: 3rd byte of
button states
     ps2_txrx(0x00,&PS2_byte4.byte);
                                                     // receive: 4th byte of
button states
     ps2_txrx(0x00,&PS2_byte5.byte);
                                                     // receive: 5th byte of
button states
     ps2_txrx(0x00,&PS2_byte6.byte);
                                                     // receive: 6th byte of
button states
     ps2_txrx(0x00, &PS2_pressure[0]);
     ps2 txrx(0x00, &PS2 pressure[1]);
     ps2_txrx(0x00, &PS2_pressure[2]);
     ps2_txrx(0x00, &PS2_pressure[3]);
     ps2_txrx(0x00, &PS2_pressure[4]);
     ps2_txrx(0x00, &PS2_pressure[5]);
     ps2_txrx(0x00, &PS2_pressure[6]);
     ps2_txrx(0x00, &PS2_pressure[7]);
     ps2_txrx(0x00, &PS2_pressure[8]);
     ps2_txrx(0x00, &PS2_pressure[9]);
     ps2_txrx(0x00, &PS2_pressure[10]);
     ps2_txrx(0x00, &PS2_pressure[11]);
     pin_GP = 1;
     RJX = PS2_byte3.byte-127 + RJX;
     RJY = PS2_byte4.byte-127 + RJY;
     LJX = PS2_byte5.byte-127 + LJX;
     LJY = PS2_byte6.byte-127 + LJY;
      }
     RJX = RJX/100;
     RJY = RJY/100;
     LJX = LJX/100;
     LJY = LJY/100;
}
void
output_buttons() {
      //Outputs the states of the gamepad buttons to the USART, meant to be
used
      //with PuTTY
     putch('\f');
     putch(MSG.byte);
     printf("\r RJX [%d]\n",RJX);
     printf("\r RJY [%d] \n",RJY);
```

```
printf("\r LJX [%d]\n",LJX);
      printf("\r LJY [%d]\n",LJY);
      printf("\r Select: [%d] \n", PS2_Select);
      printf("\r L3: [%d] \n",PS2_L3);
      printf("\r R3: [%d] \n",PS2_R3);
     printf("\r Start: [%d] \n",PS2_Start);
     printf("\r Up: [%d] \n",PS2_Up);
      printf("\r Right: [%d] \n",PS2_Right);
      printf("\r Down: [%d] \n",PS2_Down);
      printf("\r Left: [%d] \n",PS2_Left);
      printf("\r L2: [%d] \n",PS2_L2);
      printf("\r R2: [%d] \n",PS2_R2);
      printf("\r L1: [%d] \n",PS2_L1);
     printf("\r R1: [%d] \n",PS2_R1);
      printf("\r Triangle: [%d] \n", PS2_Triangle);
      printf("\r Circle: [%d] \n",PS2_Circle);
     printf("\r X: [%d] \n",PS2_X);
     printf("\r Square: [%d] \n",PS2_Square);
      }
void
process_commands()
{
/* The function of this function is to take the commands from the gamepad,
* and turn them into a standardized number that can be sent to each of the
individual
 * slaves
 */
unsigned char reg_in; //will contain whatever the PICS send back, which is
probably nothing
```

```
//send data to the Wheel PIC
    transmit_instructions(LJX, &reg_in, 'W');
    transmit_instructions(LJY, &reg_in, 'W');
}
```

```
void wheel_control()
{
    /*Uses Mixed Mode on the driver*/
    unsigned char chanldir, chan2dir;
    char numberValA[2];
    char numberValB[2];
    int turn_mag = 0;
```

```
int drive_mag = 0;
int turn = LJX;
int drive = LJY;
if(drive > 0)
                 //Determine direction
      chan1dir = 'a'; //Backward
else
      chanldir = 'A'; //Forward
if(turn > 0)
                        //Changes the direction
      chan2dir = 'B';
                        //Right
else
      chan2dir = 'b'; //Left
drive_mag = robo_abs(drive);
turn_mag = robo_abs(turn);
turn_mag = turn_mag / 10;
//drive_mag = drive_mag / 20;
if(drive mag > 127)
      drive_mag = 127;
if(turn_mag > 127)
      turn_mag = 127;
if(PS2_Circle == 0)
      turn_mag = 0;
if(PS2_X == 0)
      drive_mag = 0;
itoa(numberValA, drive_mag, 16); //convert to ASCII characters
if(drive_mag < 16){</pre>
      numberValA[1] = numberValA[0];
      numberValA[0] = '0';
}
itoa(numberValB, turn_mag, 16);
if(turn_mag < 16){</pre>
      numberValB[1] = numberValB[0];
      numberValB[0] = '0';
}
for(int x=0; x<=1; x++) //can't have a null character, need it to be a</pre>
{
      if(numberValA[x]==0)
            numberValA[x]='0';
      if(numberValB[x]==0)
            numberValB[x]='0';
}
send_command(chan1dir, numberValA[0], numberValA[1]);
sevenbitsend('\t');
send_command(chan2dir, numberValB[0], numberValB[1]);
sevenbitsend('\n');
```

```
Page B-7
```

0

}

```
int robo_abs(int number) {
      if(number>=0)
           return number;
      else return -1*number;
}
void wheel_control2()
{
      /*Uses Mixed Mode on the driver*/
     unsigned char chanldir, chan2dir;
      char numberValA[2];
      char numberValB[2];
     unsigned int RJXloc_mag = 0;
     unsigned int LJYloc_mag = 0;
      //if(count%1000 == 0)
      //{
            if(PS2_L1 == 0 && LJYloc < 127) //Decrease Speed
                 LJYloc = LJYloc + 1;
                                              //Do what we would do with a
joystick pointed down
            if(PS2_R1 == 0 && LJYloc > -127)//Increase Speed
                  LJYloc = LJYloc - 1;
                                              //Do what we would do with a
joystick pointed up
            if(PS2_L2 == 0 && RJXloc > -127)//Increase Turning
                 RJXloc = RJXloc - 1;
                                            //Do what we would do with a
joystick pointed left
            if(PS2_R2 == 0 && RJXloc < 127)//Decrease Turning
                  RJXloc = RJXloc + 1;
                                          //Do what we would do with a
joystick pointed right
      11
           count = 0;
      //}
      //count = count + 1;
      if( LJYloc > 0 ) //Determine
           chan1dir = 'a'; //Backward
      else
           chanldir = 'A'; //Forward
      if(RJXloc > 0 )
                             //Changes the direction
           chan2dir = 'B'; //Right
      else
            chan2dir = 'b'; //Left
      LJYloc_mag = abs(LJYloc);
     RJXloc_mag = abs(RJXloc);
      //RJXloc = RJXloc / 20;
      //LJYloc = LJYloc / 20;
      /*if(LJYloc mag > 127)
           LJYloc mag = 127;
      if(RJXloc mag > 127)
           RJXloc_mag = 127;*/
```

```
if(PS2_Circle == 0)
            RJXloc = 0;
      itoa(numberValA, LJYloc_mag, 16); //convert to ASCII characters
      if(LJYloc_mag < 16){</pre>
            numberValA[1] = numberValA[0];
            numberValA[0] = '0';
      }
      itoa(numberValB, RJXloc_mag, 16);
      if(RJXloc_mag < 16){</pre>
            numberValB[1] = numberValB[0];
            numberValB[0] = '0';
      }
      for(unsigned int x=0; x<=sizeof(numberValA); x++) //can't have a null</pre>
character, need it to be a 0
      {
            if(numberValA[x]==0)
                  numberValA[x]='0';
            if(numberValB[x]==0)
                  numberValB[x]='0';
      }
      send_command(chan1dir, numberValA[0], numberValA[1]);
      sevenbitsend('\t');
      send_command(chan2dir, numberValB[0], numberValB[1]);
      sevenbitsend(' \ );
}
void send_command(char dir, char val1, char val2) {
      sevenbitsend('!');
      sevenbitsend(dir);
      sevenbitsend(val1);
      sevenbitsend(val2);
      //Return and commit command
      sevenbitsend(0x0D);
}
void sevenbitsend(unsigned char byte)
{
      //Input: unsigned character
      //Output: Converts to 7 bit serial, even parity, sends out USART
      //Depends: bitCount();
      unsigned int check;
      check = bitCount(byte); //count the number of 1's
      //check = 2;
      if(check % 2 == 0)
      {
      // It's even
            putch(byte & 0x7F);//set first bit to 0
      }
      else
      {
```

```
// It's odd
            putch(byte | 0x80); //set last bit to 1
      }
}
void
transmit_instructions(unsigned char data_out, unsigned char *reg_in, unsigned
char uc)
{
/*This function takes the standardized numbers from process_commands and
transmits them
 * via SPI to each of the slave PICs.
 * /
      switch(uc){ //Set the slave select line for the PIC we're talking to
      case 'T':
                //tower
            pin_T=0;
            break;
      case 'W': //wheel
            pin_W=0;
            break;
      case 'H': //camera head
            pin_H=0;
            break;
      default:
            break;
      }
      SSPBUF = (data_out); //write the data to the outgoing buffer
      while(!BF);
                              //wait for incoming data to fill the incoming
buffer
      *req in = SSPBUF;
                             //write incoming data to *reg_in
      switch(uc){ //set the slave select line back high again
      case 'T':
            pin_T=1;
            break;
      case 'W':
            pin_W=1;
            break;
      case 'H':
            pin H=1;
            break;
      default:
            break;
      }
}
unsigned int
bitCount(unsigned char n)
{
  // This is for 32 bit numbers. Need to adjust for 64 bits
  register unsigned char tmp;
  tmp = n - ((n >> 1) \& 03333333333) - ((n >> 2) \& 01111111111);
 return ((tmp + (tmp >> 3)) & 030707070707) % 63;
```

Additional Code for the Master Microcontroller

```
#ifndef _MAIN_H_
#define _MAIN_H_
#define Delay(x) DELAY = x; while(--DELAY){ Nop(); Nop(); }
/***** Buttons *****/
// these macros can be used as meaningful shortcuts into
// the response bytes in a PS2's return packet.
#define PS2_Select PS2_byte1.bit0
                               PS2_byte1.bit1
#define PS2_L3 PS2_byte
#define PS2_R3 PS2_byte
#define PS2_Start PS2_byte1.bit3
#define PS2_Up
                                    PS2_byte1.bit2
#define PS2_UpPS2_byte1#define PS2_RightPS2_byte1.bit5#define PS2_DownPS2_byte1.bit6#define PS2_LeftPS2_byte1.bit7
                               PS2_byte1.bit4
#definePS2_L2PS2_byte#definePS2_R2PS2_byte#definePS2_L1PS2_byte#definePS2_R1PS2_byte#definePS2_TrianglePS2_byte#definePS2_CirclePS2_byte
#define PS2 L2
                                    PS2 byte2.bit0
                              PS2_byte2.bit1
PS2_byte2.bit2
PS2_byte2.bit3
#define PS2_Circle PS2_byte2.bit5
#define PS2_X PS2_byte2.bit6
#define PS2_Square
                                   PS2_byte2.bit7
                               PS2_byte3.byte
PS2_byte4.byte
PS2_byte5.byte
#define PS2_RJX
#define PS2_RJY
#define PS2_LJX
#define PS2_LJY
                                    PS2_byte6.byte
/**** Types ****/
// the union lets us access the bytes coming back from a PS2
// either bit by bit or by a whole byte. same memory location,
// just two different names.
typedef union {
  struct {
     unsigned bit7:1;
     unsigned bit6:1;
     unsigned bit5:1;
     unsigned bit4:1;
     unsigned bit3:1;
     unsigned bit2:1;
     unsigned bit1:1;
     unsigned bit0:1;
  };
  struct {
    unsigned char byte;
  };
} uint8;
```

```
#endif
```

Code for Servo microcontroller

#include <htc.h> #include "delay.h" /* For XTAL FREQ macros */ #include <stdlib.h> //A is configured for the tilt servo, B is configured for the roll servo /* The default servo position after power up (128=centered, 0-255) */ #define SERVO_DEFAULT_POS 128 /* Min and max servo pulse widths in microseconds */ #define SERVO PERIOD MIN US A 1000L #define SERVO_PERIOD_MIN_US_B 1085L #define SERVO_PERIOD_MAX_US_A 1800L #define SERVO_PERIOD_MAX_US_B 1430L /* All servos updated once within the following period in microseconds */ #define SERVO FRAME US 20000L //Timer prescaler #define SERVO TIMER DIV 8 //Tick period in us - This is extremely important. This has to be correct or //everything goes to hell. Unfortunately it gets set to 1, but needs to be 1.6. //In order to correct for this, we will just aavoid using this variable and divide //by 1.6 when needed. //#define SERVO_TIMER_TICK_US ((4MHZ*SERVO_TIMER_DIV)/(XTAL_FREQ)) #define SERVO_TIMER_TICK_US 1 double servo_tick_period = (double) SERVO_TIMER_TICK_US; //Min and max servo pulse widths in timer ticks //#define SERVO_PERIOD_MIN_TICKS (SERVO_PERIOD_MIN_US/SERVO_TIMER_TICK_US) #define SERVO_PERIOD_MIN_TICKS_A (int)(SERVO_PERIOD_MIN_US_A/1.6) #define SERVO PERIOD MIN TICKS B (int)(SERVO PERIOD MIN US B/1.6) //#define SERVO PERIOD MAX TICKS (SERVO PERIOD MAX US/SERVO TIMER TICK US) #define SERVO PERIOD MAX TICKS A (int)(SERVO PERIOD MAX US A/1.6) #define SERVO PERIOD MAX TICKS B (int)(SERVO PERIOD MAX US B/1.6) //Number of timer ticks in the whole servo frame, how many tick lengths fit into total frame #define SERVO_FRAME_TICKS (int)(SERVO_FRAME_US/1.6) double period_total_ticks = (double) SERVO_FRAME_TICKS; /* The servo output pin */ #define SERVO_PIN_A RB1 #define SERVO_PIN_B RB2 ___CONFIG(WDTDIS & HS & UNPROTECT); //The servo period in ticks, and the pulsewidth in ticks unsigned int PERIOD= SERVO FRAME TICKS; unsigned int PULSEWIDTH_A;

```
unsigned int PULSEWIDTH_B;
//This is treated as a boolean to switch between emitting a pulse and not
emitting a pulse
unsigned int pulsing_A = 1;
unsigned int pulsing B = 0;
unsigned int position_A;
unsigned int position_B;
void InitServo(void);
void SetServoPos(unsigned char pos, char servo_ID);
void IncrDecrServoPos(unsigned int dir, char servo_ID);
//unsigned int passvar;
/**
* Basic main function just for simulation.
 * Set up port pins, initialise the servo PWM timer and enable interrupts.
 */
void main(void) {
      //Set up PORTc as an input
      TRISC = 0 \times FF;
      //Set up PORTB as an output, then set it low
      TRISB = 0 \times 00;
      PORTB = 0 \times 00;
      while (RC4 != 1)
            ;
      InitServo();
      //INTCON register, not sure what it does
      PEIE = 1; //Peripheral interrupt enable
      GIE = 1; //Global interrupt enable
      unsigned int count = 0;
      for (;;) {
            if (RC4 == 1 && count%15 == 0) {
                  if (count == 15)
                        count = 0;
                  if (RC2 == 1)
                        IncrDecrServoPos(1, 'A');
                  if (RC1 == 1)
                         IncrDecrServoPos(0, 'A');
            if (RC4 == 0 && count%15 == 0) {
                  if (count == 15)
                         count = 0;
                  if (RC2 == 1)
                         IncrDecrServoPos(1, 'B');
                  if (RC1 == 1)
                         IncrDecrServoPos(0, 'B');
            }
            count = count+1;
            //NOP();
      }
}
```

```
/**
* Initialise the servo PWM timer and set initial servo positions.
 * /
void InitServo(void) {
      unsigned char i;
      /* Set up servo timer */
#if SERVO_TIMER_DIV == 1
      T1CON = 0 \times 00;
#elif SERVO_TIMER_DIV == 2
      T1CON = 0 \times 10;
#elif SERVO_TIMER_DIV == 4
      T1CON = 0 \times 20;
#elif SERVO_TIMER_DIV == 8
      T1CON = 0 \times 30;
#else
#error Invalid prescaler value for Timer1
#endif
      SetServoPos(SERVO_DEFAULT_POS, 'A');
      SetServoPos(SERVO DEFAULT POS, 'B');
      //Clearing any pending interrupts
      //Enable interrupts
      //Switch the timer on
      TMR1IF = 0;
      TMR1IE = 1;
      TMR1ON = 1;
}
/**
 * Timer interrupt to run low speed servo PWM.
 * /
void interrupt isr( void ) {
      static unsigned int total_ticks=0;
      unsigned int low_ticks;
      //TMR1IE - Interrupt Enable (turns interrupt on and off)
      //TMR11F - Interrupt Flag (goes high when interrupt occurs)
      if(TMR1IE && TMR1IF) {
            TMR1IF = 0;
            TMR1ON = 0;
            if(pulsing_A) {
                  //Set the timer to wait until the pulse is done before
interrupting
                  TMR1H = (unsigned char)((65535-PULSEWIDTH_A) >> 8);
                  TMR1L = (unsigned char)((65535-PULSEWIDTH_A) & 0xFF);
                  TMR1ON = 1;
                  //Start servo pulse and set the pulsing flag to 0 for the
next interrupt
                  //Stop servo B pulse, Start servo A pulse
                  SERVO_PIN_B = 0;
                  SERVO_PIN_A = 1;
                  pulsing_A = 0;
                  pulsing_B = 1;
            } else if(pulsing_B) {
```

```
/* Finish servo pulse, use up the rest of the frame period
*/
                  TMR1H = (unsigned char)((65535-PULSEWIDTH_B) >> 8);
                  TMR1L = (unsigned char)((65535-PULSEWIDTH_B) & 0xFF);
                  TMR1ON = 1;
                  //Stop servo A pulse, Start servo B pulse
                  SERVO_PIN_A = 0;
                  SERVO PIN B = 1;
                  pulsing B = 0;
            } else {
                  //Set the timer to wait for the rest of the frame before
interrupting again
                  low_ticks = SERVO_FRAME_TICKS - PULSEWIDTH_A -
PULSEWIDTH_B;
                  TMR1H = (unsigned char)((65535-low_ticks) >> 8);
                  TMR1L = (unsigned char)((65535-low_ticks) & 0xFF);
                  TMR1ON = 1;
                  SERVO PIN B = 0;
                  //Reset for the next frame
                  total_ticks = 0;
                  pulsing_A = 1;
            }
      }
}
/**
* Set a servo position.
 * 0 = fully anti-clockwise, 128 = middle, 255 = fully clockwise
 */
void SetServoPos(unsigned char pos, char servo_ID) {
      unsigned int ticks;
      unsigned int min_ticks;
      unsigned int max_ticks;
      if (servo_ID == 'A') {
            position A = pos;
            min_ticks = SERVO_PERIOD_MIN_TICKS_A;
            max_ticks = SERVO_PERIOD_MAX_TICKS_A;
      } else if (servo ID == 'B') {
            position_B = pos;
            min_ticks = SERVO_PERIOD_MIN_TICKS_B;
            max_ticks = SERVO_PERIOD_MAX_TICKS_B;
      } else
            return;
      /* Convert the 8 bit position into the pulse width in timer ticks */
      //ticks = (2*pos*(SERVO_PERIOD_MAX_TICKS -
SERVO_PERIOD_MIN_TICKS))/(255*1.6);
      ticks = (int)((max_ticks - min_ticks)*((float)pos/255));
      /* Set the pulse width with interrupts disabled (ISR uses this array)
*/
      di();
      if (servo_ID == 'A')
```

```
PULSEWIDTH_A = ticks+SERVO_PERIOD_MIN_TICKS_A;
else if (servo_ID == 'B')
        PULSEWIDTH_B = ticks+SERVO_PERIOD_MIN_TICKS_B;
ei();
}
void IncrDecrServoPos(unsigned int dir, char servo_ID) {
    if (servo_ID=='A') {
        if (dir == 1 && position_A < 255)
            position_A = position_A + 1;
        else if (dir == 0 && position_A > 0)
            position_A = position_A - 1;
```

```
else
return;
```

```
SetServoPos(position_A, servo_ID);
} else if (servo_ID=='B') {
    if (dir == 1 && position_B < 255)
        position_B = position_B + 1;
    else if (dir == 0 && position_B > 0)
        position_B = position_B - 1;
    else
        return;
    SetServoPos(position_B, servo_ID);
}
return;
```

```
}
```

C Schedule

The work breakdown schedule (WBS) and gantt chart were developed in Microsoft Project. The schedule for both the Fall and Spring semesters are included.

| I Develop model 66 days Tue 9/208 Mon 12/108 MIT WIT FIT
 | evelop model 65 days? Tue 9/208 Non 12/108 MIIII VIIII VIIIII VIIIIIIIIIIIIIIIIIIIIIIIIIIIIIIIIIIII

 | 1 Develop model 65 days Ture 3028 Mon 12108 Mon 12108 2 Present ensing analoguo podem and sublicion 15 days Ture 3028 Mon 52268 2 3 Baristom 5 days Ture 3028 Mon 52268 2 4 Device garrial design 5 days Ture 3028 Mon 52680 2 5 Determine taxes system 5 days Ture 3028 Mon 16668 2 7 Determine carring system 5 days Ture 10084 Mon 16668 2 8 Create competer model 5 days Ture 10784 Mon 166788 1 1 9 Device specific Scorendition and camera positioning designs 15 days Ture 10784 Mon 160788 1 11 Determine contraints and parameters to past 15 days Ture 107844 Mon 120188 1 1 Mon 12018 12 Determine contraints and parameters to past 2 days Ture 107844 Mon 120188 1 1 Mon 12018 1 1 Mon 12018 1

 | 1 Develop model 64 days Ture 3208 Mon 12/108

 | 1 Develop model 65 days 7 Tue 8208 Multi 1 (1 / 1 / 1 / 1 / 1 / 1 / 1 / 1 / 1 /
 | 1 Develop model 64 days? Tue 8028 Main 1211 Main 12111 Main 1211 Mai
 | 1 Develop model 64 days? The 2018 Mn 12 / MR M 1 / MR M 1 / MR M 1 / MR 2 Research smidg analogous problems and skullows 5 days The 2028 M 1 / Size 20

 | 1 Develop model 64 days? The 20708 Mn 12 / MR M 1 M 1 M 1 M 1 2 Present ensing analogue problems and valutions 5 days? The 20708 Mn 22008 Nn 2200 | 1 Develop model 65 days? The 8708 Mon 2206 2 Presend ensing analogo problems and valutions 5 days? The 8208 Mon 22060 3 Brainstom 5 days? The 8208 Mon 22060 Mon 22060 4 Device general design 5 days? The 8208 Mon 62060 The 8008 5 Determine bacerdio system 5 days? The 8208 Mon 16060 The 8008 6 Determine bacerdio system 5 days? The 9008 Mon 16060 The 9008 7 Determine constrate model 5 days? The 10778 Mon 160208 The 10788 10 Determine constrate and parameters to garts 5 days? The 10778 Mon 162030 The 10788 11 Determine constrate and parameters to garts 10 days? The 10788 Mon 162030 The 10788 12 Decours when and parameters to garts 10 days? The 10788 Mon 122018 The 10788 13 Determine constrate grant for garts 25 days? The 102088 Mon 122018 The 111111
 | 1 Develop model 64 dary3 The 2018 Mon 2206 2 Present ensing analogue problems and valutions 5 dary 1 The 2028 Mon 22068 Non
 | 1 Develop model 65 days? Tue 8028 Mail 1 W V | 1 Develop model 64 days? The 927at Mex 1217a Mex 1217a Mex 1217a Mex 1217a 2 Presenta design and outgos problems and solutions 5 days The 927ab Min 922bi0 days Min 922bi0 days 3 Develop model 5 days The 922bi0 days Min 922bi0 days Min 922bi0 days 4 Develop model 5 days The 920bi0 days Min 1042bi0 days 5 Develop model 6 days The 920bi0 days
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Tue 107/08 Mon 102/708 1 12 Choose wheel and motor parts 10 days Tue 107/408 Mon 102/708 1 13 Determine constraints and parameters for parts 5 days Tue 107/408 Mon 102/708 1 14 Determine constraints and parameters for parts 5 days Tue 10/280 Mon 11/208 1 2 <td>Present existing analogous problems and solutions 15 days Tue 92/208 Mon 92/208 Brainstorm 5 days Tue 92/208 Mon 92/208 2 Determine base system 5 days Tue 92/208 Mon 10/608 3 Determine base system 5 days Tue 92/208 Mon 10/608 5 Determine constaints and parameters 5 days Tue 92/208 Mon 10/608 5 Create computer model 15 days Tue 10/708 Mon 10/2708 5 10/778 Determine constraints and parameters for parts 5 days Tue 10/7788 Mon 10/2708 11 Determine constraints and parameters for parts 5 days Tue 10/7788 Mon 10/2708 11 Determine constraints and parameters for parts 10 days Tue 10/7788 Mon 10/2708 11 Determine constraints and parameters for parts 10 days Tue 10/7788 Mon 10/2708 11 Determine control system model 15 days Tue 10/788 Mon 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The 1070b Non 16270b 1 12 Chocara wheel and not parts 1 diry The 1070b Non 16270b 1 13 Determine control system model 1 diry The 1070b Non 16270b 1 14 Determine someward system model 1 diry The 1072b Non 16270b 1 15 Determine control system 2 diry The 1072b Non 1270b 1 16 Determine control syst</td><td>12 Research existing subgoup problems and solutions 15 dirgs The 2020b Non 2020b 4 Devise general design 5 dirgs The 2020b Non 2020b 1 4 Devise general design 5 dirgs The 2020b Non 2020b 1 5
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 | 13 Determine control system 19 days Tue 107/08 Am 1027/08 /// 14 Determine control and parameters for parts 5 days Tue 107/08 Am 1027/08 // 15 Oncose materialsparts 10 days Tue 107/08 Mm 1027/08 // 16 Determine control system 25 days Tue 102/08 Mm 117/08 // 17 Design control on document system 25 days Tue 102/08 Mm 117/08 // 18 Determine control system meal/ements 6 days Tue 11/02/08 Mm 117/08 // 20 Determine control system model 5 days Tue 11/08 Mm 117/08 // // 21 Braintom control system control 5 days Tue 11/08 Mm 117/08 // // // 22 Choose control system 25 days Tue 10/2008 Mm 117/08 // // // // // // // // // // // // // // // // // <td>13 Determine contrains and parameters for parts 15 days Ture 107788 Mon 1027081 Ture 107788 Mon 127081 Ture 102808 Mon 1177081 Ture 102808 Ture 102808 Mon</td> <td>13 Determine contrains and parameters for parts 15 days Ture 107788 Mon 1027088 Ture 102788 Mon 1027088 Ture 102788 Mon 1177088 Tu</td> <td>13 Determine control system 15 days Ture 107768 Mon 102708 F 14 Determine control system 25 days Ture 107768 Mon 102708 Ture 102708</td> <td>13 Determine contrains and parameters for parts 15 days Tue 107708 Mon 102708 F 14 Determine contrains and parameters for parts 10 days Tue 107708 Mon 102708 F 15 Choose materialsplants 10 days Tue 107708 Mon 102708 F 16 Determine control system 25 days Tue 102208 Mon 127708 F 17 Design bocomotion control system 25 days Tue 102208 Mon 127708 F 18 Determine vorted system model 15 days Tue 10208 Mon 117708 F 20 Determine vorted system model 5 days Tue 11708 Mon 117708 F 21 Braindom control system 25 days Tue 11708 Mon 117708 F 22 Choose particle system model 16 days Tue 11708 Mon 117708 F 23 Determine control system 25 days Tue 11708 Mon 117708 F Mon 117708 F 23 Determine control system model 10 days Tue 11708</td> <td>13 Determine control system 15 days Tue 107768 Ken 1027768 Z 14 Determine controls and parameters for parts 10 days Tue 107768 Ken 1027768 Y 15 Choose materialsparts 10 days Tue 107768 Ken 1027768 Y 16 Detaign control of control system 25 days Tue 102268 Ken 127768 Y 17 Design boconclon control system 25 days Tue 102268 Ken 127768 Y 18 Determine control system meal/ements 6 days Tue 170268 Ken 127768 Y 21 Brainform control system control 5 days Tue 170268 Ken 177768 Y 22 Choose control system 25 days Tue 170268 Ken 177768 Y 23 Determine control system 25 days Tue 170268 Ken 177768 Y 24 Determine control system 25 days Tue 170268 Ken 177768 Y 25 Decontrol system control 5 days Tue 170268 Ken 177768 Y</td> <td>13 Determine some specifics 19 days Tue 107/08 Ken 1027/08 /// 14 Determine contrains and parameters for parts 5 days Tue 107/08 Mon 1027/08 1// 15 Choose materialisparts 10 days Tue 107/08 Mon 1027/08 1// 16 Design bocontion control system 25 days Tue 102/208 Mon 12//08 Mon 12//08 17 Design bocontion control system 25 days Tue 102/208 Mon 12//08 Mon 12//08 18 Determine control system model 5 days Tue 10/2006 Mon 11//08 Mon 11//08 21 Braindom control system model 5 days Tue 11//08 Mon 11//08 Mon 11//08 22 Choose control system model 15 days Tue 11//08 Mon 11//08 Mon 11//08 23 Design arm control system model 15 days Tue 10/2006 Mon 11//08 Mon 11//08 24 Determine control system model 15 days Tue 10/2006 Mon 11//08 Mon 11//08 25 Decontrothant stage system model 15 days<td>13 Determine any specifies 15 days Tue 10708 Men 102708 Tue 102708 Men 12108 Men 12108<!--</td--><td>13 Determine any specifics 15 days Tue 107/28 North 207/28 North 207/28 14 Determine controls and parameters for parts 5 days Tue 107/268 Mon 107/2706 11.14 15 Choose materializations 25 days Tue 107/268 Mon 107/2706 11.14 16 Determine control system 25 days Tue 107/268 Mon 11/208 Mon 11/208 17 Determine control system 25 days Tue 102/268 Mon 11/208 Mon 11/208 18 Determine control system 25 days Tue 102/268 Mon 11/208 Mon 11/208 19 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 21 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 22 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 23 Determine control system requiremets 5 days Tue 10/208 Mon 11/208 Mon 11/208 24 Determine control system requiremets 5 days</td><td>12</td><td>Choose wheel and motor parts</td><td>10 days</td><td>Tue 10/14/08</td><td>Mon 10/27/08</td><td>8.11</td><td>-</td><td></td></td></td> | 13 Determine contrains and parameters for parts 15 days Ture 107788 Mon 1027081 Ture 107788 Mon 127081 Ture 102808 Mon 1177081 Ture 102808 Ture 102808 Mon
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 | 13 Determine control system 15 days Tue 107768 Ken 1027768 Z 14 Determine controls and parameters for parts 10 days Tue 107768 Ken 1027768 Y 15 Choose materialsparts 10 days Tue 107768 Ken 1027768 Y 16 Detaign control of control system 25 days Tue 102268 Ken 127768 Y 17 Design boconclon control system 25 days Tue 102268 Ken 127768 Y 18 Determine control system meal/ements 6 days Tue 170268 Ken 127768 Y 21 Brainform control system control 5 days Tue 170268 Ken 177768 Y 22 Choose control system 25 days Tue 170268 Ken 177768 Y 23 Determine control system 25 days Tue 170268 Ken 177768 Y 24 Determine control system 25 days Tue 170268 Ken 177768 Y 25 Decontrol system control 5 days Tue 170268 Ken 177768 Y | 13 Determine some specifics 19 days Tue 107/08 Ken 1027/08 /// 14 Determine contrains and parameters for parts 5 days Tue 107/08 Mon 1027/08 1// 15 Choose materialisparts 10 days Tue 107/08 Mon 1027/08 1// 16 Design bocontion control system 25 days Tue 102/208 Mon 12//08 Mon 12//08 17 Design bocontion control system 25 days Tue 102/208 Mon 12//08 Mon 12//08 18 Determine control system model 5 days Tue 10/2006 Mon 11//08 Mon 11//08 21 Braindom control system model 5 days Tue 11//08 Mon 11//08 Mon 11//08 22 Choose control system model 15 days Tue 11//08 Mon 11//08 Mon 11//08 23 Design arm control system model 15 days Tue 10/2006 Mon 11//08 Mon 11//08 24 Determine control system model 15 days Tue 10/2006 Mon 11//08 Mon 11//08 25 Decontrothant stage system model 15 days <td>13 Determine any specifies 15 days Tue 10708 Men 102708 Tue 102708 Men 12108 Men 12108<!--</td--><td>13 Determine any specifics 15 days Tue 107/28 North 207/28 North 207/28 14 Determine controls and parameters for parts 5 days Tue 107/268 Mon 107/2706 11.14 15 Choose materializations 25 days Tue 107/268 Mon
107/2706 11.14 16 Determine control system 25 days Tue 107/268 Mon 11/208 Mon 11/208 17 Determine control system 25 days Tue 102/268 Mon 11/208 Mon 11/208 18 Determine control system 25 days Tue 102/268 Mon 11/208 Mon 11/208 19 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 21 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 22 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 23 Determine control system requiremets 5 days Tue 10/208 Mon 11/208 Mon 11/208 24 Determine control system requiremets 5 days</td><td>12</td><td>Choose wheel and motor parts</td><td>10 days</td><td>Tue 10/14/08</td><td>Mon 10/27/08</td><td>8.11</td><td>-</td><td></td></td> | 13 Determine any specifies 15 days Tue 10708 Men 102708 Tue 102708 Men 12108 Men 12108 </td <td>13 Determine any specifics 15 days Tue 107/28 North 207/28 North 207/28 14 Determine controls and parameters for parts 5 days Tue 107/268 Mon 107/2706 11.14 15 Choose materializations 25 days Tue 107/268 Mon 107/2706 11.14 16 Determine control system 25 days Tue 107/268 Mon 11/208 Mon 11/208 17 Determine control system 25 days Tue 102/268 Mon 11/208 Mon 11/208 18 Determine control system 25 days Tue 102/268 Mon 11/208 Mon 11/208 19 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 21 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 22 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 23 Determine control system requiremets 5 days Tue 10/208 Mon 11/208 Mon 11/208 24 Determine control system requiremets 5 days</td> <td>12</td> <td>Choose wheel and motor parts</td> <td>10 days</td> <td>Tue 10/14/08</td> <td>Mon 10/27/08</td> <td>8.11</td> <td>-</td> <td></td> | 13 Determine any specifics 15 days Tue 107/28 North 207/28 North 207/28 14 Determine controls and parameters for parts 5 days Tue 107/268 Mon 107/2706 11.14 15 Choose materializations 25 days Tue 107/268 Mon 107/2706 11.14 16 Determine control system 25 days Tue 107/268 Mon 11/208 Mon 11/208 17 Determine control system 25 days Tue 102/268 Mon 11/208 Mon 11/208 18 Determine control system 25 days Tue 102/268 Mon 11/208 Mon 11/208 19 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 21 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 22 Determine control system 25 days Tue 10/208 Mon 11/208 Mon 11/208 23 Determine control system requiremets 5 days Tue 10/208 Mon 11/208 Mon 11/208 24 Determine control system requiremets 5 days | 12 | Choose wheel and motor parts | 10 days | Tue 10/14/08 | Mon 10/27/08 | 8.11 | - | |
| 14 Determine constraints and parameters for parts 5 days Tue 107/06 Mon 127/08 Mon 127/08<
 | Determine construits and parameters for parts 5 days Tex 107/08 Mon 107/308 Choose materialisparia 10 days Tex 107/08 Mon 107/308 Tex 107/08 Design control and computing system 25 days Tex 102808 Mon 127/08 Mon 127/08 Determine overall system model 15 days Tex 102808 Mon 127/08 Mon 127/08 Determine overall system model 5 days Tex 102808 Mon 127/08 Mon 127/08 Determine overall system model 5 days Tex 102808 Mon 117/08 Mon 127/08 Determine overall system model 5 days Tex 102808 Mon 117/08 Mon 117/08 Choose outrid system potons 5 days Tex 117/88 Mon 117/08 Tex 117/88 Determine overall system model 5 days Tex 117/88 Mon 117/08 Tex 117/88 Determine overall system model 5 days Tex 117/88 Mon 127/08 Tex 117/88 Determine overall system model 5 days Tex 102808 Mon 127/08 Tex 107/08 Determine overall system model 5 days Tex 102808 Mon 127/08 </td <td>14 Determine constants and parameters for parts 5 days Tex 107/88 Mon 107/306 15
Choose metricinalsports 10 days Tex 107/88 Mon 127/08 11 16 Design control and computing system 25 days Tex 107/88 Mon 127/08 11 17 Design bocomation control system 25 days Tex 102/88 Mon 11/308 12 18 Determine overal system model 15 days Tex 102/88 Mon 11/308 12 20 Preleminary research on existing cortor system sign of the 3 days Tex 102/88 Mon 11/308 12 21 Banastom cortorid system requirements 5 days Tex 10/288 Mon 11/308 12 22 Choose cortorid system requirements 5 days Tex 10/288 Mon 11/308 12 23 Determine hordwate 10 days Tex 10/288 Mon 11/308 12 24 Determine hordwate 5 days Tex 10/288 Mon 11/306 12 24 Determine hordwate 5 days Tex 10/288 Mon 11/306 12</td> <td>14 Determine constantist and parameters for parts 15 gray Tate 107/08 Intel 107/08 15 Decloses metalisabiparis 10 days Tate 107/08 Intel 107/08 Intel 107/08 16 Decloses metalisabiparis 25 days Tate 102/08 Intel 107/08 Intel 107/08 17 Design accordition control system 25 days Tate 102/08 Intel 107/08 Intel 107/08 18 Determine 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23 Determine control system model 5 days Tus 117168 Mon 117208 24 24 Determine control system model 26 days Tus 117168 Mon 117208 24 25 Choose points 5 days Tus 117268 Mon 117208 24 26</td><td>14 Determine constanting and parameters for parts 15 app Tus 107780 Non 1071305 15 Declose materialisabris 20 days Tus 107780 Non 1071601 114 16 Declose materialisabris 20 days Tus 107280 Non 1071601 114 17 Design bocomotion control system 20 days Tus 107280 Non 1071601 114 18 Determine control system mag/memtrs 5 days Tus 102580 Mon 1171608 114 20 Preliminary research on existing control system 5 days Tus 102580 Mon 1171608 150 21 Braintomo control system model 5 days Tus 1171680 Mon 1171608 150 22 Choose control system model 5 days Tus 1171680 Mon 1171608 120 23 Determine control system model 5 days Tus 1171680 Mon 1171608 120 24 Determine control system model 5 days Tus 1171680 Mon 1171608 120 25 Declose control system model 5 days Tus 1171680 Mon 1</td><td>14 Determine constants as parameters 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 | 14 Determine constantist and parameters for parts 15 gray Tate 107/08 Intel 107/08 15 Decloses metalisabiparis 10 days Tate 107/08 Intel 107/08 Intel 107/08 16 Decloses metalisabiparis 25 days Tate 102/08 Intel 107/08 Intel 107/08 17 Design accordition control system 25 days Tate 102/08 Intel 107/08 Intel 107/08 18 Determine overall system model 15 days Tate 102/08 Intel 107/08 Intel 107/08 20 Determine overall system model 5 days Tate 102/08 Intel 107/08 Intel 107/08 21 Brainstom control system model 5 days Tate 117/08 Intel 117/08 Intel 117/08 22 Choose parts 5 days Tate 117/08 Intel 117/08 Intel 117/08 23 Determine varial system model 5 days Tate 117/08 Intel 117/08 Intel 117/08 24 Determine varial system model 5 days Tate 117/08 Intel 117/08 Intel 117/08 25 Declosintat daystem model <t< td=""><td>14 Determine constants and parameters for parts 5 days Tax 107/88 Mon 107/308 15 Obcose materialisparts 10 days Tax 107/88 Mon 127/88 Mon 1127/88 Mon 1127/88</td><td>14 Determine 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101, 100, 101, 1</td><td>13</td><td>Determine arm specifics</td><td>15 days</td><td>Tue 10/7/08</td><td>Mon 10/27/08</td><td>7</td><td>-</td><td></td></t<> | 14 Determine constants and parameters for parts 5 days Tax 107/88 Mon 107/308 15 Obcose materialisparts 10 days Tax 107/88 Mon 127/88 Mon 1127/88

 | 14 Determine constants and parameters for parts 15 gene 100708 Nen 107308 15 Decloses metatiologints 25 days Tue 107208 Nen 107308 17 Design accornidio control system 25 days Tue 107208 Nen 127088 18 Determine overall system model 15 days Tue 107208 Nen 117708 19 Determine overall system model 5 days Tue 107208 Nen 117708 21 Brainstom control system Gotton's system 5 days Tue 107208 Nen 117708 22 Choose control system model 6 days Tue 117108 Nen 117708 11 23 Determine control system model 6 days Tue 117108 Nen 117708 12 24 Determine control system model 7 days Tue 107208 Nen 117708 12 25 Choose control system model 7 days Tue 107208 Nen 117708 12 26 Determine control system model 7 days Tue 117108 Nen 117708 12 27 Determine control system model 7 day
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 | 31 Choose cortrol system model 5 days Tut 11/108 Mon 12/108 S0 32 Determine hardware 10 days Tut 11/108 Mon 12/108 S1 33 Determine compuling requirements 5 days Tut 11/208 Mon 12/108 S1 34 Choose parts 5 days Tut 11/208 Mon 12/108 S1 36 Construct the robot 61.5 days Thu 1/2208 Fit 41/108 Thu 1/2208 Fit 41/108 37 Construct the stage 61.5 days Thu 1/2208 Fit 41/108 Thu 1/2208 Fit 41/108 38 Mourt moders and their motors, test motors (First moving part) 28.8 days Thu 2/208 Thu 4/208 37 39 Mourt moders and indexent sets signal 71.3 days Thu 4/108 34 Thu 4/208 Fit 41/108 34 40 Test the base and evaluate and implement necessary improvement 43.7 days Thu 4/208 Thu 4/208 Thu 4/208 43 41 Mourt moder and gaes to base and turn-table, then the stage 11.0 days Thu 4/209 Thu 4/209
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 | 32 Determine hardware 10 days Tue 11/18/08 Mon 12/2408 33 Determine computing requirements 5 days Tue 11/18/08 Mon 12/2408 34 Choose parts 5 days Tue 11/25/08 Mon 12/2408 33 36 Construct the robot 61.5 days Thue 11/2209 Fri 41/1709 34 37 Construct the base 61.5 days Thue 12/209 Fri 41/1709 35 39 Mourt encoders and test signal Tue 12/209 Fri 41/1709 39 40 Test the base and evaluate and implement necessary improvement 4.37 days Thue 42/08 Mourt the column 10 days 41 Mourt the column 0.9 days Thue 42/08 Thue 42/08 34 42 Mourt colum to the un-table, then test 3 days Thue 42/08 Thue 47/08 34 44 Mourt account on the un-table, then test 3 days Thue 47/08 Thue 47/08 34 45 Mourt account and evaluate and implement necessary improvems 5 days Thue 47/08 14 34 34 </td <td>32 Determine hardware 10 days Tue 117808 Mon 12/1408 Z7 33 Determine computing requirements 5 days Tue 117808 Mon 12/2408 34 34 Choose parts 5 days Tue 117808 Mon 12/2408 33 36 Construct the robot 615 days Thu 11/2609 Fri 417708 36 37 Construct base 615 days Thu 12/209 Fri 417708 36 39 Mourt encoders and test signal 71 days Thu 42/209 Thu 42/209 37 40 Test the base and evaluate and implement necessary improvement 437 days Thu 41/209 Mourt 4/209 38 41 Mourt the colum 0.9 days Thu 4/209 Thu 4/209 38 42 Mourt colum to the turn table, etcl motor again 1 days Thu 4/209 140 Mourt activate and evaluate and implement necessary improvement 437 days Thu 4/209 84 34 43 Mourt motor and gars to base and turn-table, then test 3 days Thu 4/209 141/208 144 140</td> <td>32 Determine hardware 10 days Tue 117808 Mon 12/208 77 33 Determine computing requirements 5 days Tue 117808 Mon 11/2408 33 34 Choose parts 5 days Tue 117808 Mon 11/2408 33 35 Construct the robot 61.5 days Thu 11/2090 Fri 417708 34 36 Construct heads as mble the base 61.5 days Thu 11/2090 Fri 417708 54 37 Construct the base and evaluate and implement necessary improvement 7.1 days Thu 47200 Thu 47209 93 40 Test the base and evaluate and implement necessary improvement 4.37 days Thu 47208 Thu 47208 94 41 Mourt the column 0.9 days Thu 47208 Thu 47208 84 42 Mourt colum: to the unriable, test motor again 1 days Thu 47208 1 thu 47208 84 43 Mourt account on the unriable, test motor again 1 days Thu 47008 1 thu 47008 1 thu 47008 44 Mourt count on the unriable, test motor again <t< td=""><td>32 Determine hardware 10 days Tue 11/808 Mon 12/208 77 33 Determine computing requirements 5 days Tue 11/808 Mon 12/208 33 34 Choose parts 5 days Tue 11/2508 Mon 12/208 33 35 Construct the robot 61.5 days Thu 12/209 Fri 41/708 - 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1/12/08 Mon 12/10/08 33 35 Construct the robot 61.5 days Thut 1/22/08 Fri 4/17/08 14/10/08 37 Construct and assemble the base 61.5 days Thut 1/22/08 Fri 4/17/08 14/10/10/10/10/10/10/10/10/10/10/10/10/10/</td><td>32</td><td>Determine hardware</td><td>10 days</td><td>Tue 11/18/08</td><td>Mon 12/1/08</td><td>27</td><td></td><td></td></t<> | 33 Determine computing requirements 5 days Tut 1178/08 Mon 127/08 33 34 Choose parts 5 days Tut 1178/08 Mon 127/08 33 35 Construct the robot 61.5 days Thu 1172/09 Fri 417/09 37 Construct and assemble the base 61.5 days Thu 122/09 Fri 417/08 37 Construct he robot 61.5 days Thu 122/09 Fri 417/08 38 Mourt the wheels and their motors (First moving 171 3 days Thu 42/09 Fri 417/08 58 40 Test the base and evaluate and implement necessary improvement 4 37 days Thu 41/09 Mourt from 417/08 58 41 Mourt the column 10 days Thu 42/09 Thu 47/09 42 42 Mourt motor and gaes to base and turn-table, then test 3 days Thu 42/09 Thu 47/09 14 42 43 Mourt could net stei signal 10 days Tut 47/09 Thu 47/09 42 44 Mourt motor and evaluate and implement necessary improvement 5 days Thu 47/09 17 43 14 <
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 | 34 Choose parts 5 days Tus 1/2508 Mon 12/108 33 35 Construct the robot 61.5 days Tus 1/2508 Fil 4/1708 33 36 Construct the robot 61.5 days Tus 1/2208 Fil 4/1708 34 37 Construct the base 61.5 days Tus 1/2208 Fil 4/1708 34 38 Mourt the wheels and their motors, test motors (first moving part) 28.88 days Fil 2/2009 Tus 4/208 37 39 Mourt the column 13 days Tus 4/208 Mon 4/1309 36 40 Test the base and evaluate and implement necessary improvement 13 days Tus 4/208 Tus 4/208 38 41 Mourt turn-table 0.96 days Tus 4/208 Tus 4/208 33 Tus 4/208 33 34 44 Mourt column to the turn-table, test motor again 1 days Tus 4/208 Tus 4/208 34 34 Tus 4/208 Tus 4/208 37 34 45 Mourt column to the turn-table, test motor again 1 days Tus 4/208 Tus 4/

 | 34 Choose parts 5 days Tut 172/08 Mon 12/08 [33] 35 Construct the robot 61.5 days Thut 172/08 F14/1708 36 Construct the robot 61.5 days Thut 172/08 F14/1708 37 Construct the base 61.5 days Thut 172/08 F14/1708 38 Mourt the wheels and their motors, test motors (F1st moving part) 28.8 days F13/2006 Thut 4700 [37] 39 Mourt the wheels and their motors, test motors (F1st moving part) 28.8 days F13/4708 [36] 40 Test the base and evaluate and implement necessary improvemet 437 days F14/4708 [36] 41 Mourt thun-table, then test 3 days Thu 4/200 [76] Thu 4/200 [36] 42 Mourt courns to the turn-table, then test 3 days Thu 4/200 [76] Thu 4/200 [36] 43 Mourt courns to the un-table, test motor again 1 days Thu 4/200 [76] Thu 4/200 [42] 44 Mourt courns to the un-table, test motor again 1 days Thu 4/200 [76] Thu 4/200 [43] 45 Mourt courns and evaluate and implement necessary improvemet 5 days Thu 4/7
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 | 33 Construct the robot 61.5 days Thu 1/2208 Fri 4/1708 36 Construct and assemble the base 61.5 days Thu 1/2208 Fri 4/1708 37 Construct and assemble the base 61.5 days Thu 1/2208 Fri 4/1708 37 Construct the base 21.13 days Thu 1/2208 Fri 4/1708 38 Mourt encoders and test signal 7.13 days Thu 4/208 57 39 Mourt encoders and test signal 7.13 days Thu 4/208 Fri 4/1708 40 Test the base and valuate and implement necessary improvement 43.7 days Thu 4/209 Thu 4/209 41 Mourt throat and gars to base and turn-table, then test 3 days Thu 4/209 Thu 4/209 42 Mourt andor and gars to base and turn-table, then test 3 days Thu 4/209 Thu 4/209 43 Mourt encoder and test signal 10 days Thu 4/209 Thu 4/209 Thu 4/209 44 Mourt motor and aread table and implement necessary improveme 5 days Thu 4/208 Thu 4/208 Thu 4/208 45 Mourt encoder and test signal 10 days Fri 2/2008 Thu 4/1080 Thu 4/10

 | 35 Construct the solution [61.5 days Thu 1/2209 [F1.417/09] 36 Construct and assemble the base [61.5 days Thu 1/2209 [F1.417/09] 37 Construct and assemble the base [61.5 days Thu 1/2209 [F1.417/09] 37 Construct the base [11.3 days Thu 1/2209 [F1.417/09] 38 Mourt be wheels and their motors, test motors (First moving part) 28.8 days [F1.2 dx009] Thu 4/209 [F1.417/09] 39 Mourt be ovelase and test signal [71.3 days [Thu 4/209] [F1.417/09] [S1.6 days] [S1.6 days] 41 Mourt be ovelase and turnhable then test 3 days [Thu 4/209] [Thu 4/209] [S3.6 days] [Thu 4/209] <t< td=""><td>33 Construct the robot 61.5 days Thut 1/2/09 Fri 4/1709 36 Construct and assemble the base 61.5 days Thut 1/2/09 Fri 4/1709 37 Construct and assemble the base 61.5 days Thut 1/2/09 Fri 4/2709 38 Mourt he wheels and their motors, test motors (First moving) pp.10 88.6 days Thut 4/209 Fri 4/2709 39 Mourt he wheels and their motors, test motors (First moving) pp.10 88.6 days Thu 4/209 Fri 4/1709 40 Test the base and evaluate and implement necessary improvemed. 43 days Thu 4/209 Thu 4/209 Thu 4/209 41 Mourt motor and gens to base and turn-table, then test. 3 days Thu 4/209 Thu 4/209 Thu 4/209 42 Mourt motor and gens to base and turn-table, then test. 3 days Thu 4/209 Thu 4/209 Thu 4/209 44 Mourt ecoder and test signal 10 days Thu 4/209 Thu 4/209 Thu 4/209 45 Mourt ecoder and evaluate and implement necessary improvems 5 days Thu 4/200 Thu 4/209 46 Test the column and evaluate and implement necessary improvems 5 days Thu 4/200 Thu 4/200 <!--</td--><td>33 Construct the robot 61.5 days Thut 12/209 Fri 41/109 36 Construct and assemble the base 61.5 days Thut 12/209 Fri 41/109 37 Construct and assemble the base 61.5 days Thut 12/209 Fri 42/209 37 Construct the base 61.5 days Thut 42/209 Fri 42/209 38 Mourt heweles and their motors, test motors (First moving part) 28.8 days Fri 42/209 Thu 42/209 40 Test the base and evaluate and implement necessary improvement 43.7 days Mon 41/300 Fri 41/709 41 Mount motor and gears to base and turn-table, filen test 3 days Thu 42/209 Thu 41/609 42 Mount motor and gears to base and turn-table, filen test 3 days Thu 42/209 Thu 41/609 43 Mount encoder and test signal 10 days Thu 42/009 Thu 41/609 43 44 Mount encoder and test signal 10 days Thu 42/009 Thu 41/609 43 45 Mount encoder and evaluate and implement necessary improveme 5 days Thu 4/609 17 44/609 44 46 Tost the columa and conhitesi signal 10</td><td>35 Construct the robot 61.5 days Thin 1/2209 Fri 41/109 36 Construct and assemble the base 61.5 days Thui 1/2209 Fri 41/109 37 Construct and assemble the base 61.5 days Thui 1/2209 Fri 42/09 37 Construct the base 61.5 days Thui 4/209 Fri 42/09 38 Mourt the wheels and their motors, test motors (First moving part) 28.6 days Thui 4/209 Thui 4/209 41 Mourt the ockarm 10 days Thui 4/209 Thui 4/209 Thui 4/209 42 Mount motor and gens to base and turn-table, then test 3 days Thui 4/209 Thui 4/209 30 43 Mount motor and gens to base and turn-table, test motor again 1 days
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47090</td><td>38 Construct and assemble the base 61.5 days Thu 172208 Fri 4/1708 37 Construct the base 21.15 days Thu 172208 Fri 4/1708 38 Mourt the wheels and their motors, test motors (First moving part) 28.86 days Fri 22009 Thu 47208 Won 41306 37 38 Mourt the wheels and their motors, test motors (First moving part) 28.86 days Thu 47208 Mount 41006 37 40 Test the base and evaluate and implement necessary improvement 4.37 days Mon 41308 (Mon 41308) Thu 47208 41 Mount the column 0.99 days Thu 4200 (Mon 41308) Thu 47208 42 Mount motor and pars to base and turn-table. the 1.91 days Thu 4700 (Man 4200) Thu 4700 (Man 4200) 43 Mount ecoder and lest signal 1.01 days Thu 4700 (Man 4300) Thu 4700 (Man 4300) 44 Mount ecoder and lest signal 1.01 days Thu 4700 (Man 4300) Thu 4700 (Man 4300) 45 Mount moor and evaluate and implement necessary improvems 5 days Thu 4500 (Man 4300) Thu 4700 (Man 4300) 46 Mount ecoder and lest signal 1.01 days Thu 4700 (Man 4300) Thu 4700 (Man 4300) Thu 4700 (Man 4300) Thu 4700 (Man 4300) Thu 4700</td><td>38 Construct and assemble the base 61.5 days Thu 17209 Fri 41/109 37 Construct the base 61.5 days Thu 17209 Fri 41/109 38 Mourt the wheels and their motors, test motors (First moving part) 28.8 days Fri 22006 Thu 47209 37 38 Mourt the wheels and their motors, test motors (First moving part) 28.8 days Thu 47209 17 Thu 47209 39 40 Test the base and evaluate and implement necessary improvement 4 37 days Thu 47209 17 Thu 47209 30 41 Mount the column 0.99 days Thu 47209 17 Thu 47209 12 42 Mount motor and gens to base and turn-table. then test 3 Thu 47209 17 Thu 47209 17 43 Mount motor and gens to base and turn-table, then test 3 Thu 4700 1700 142 Thu 4700 143 44 Mount encoder and turn-table, test motor 3gain 1 10 days Thu 4700 143 Thu 4700 143 45 Mount anders to and tarn bases and presensary improvems 5 days Thu 4700 170 170 170 170 1450 13 46 Test the column and evaluate and implement necessary improvems 7 days Fit 327009 170 170 370 140 13 47 Assemble and mount camera head to pinion 17 13 days Thu 1</td><td>38 Construct and assemble the base 61.5 days Thu 17209 Fri 47709 37 Construct the base 61.5 days Thu 17209 Fri 47709 38 Mourt the wheels and their motors, test motors (First moving part) 28.8 days Fri 22009 Thu 47209 97 38 Mourt the wheels and their motors, test motors (First moving part) 28.8 days Fri 47709 39 40 Test the base and evaluate and implement necessary improvement 437 days Thu 4709 Fri 47709 39 41 Mount the column 0.99 days Thu 4709 Thu 4709 10 42 42 Mount column to the turnable, test motor again 1 day Thu 4709 Thu 4709 12 43 43 Mount column to the turnable, test motor again 1 days Thu 4709 Thu 4709 12 44 44 Mount column to the unnable, test motor again 1 days Thu 4709 Thu 4709 14 45 45 Mount column to the unnable, test motor again 1 days Thu 4709 17 4209 Thu 4709 14 10 45 14 4309 17 14 <td< td=""><td>35</td><td>Construct the robot</td><td>61.5 days</td><td>Thu 1/22/09</td><td>Fri 4/17/09</td><td></td><td></td><td></td></td<></td></td> | 38 Construct the base [F1.3 days Thu 17208 FH 4708 37 Construct the base [F1.3 days Thu 17208 FH 27006 38 Mourt the wheels and their motors, test motors (First moving part) 28.8 days FH 22006 Thu 4706 37 39 Mourt encoders and test signal [7.13 days Thu 4706 1706 39 40 Test the base and evaluate and implement necessary improvement 4.97 days Thu 4706 1706 1706 39 41 Mount motor and gears to base and turn-table, then test 3 days Thu 4706 1706 1706 42 42 Mount column to the turn-table, test motor again 1 days Thu 4706 1706 1706 142 43 Mount column to the turn-table, test motor again 1 days Thu 4706 1706 1706 1706 142 44 Mount column to the turn-table, test motor again 1 days Thu 4706 1706 1706 1706 1706 142 45 Mount column to the turn-table, test motor again 1 days Thu 4706 1706 1704 7706 142 46 Test the column and revaluate and implement necessary improvement 5 days Thu 4706 1706 1706 170 1706 143 1305 47 Assemble and mount camera head to pinion 7.13 days Thu 17008 170 1700 170 1700 170 1700 1700 1

 | 38 Construct the base 61.5 days Thu 17209 Fri 47109 37 Construct the base 61.5 days Thu 17209 Fri 47109 38 Mourt the wheels and their motors, test motors (First moving part) 28.88 days Fri 32009 Thu 4709 30 39 Mourt the wheels and their motors, test motors (First moving part) 28.88 days Fri 472009 Thu 4709 30 40 Test the base and evaluate and implement necessary improvement 4.37 days Mon 47309 30 41 Mourt the column 10 days Thu 42009 Thu 47009 Thu 47009 42 Mourt motor and pars to base and turn-table, test motor again 1 days Thu 47009 Thu 47009 Thu 47009 43 Mourt column to the turn table, test motor again 1 days Thu 47009 Thu 47009 410 44 Mourt column to the turn table, test motor again 1.01 days Thu 47009 Thu 47009 120 45 Mourt motor brinin 1.43 days Thu 47009 Thu 47009 130 140 46 Test the column and evaluate and inplement necessary improvement 5 days Thu 47009 Thu 47100 143 1400 <td>30 Construct an assemble the base 61.5 days Thu 17209 Fri 4/109 31 Construct the base 61.5 days Thu 17209 Fri 4/109 33 Mourt the wheels and their motors, test motors (Fist moving part) 28.8 days Thi 22009 Thu 47209 34 40 Test the base and evaluate and implement necessary improvement (4.37 days) Mon 4/1309 Fri 4/1709 34 41 Mourt the column 0.99 days Thu 4/209 Thu 4/209 Thu 4/209 42 Mourt motor and gears to base and turn-table. The test and the first motor again 1 days Thu 4/209 Thu 4/209 Thu 4/209 43 Mourt concert and gears to base and turn-table. The test and 10 days Thu 4/209 Thu 4/209 Thu 4/209 Thu 4/209 44 Mourt encoder and test signal 10 days Thu 4/209 Thu 4/200 Thu 4/200 14 45 Mourt encoder and test signal 10 days Thu 4/200 Thu 4/200 Thu 4/200 14 46 Test the column and evaluate and implement necessary improvement 5 days Thu 4/200 Thu 4/200 14 16 14 16 days Thu 4/1600 15 14</td> <td>30 Construct and assemble the base 61.5 days Fri 41/108 31 Construct the base 61.5 days Thu 1/22/08 Fri 42/108 33 Mourt the wheels and their motors, test motors (First moring part) 28.8 days Fri 22/006 Thu 4/22/08 34 Mourt the wheels and test signal 71.3 days Thu 4/22/08 Mourt 41/108 40 Test the base and evaluate and implement necessary improvement 4.37 days Thu 4/200 Fri 41/109 9. 41 Mourt the column 10 days Thu 4/200 Thu 4/200 8. 42 Mourt the column 0.99 days Thu 4/200 Thu 4/200 Thu 4/200 8. 43 Mourt concore and gears to base and turn-table, then test 3 days Thu 4/200 Thu 4/200 14.4 44 Mourt encoder and test signal 10 day Tur 4/700 42 Thu 4/800 43 45 Mount encoder and test signal 10 day Tur 4/700 7. 43/08 Thu 4/800 43 46 Mount contrare head to pinion
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 Mourt encoders and test signal 7.13 days Thu //2006 Thu //2006 37 Mourt encoders and test signal 7.13 days Thu //2006 F14 //2006 37 Mourt encoders and test signal 7.13 days Thu //2006 F14 //2006 37 Mourt motors and pears to base and implement necessary improvement 10 days Thu //2006 Thu //2006 38 Mourt motor and gears to base and implement the test signal 0.99 days Thu //2008 154 Mourt motor and gears to base and implement test enter signal 0.39 days Thu //2008 154 Mourt motor and gears to base and implement test enter signal 0.39 days Thu //2008 154
 | 3/3 Construct the base Character bases Character bases <td>37 Construct the base Construct the base and their motors, test motors (First moving part) 28.8 app. Fir 22009 Fir 242009 38 Mourt moders and test signal T13 days T10 4/206 37 39 Mourt moders and test signal T13 days T10 4/206 37 39 Mourt moders and test signal T13 days T10 4/206 Model 33 41 Mount moders and test signal T13 days T10 4/206 Model 33 42 Mourt throad and evaluate and implement necessary improvement 43.7 days T10 4/206 T10 4/206 J3 43 Mourt throad and gears to base and turn-table, then test 3 days T10 4/206 T10 4/206 J3 44 Moure column to the turn-table, test motors again 1 days Tur 4/206 T10 4/206 J3 45 Moure column to the turn-table, test motors again 1 days Tur 4/206 T10 4/206 J3 46 Tost the column and evaluate and implement necessary improvement 5 days Thu 4/206 T10 4/206 J3 47 Assemble and mount camera head 32.5 days Fir 1/2000 T0 4/400 J3 48 Mourt motor to prism 71.3 days Thu 3/1206 Mon 3/2306 J46 50 Mourt concorts not expatilies, implement necessary improv 71.3 days Thu 3/1</td> <td>37 Construct the base Construct the stage F11 3 days F11 12 000 F11 4 2000 38 Mourt encoders and test signal 713 days Thu 4/200 Thu 4/200 Thu 4/200 39 Mourt the wheels and their motors, test motors
(First moving par) 713 days Thu 4/200 Thu 4/200 Thu 4/200 39 Mourt encoders and test signal 713 days Thu 4/200 F14 4/100 39 41 Mourt throader and evaluate and implement necessary improvement 437 days Thu 4/200 Thu 4/200 Thu 4/200 42 Mourt throader and gears to base and turn-table, then test 3 days Thu 4/200 Thu 4/200 Thu 4/200 33 43 Mourt column to the turn-table, eta motor again 1 days Thu 4/200 Thu 4/200 Thu 4/200 34 44 Mourt column to the turn-table, eta motor again 1 days Thu 4/200 Thu 4/100 Thu 4/200 143 34 45 Mourt column to the un-table, eta motor again 1 days Thu 4/200 Thu 4/100 143 34 140 143 34 140 143 34 144 34 36 1413</td> <td>37 Construct the basise (113 days) (113 days) (113 days) (112 days) (112 days) 38 Mourt the wolder and their motors, test motors (First moving part) (288 days) (112 days)</td> <td>3/3 Construct the basis 113 days 113 days 111 2208 1111 2208 111 2208 111 2208</td> <td>37 Construct the basise 11.3 days 11.4 3 days 11.1 2009 11.2 days 11.1 2009 11.2 days 11.1 2009</td> <td>37 Construct the base Construct the base and their motors, test motors (First moving part) 288 Mourt 22008 Fin 4/2008 38 Mourt flew wheels and their motors, test motors (First moving part) 288 days Thu 4/2008 Thu 4/2008 39 Mourt encoders and test signal Th 3 days Thu 4/2008 Thu 4/2008 ST 39 Mourt the colders and test signal Th 3 days Thu 4/2008 Thu 4/2008 ST 41 Mount the colders and test signal 10 days Thu 4/2009 Thu 4/2009 Thu 4/2009 42 Mount turn-table 0.90 days Thu 4/2009 Thu 4/2009 Thu 4/2009 Thu 4/2009 43 Mount encoder and test signal 1 days Thu 4/2009 Thu 4/2009 Thu 4/2009 43 44 Mount encoder and test signal 1 0 days Thu 4/2009 Thu 4/2009 43 45 Mount amere head to minon 141 days Thu 4/2009 Thu 4/2009 43 46 Test the column and evaluate and implement necessary improvem 5 days Thu 4/2009 Thu 4/2009 50 47 Assemble and mount camere head 82.52 days</td> <td>37 Construct the base 1-13 days 1-13 days 1-14 days 1-14 days 1-14 days 38 Mourt the woldes and their motors, test motors (First moving part) 288 days 1-14 d2/08 7-1 39 Mourt the woldes and their motors, test motors (First moving part) 288 days Thu 4/208 7-1 39 Mourt the voldes and test signal 7-13 days Thu 4/208 7-1 40 Test the base and vulbate and implement necessary improvement 37 days Thu 4/209 7-1 41 Mount the oclumn 0-9 days Thu 4/209 Thu 4/209 7-1 42 Mount motor and gears to base and turn-table, then test 3 days Thu 4/209 Thu 4/209 7-1 43 Mount motor and evaluate and implement necessary improvem 5 days Thu 4/209 Thu 4/209 1-0 1-0 44 Mount concern head to printon 1-01 days Thu 4/209 Thu 4/209 1-0</td> <td>37 Construct the base </td> <td>37 Construct the base Finit 2009 38 Mount the wheels and their motors, test motors (Finit moving part) 28.8 days Finit 22008 39 Mount the wheels and their motors, test motors (Finit moving part) 28.8 days Finit 22008 39 Mount the wheels and their motors, test motors (Finit moving part) 28.8 days Finit 22008 31 Mount the valuate and implement necessary improvement 4.37 days Finit 42009 41 Mount the valuate and implement necessary improvement 4.37 days Tinu 42009 42 Mount the valuate and implement necessary improvement 4.37 days Tinu 47009 43 Mount motor and gears to base and turn-table. Ihen test 3 days Tinu 47009 44 Mount column to the turn-table. Itest motor again 1 days Tinu 47009 Wed 45009 45 Mount motor to prinon 14.13 days Finit 220009 Tinu 47009 Moint 32009 46 Mount camere head to pinion 7.13 days Tinu 47009 Moint 32009 Moint 322009 Moint 32009 Moint 32009</td> <td>37 Construct the base (113 days) (113 days) (113 days) (114 days) 38 Mount the wheels and their motors, test motors (First moving part) (288 days) (114 days) (114 days) 39 Mount the wheels and their motors, test motors (First moving part) (288 days) (114 days) (114 days) (114 days) 39 Mount the valuate and implement necessary improvem (137 days) (114 days) (114 days) (114 days) 41 Mount the valuate and implement necessary improvem (137 days) (114 days) (114 days) (114 days) 42 Mount thur-table (114 days) (114 days) (114 days) (114 days) (114 days) 43 Mount column to the turn-table, then test 3 days) (114 da</td> <td>37 Construct the base 1/13 days 1/13 days 1/12 days<td>36</td><td>Construct and assemble the base</td><td>61.5 days</td><td>Thu 1/22/09</td><td>Fri 4/17/09</td><td></td><td>-</td><td></td></td>
 | 37 Construct the base Construct the base and their motors, test motors (First moving part) 28.8 app. Fir 22009 Fir 242009 38 Mourt moders and test signal T13 days T10 4/206 37 39 Mourt moders and test signal T13 days T10 4/206 37 39 Mourt moders and test signal T13 days T10 4/206 Model 33 41 Mount moders and test signal T13 days T10 4/206 Model 33 42 Mourt throad and evaluate and implement necessary improvement 43.7 days T10 4/206 T10 4/206 J3 43 Mourt throad and gears to base and turn-table, then test 3 days T10 4/206 T10 4/206 J3 44 Moure column to the turn-table, test motors again 1 days Tur 4/206 T10 4/206 J3 45 Moure column to the turn-table, test motors again 1 days Tur 4/206 T10 4/206 J3 46 Tost the column and evaluate and implement necessary improvement 5 days Thu 4/206 T10 4/206 J3 47 Assemble and mount camera head 32.5 days Fir 1/2000 T0 4/400 J3 48 Mourt motor to prism 71.3 days Thu 3/1206 Mon 3/2306 J46 50 Mourt concorts not expatilies, implement necessary improv 71.3 days Thu 3/1

 | 37 Construct the base Construct the stage F11 3 days F11 12 000 F11 4 2000 38 Mourt encoders and test signal 713 days Thu 4/200 Thu 4/200 Thu 4/200 39 Mourt the wheels and their motors, test motors (First moving par) 713 days Thu 4/200 Thu 4/200 Thu 4/200 39 Mourt encoders and test signal 713 days Thu 4/200 F14 4/100 39 41 Mourt throader and evaluate and implement necessary improvement 437 days Thu 4/200 Thu 4/200 Thu 4/200 42 Mourt throader and gears to base and turn-table, then test 3 days Thu 4/200 Thu 4/200 Thu 4/200 33 43 Mourt column to the turn-table, eta motor again 1 days Thu 4/200 Thu 4/200 Thu 4/200 34 44 Mourt column to the turn-table, eta motor again 1 days Thu 4/200 Thu 4/100 Thu 4/200 143 34 45 Mourt column to the un-table, eta motor again 1 days Thu 4/200 Thu 4/100 143 34 140 143 34 140 143 34 144 34 36 1413
 | 37 Construct the basise (113 days) (113 days) (113 days) (112 days) (112 days) 38 Mourt the wolder and their motors, test motors (First moving part) (288 days) (112 days)
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 | 37 Construct the basise 11.3 days 11.4 3 days 11.1 2009 11.2 days 11.1 2009 11.2 days 11.1 2009
11.1 2009 | 37 Construct the base Construct the base and their motors, test motors (First moving part) 288 Mourt 22008 Fin 4/2008 38 Mourt flew wheels and their motors, test motors (First moving part) 288 days Thu 4/2008 Thu 4/2008 39 Mourt encoders and test signal Th 3 days Thu 4/2008 Thu 4/2008 ST 39 Mourt the colders and test signal Th 3 days Thu 4/2008 Thu 4/2008 ST 41 Mount the colders and test signal 10 days Thu 4/2009 Thu 4/2009 Thu 4/2009 42 Mount turn-table 0.90 days Thu 4/2009 Thu 4/2009 Thu 4/2009 Thu 4/2009 43 Mount encoder and test signal 1 days Thu 4/2009 Thu 4/2009 Thu 4/2009 43 44 Mount encoder and test signal 1 0 days Thu 4/2009 Thu 4/2009 43
45 Mount amere head to minon 141 days Thu 4/2009 Thu 4/2009 43 46 Test the column and evaluate and implement necessary improvem 5 days Thu 4/2009 Thu 4/2009 50 47 Assemble and mount camere head 82.52 days | 37 Construct the base 1-13 days 1-13 days 1-14 days 1-14 days 1-14 days 38 Mourt the woldes and their motors, test motors (First moving part) 288 days 1-14 d2/08 7-1 39 Mourt the woldes and their motors, test motors (First moving part) 288 days Thu 4/208 7-1 39 Mourt the voldes and test signal 7-13 days Thu 4/208 7-1 40 Test the base and vulbate and implement necessary improvement 37 days Thu 4/209 7-1 41 Mount the oclumn 0-9 days Thu 4/209 Thu 4/209 7-1 42 Mount motor and gears to base and turn-table, then test 3 days Thu 4/209 Thu 4/209 7-1 43 Mount motor and evaluate and implement necessary improvem 5 days Thu 4/209 Thu 4/209 1-0 1-0 44 Mount concern head to printon 1-01 days Thu 4/209 Thu 4/209 1-0
 | 37 Construct the base
 | 37 Construct the base Finit 2009 38 Mount the wheels and their motors, test motors (Finit moving part) 28.8 days Finit 22008 39 Mount the wheels and their motors, test motors (Finit moving part) 28.8 days Finit 22008 39 Mount the wheels and their motors, test motors (Finit moving part) 28.8 days Finit 22008 31 Mount the valuate and implement necessary improvement 4.37 days Finit 42009 41 Mount the valuate and implement necessary improvement 4.37 days Tinu 42009 42 Mount the valuate and implement necessary improvement 4.37 days Tinu 47009 43 Mount motor and gears to base and turn-table. Ihen test 3 days Tinu 47009 44 Mount column to the turn-table. Itest motor again 1 days Tinu 47009 Wed 45009 45 Mount motor to prinon 14.13 days Finit 220009 Tinu 47009 Moint 32009 46 Mount camere head to pinion 7.13 days Tinu 47009 Moint 32009 Moint 322009 Moint 32009 | 37 Construct the base (113 days) (113 days) (113 days) (114 days) 38 Mount the wheels and their motors, test motors (First moving part) (288 days) (114 days) (114 days) 39 Mount the wheels and their motors, test motors (First moving part) (288 days) (114 days) (114 days) (114 days) 39 Mount the valuate and implement necessary improvem (137 days) (114 days) (114 days) (114 days) 41 Mount the valuate and implement necessary improvem (137 days) (114 days) (114 days) (114 days) 42 Mount thur-table (114 days) (114 days) (114 days) (114 days) (114 days) 43 Mount column to the turn-table, then test 3 days) (114 da | 37 Construct the base 1/13 days 1/13 days 1/12 days <td>36</td> <td>Construct and assemble the base</td> <td>61.5 days</td> <td>Thu 1/22/09</td> <td>Fri 4/17/09</td> <td></td> <td>-</td> <td></td> | 36 | Construct and assemble the base
 | 61.5 days | Thu 1/22/09 | Fri 4/17/09 | | - | |
| 36 Modult lew interes and uter motors, test motors prise moting parti (266 days) The 22006 The 42000 J7 39 Modult encodes and lest signal Tri (3200 days) Thu (4200 days) 40 Test the base and evaluate and implement necessary improvement (4.37 days) Thu (4200 days) Find 4700 gas) 41 Mount turn-table 10 days Thu (4200 days) Thu (4200 fail) 42 Mount turn-table, est notor and gears to base and turn-table, test motor and in the test motor and intervale. 0.99 days) Thu (4200 fail) 43 Mount column to the turn-table, test motor and intervale. 1 days Thu (4200 fail)
 | mout the wheels and bell microls (as include (risk inverse) gard) 26.86 days m12.4206 Jar Mourt encodes and test signal 7.13 days Thu 4/206 Mourt mocks and evaluate
and implement necessary improvement 4.37 days Mon 4/1300 Mount mocks and evaluate and implement necessary improvement 4.37 days Mon 4/1300 Mount much and evaluate and implement necessary improvement 4.37 days Mon 4/1300 Mount much and evaluate and implement necessary improvement 4.07 days Thu 4/208 Mount much and evaluate and implement necessary improvement 4.07 days Thu 4/208 Mount much and evaluate and implement necessary improvement 6.98 days Thu 4/208 Mount much and the bus the hole hole in endors one point 6.98 days Thu 4/208 Mount much and the bus the hole hole in endors one point 6.407 Thu 4/208
 | 30 modult encoders and test signal 11.3 22.005 11.9 22.005

 | 30 Modul encoders and test signal 17.3 days Thu 22008 T

 | 30 Indust where and text signal 17.3 days 17.4 2000 11.0 4200 37 30 Mout encoders and text signal 7.7 3 days Mon 41300 53 40 Test the base and evaluate and implement necessary improvement 4.37 days Mon 41300 Fir 41700 39 41 Mout the column 10 days Thu 4200 Thu 4200 31 42 Mourt motor and gears to base and turn-table, test motor agin 10 days Thu 4200 Thu 4200 31 43 Mourt motor and gears to base and turn-table, test motor agin 10 days Thu 4200 Thu 4200 34 44 Mourt encoder and test signal 101 days Tur 4700 Thu 44000 143 45 Mourt motor and evaluate and implement necessary improvemet 5 days Thu 4700 Thu 4700 Thu 4700 153 46 Test the column and evaluate and implement necessary improvemet 5 days Thu 3700 Thu 3700 37 48 Mourt motor torion 14.13 days Thu 3700 Mon 4800 He9 50 Mourt encoders and test signal 10 days Mon 4800 He9 51 Test the column and test signal 10 days Thu 3700 Mon 4800 He9 53 Determine singnal type and interfacing, choose a
 | 30 Model at winders and uter microsity, risk microsity pairs, 12-2006 The 22-006 The 22-006 The 22-006 The 42-006

 | 30 Initial Life millets and Life millets (rest millets) (rest millets) (rest millets) Initial 22006 Initial 2200
 | 30 Modult all winders and uter mixed system. There inform julie j. 22-06 or gas The 42-06 inform julie j. 22-06 or gas 30 Mount encoders and less signal 7.13 days The 42-06 j.7 31 Mount encoders and less signal 7.13 days The 42-06 j.7 40 Test the base and evaluate and implement necessary improvement 4.37 days The 47-09 j.9 41 Mount the column 0.99 days The 47-09 j.7 42 Mount motor and gars to base and turn-table, then test
 | 30 Introduct is members and their microls, test microls priors moring junit (28-66 days) The 22-006 The 42-006 junit for the stress of the microls priors moring junit (28-66 days) The 42-006 junit for the stress of the | 30 Moult all writem and uter mixeds i gran moulds (rest mould prixe movement) 713 days Thu 4/200 JI 30 Mourt encoders and lots if grant diversity in the mound prixed basis 713 days Thu 4/200 JI 40 Test the base and evaluate and implement necessary improvement (4 37 days) Thu 4/200 JI Fin 4/709 J9 41 Mount the column 10 days Thu 4/200 JI Thu 4/200 JI 42 Mount motor and gears to base and turn-table. The test signal 10 days Thu 4/200 JI Thu 4/200 JI 43 Mount concert and gears to base and turn-table. The test signal 11 days Thu 4/200 JI Thu 4/200 JI 44 Mount encoder and test signal 10 days Thu 4/200 JI Thu 4/200 JI 45 Mount encoder and test signal 10 days Thu 4/200 JI Thu 4/200 JI 46 Test the column and evaluate and implement necessary improvement 5 days Thu 4/200 JI Thu 4/200 JI 47 Assemble and mount camera head to prinon 11 3 days Thu 3/200 JI Mount 3/200 JI 48 Mount encoders and test signal 10 days Mon 3/2200 JI Mon 3/2200 JI
 | 30 Moult and meters and their micros (risk moung junit) 288 days The 22006 Mon 47308 J3 31 Mount encoders and dest signal 713 days Thu 47208 Mon 47308 J3 40 Test the base and evaluate and implement necessary improvement 4 37 days Thu 47208 Thu 47208 J3 41 Mount the column 10 days Thu 47208 Thu 47208 J3 42 Mount motor and gears to base and turn-table. then test 3 0.99 days Thu 47208 Thu 47208 J3 43 Mount motor and gears to base and turn-table. then test 3 Thu 47208 Thu 47208 J1 Thu 47208 J3 44 Mount encoder and test signal 1 days Thu 47208 Thu 47508 J3 45 Mount encoder and test signal 1 days Thu 4709 Thu 47609 J4 46 Test the column and evaluate and implement necessary improvems 5 days Thu 4709 Thu 47609 J4 47 Assemble and mount camera head to pinion 113 days Fit 320009 Thu 47609 J4 48 Mount encoders and test signals 10 days Mon 322309 J6 50 Mount encoders and test signals 10 days Mon 322309 J6 51 Test the camera's motion capabilities, implement necessary impro 7 days Mon 47009 J
 | 33 Modul in meters and their micros, test micros (most pain most pain) 7.13 4.2008 The 4.2008 The 4.2008 Mon 41308 (35 40 Test the base and evaluate and implement necessary improvement 4.37 days Thu 4.4208 Fin 4.4708 (39.9) 41 Mount mood real signal 0.99 days Thu 4.200 Thu 4.4208 Thu 4.4208 42 Mount mood real gears to base and turn-table, then test 0.99 days Thu 4.200 Thu 4.4009 (3.3) 43 Mount mood real desi signal 1.01 days Thu 4.400 (4.3) 44 Mount encoder and turn-table, test moor again 1.04 y Thu 4.400 (4.3) 45 Mount encoder and carears head 1.01 days Thu 4.400 (4.3) 46 Test the column and evaluate and implement necessary improvem 5 days Thu 4.400 (4.5) 47 Assemble and mount carears head 1.01 days Thu 4.400 (4.5) 48 Mount ancero head to philon 1.71 3 days Thu 3.4000 (4.5) 49 Mount cancero head to philon 7.1 3 days Thu 3.4000 (4.5) 41 Test the camera's motion capabilities, implement necessary improvem 7 days Mon 4.600 (4.6) 51 Test the camera's motion capabilit | 33 Modult in mineters and their middles, test middles (risk middles | 33 Modult is minetes and item motors, item motors (risk motoring junit) 28.06 days The J22000 Mon 4/1308 (3) 34 Mount encoders and item motors, item motors (risk motoring junit) 28.06 days The J22000 Mon 4/1308 (3) 40 Test the base and evaluate and implement necessary improvement (137 days) Thu 4/208 (3) Mon 4/1308 (3) 41 Mount the column 10 days Thu 4/208 (178 (3)) Thu 4/1608 (3) 42 Mount motor and gears to base and turn-table, then test (3) 0.99 days Thu 4/208 (170 (178 (3)) 43 Mount motor and gears to base and turn-table, then test (3) 0.99 days Thu 4/208 (170 (178 (3)) 44 Mount encoder and test signal 1 days Thu 4/208 (13 (178 (178 (178 (178 (178 (178 (178 (178 | 3/ | Construct the base
 | 21.13 days | Thu 1/22/09 | Fn 2/20/09 | 27 | - | |
| 33 mode reloces and less signal 1.13 days mode // 104 //208 mode // 104 //208 mode // 104 //208 // mode // 104 //208 /// /// /// /// /// /// /// /// /// /// /// /// /// /// /// /// /// ///
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 | 39 mode thockets and resk signal F10 days f10 4709 fter (H1706) 30 40 Test the base and weakuite and implement necessary improvement 43.7 days fter (H1706) 30 41 Mount thre column 10 days Tteu 4706) Tteu 47060 42 Mount turn-table 0.99 days Tteu 47060 Tteu 47060 12 43 Mount notor and gears to base and turn-table, then test 3 days Tteu 47060 Tteu 47060 13 44 Mount column to the turn-table, etch tentoro again 1 days Tteu 47060 Tteu 47060 14 45 Mount column to the turn-table, etch tentoro again 1 days Ture 47060 Tteu 47060 14 46 Test the column and evaluate and implement necessary improvement 5 days The 14000 Tteu 47060 14 47 Assemble and mount camera head 38.25 days Fti 22000 Tteu 47060 14 48 Mount camera head to pinion 1.13 days Ttru 17008 Mond 47000 14 50 Mount camera head to paino 7.13 days Ttru 17060 44 10 49 Mond 47000 14 3400

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 | 13 Involve founders and reas again 1.5 days Involve founders and reas again 14 Mount the oclumn 1.5 days Involve founders and reas again 14 Mount thre oclumn 1.6 days Thu 4/208 F1 4/1708 3.9 14 Mount thre oclumn 0.99 days Thu 4/208 Thu 4/208 3.0 14 Mount threader 0.99 days Thu 4/208 Thu 4/208 3.0 14 Mount column to the unrable, teen test 3 days Thu 4/208 1.0 4.3 14 Mount column to the unrable, teen test 3 days Thu 4/208 1.0 4.3 14 Mount accounts the unrable, teen tors again 1.01 days Thu 4/208 1.5 1.0 </td <td>39 Introduction statutes signal 17.3 days Introduction statutes signal 40 Test the base and valuate and implement necessary improvement 4.37 days Introduction statutes signal 57.4 d17.08 39 41 Mount thre column 10 days Thu 4/200 Thu 4/200 38 42 Mount thre column 0.90 days Thu 4/200 71.4 d27.09 32 43 Mount down ad pears to base and
turn-table, then test 3 days Thu 4/200 17.4 d7.00 42 44 Mount column to the turn-table, test motor again 1 days Tur 4/700 Tru 4/700 42 45 Mount column to the un-table, test motor again 1 days Tur 4/700 Thu 4/800 43 46 Test the column and ruber advaluet and implement necessary improvemes 50.3 yrs Thu 4/800 45 47 Assemble and mount camera head 38.25 days Frit 22000 Wed 4/800 45 48 Mount motor to adtest signals 10 days Thu 4/800 45 50 50 Mount ecoders and test signals 10 days Thu 1/1500 Mon 4/809 49 51 Test the column and rot</td> <td>139 Introduction statuties signal 17.3 days Introduction statuties signal 141 Mount the oclumn 18 days Thu 47.00 33 141 Mount thre oclumn 18 days Thu 47.00 33 142 Mount thre oclumn 0.90 days Thu 47.00 34 143 Mount threadie 0.90 days Thu 47.00 34 144 Mount column to the turntable, test motor again 1 days Thu 47.00 104 145 Mount column to the turntable, test motor again 1 days Thu 47.000 143 145 Mount column to the unrtable, test motor again 1 days Thu 47.000 Thu 47.000 42 146 Test the oclumn and evaluate and implement necessary improvemes 5 days Thu 47.000 Thu 47.000 43 46 Test the column and relating signal 1.01 days Tue 47.000 Thu 47.000 45 47 Assemble and mount camera head 38.25 days Fri 22.000 Mon 47.000 45 48 Mount motor to prinon 1.13 days Thu 17.000 Mon 47.000 46 50 Mount ecoretra and test signa</td> <td>133 Inclust studies signal 17.3 days Mixed 220 mixed 22</td> <td>139 Introduct studies signal 17.3 days Mixed 200 mixed</td> <td>139 Involute includes allowed signal 17.5 days Mind 17.028 39 141 Mount the ockum 10 days Thu 47.08 39 142 Mount this cokum 10 days Thu 47.08 39 141 Mount this cokum 10 days Thu 47.08 39 142 Mount this cokum 0.99 days Thu 47.09 17hu 47.09 32 143 Mount columts to the untable, tent test 3 days Thu 47.00 142 100 143 144 Mount columts to the untable, tent test 3 days Thu 47.00 142 144 145 Mount columts to the untable, tent test aginal 1 of days Tue 47.00 Thu 47.000 142 146 Test the column and evaluate and implement necessary improvems 5 days Thu 47.000 143 143 147 Assemble and mount camera head 38.25 days Thu 27.000 Non 47.000 143 143 148 Mount moore brain of test signals 10 days Thu 47.100 Non 47.000 143 143 143 143 143 143 143 143 143 14</td> <td>39 Involute involutes and verse signal 1.13 dutys Involutes and verse signal 1.14 dutys Involutes and verse signal Involutes and verse</td> <td>39 Involusion and vesk signal 1.13 days Involusion 1.13 days</td> <td>133 Intel A Bridge and Leak signal 1.7.3 days Intel A J200 (a) 50 141 Mount the column 10 days Thu 4/208 (b) 51 15.4 days Thu 4/208 (b) 52 141 Mount the column 0.9 days Thu 4/208 (b) 51 Thu 4/208 (b) 51 142 Mount thm table 0.99 days Thu 4/208 (b) 51 Thu 4/208 (b) 52 143 Mount column to the tournable, then test 3 days Thu 4/208 (b) 12 Ved 4/809 (c) 12 144 Mount column to the tournable, then test 3 days Thu 4/208 (c) 12 Ved 4/809 (c) 12 145 Mount column to the tournable, then tost again 1 days Tue 4/709 (c) 170 (c) 170 (c) 12 Thu 4/809 (c) 12 146 Test the column and evaluate and Implement necessary improvems 5 days Thu 4/809 (c) 170 (</td> <td>38</td> <td>Mount the wheels and their motors, test motors (First moving part)</td> <td>28.88 days</td> <td>Fn 2/20/09</td> <td>Mon 4/12/09</td> <td>37</td> <td>-</td> <td></td> | 39 Introduction statutes signal 17.3 days Introduction statutes signal 40 Test the base and valuate and implement necessary improvement 4.37 days Introduction statutes signal 57.4 d17.08 39 41 Mount thre column 10 days Thu 4/200 Thu 4/200 38 42 Mount thre column 0.90 days Thu 4/200 71.4 d27.09 32 43 Mount down ad pears to base and turn-table, then test 3 days Thu 4/200 17.4 d7.00 42 44 Mount column to the turn-table, test motor again 1 days Tur 4/700 Tru 4/700 42 45 Mount column to the un-table, test motor again 1 days Tur 4/700 Thu 4/800 43 46 Test the column and ruber advaluet and implement necessary improvemes 50.3 yrs Thu 4/800 45 47 Assemble and mount camera head 38.25 days Frit 22000 Wed 4/800 45 48 Mount motor to adtest signals 10 days Thu 4/800 45 50 50 Mount ecoders and test signals 10 days Thu 1/1500 Mon 4/809 49 51 Test the column and rot
 | 139 Introduction statuties signal 17.3 days Introduction statuties signal 141 Mount the oclumn 18 days Thu 47.00 33 141 Mount thre oclumn 18 days Thu 47.00 33 142 Mount thre oclumn 0.90 days Thu 47.00 34 143 Mount threadie 0.90 days Thu 47.00 34 144 Mount column to the turntable, test motor again 1 days Thu 47.00 104 145 Mount column to the turntable, test motor again 1 days Thu 47.000 143 145 Mount column to the unrtable, test motor again 1 days Thu 47.000 Thu 47.000 42 146 Test the oclumn and evaluate and implement necessary improvemes 5 days Thu 47.000 Thu 47.000 43 46 Test the column and relating signal 1.01 days Tue 47.000 Thu 47.000 45 47 Assemble and mount camera head 38.25 days Fri 22.000 Mon 47.000 45 48 Mount motor to prinon 1.13 days Thu 17.000 Mon 47.000 46 50 Mount ecoretra and test signa
 | 133 Inclust studies signal 17.3 days Mixed 220 mixed 22
 | 139 Introduct studies signal 17.3 days Mixed 200 mixed | 139 Involute includes allowed signal 17.5 days Mind 17.028 39 141 Mount the ockum 10 days Thu 47.08 39 142 Mount this cokum 10 days Thu 47.08 39 141 Mount this cokum 10 days Thu 47.08 39 142 Mount this cokum 0.99 days Thu 47.09 17hu 47.09 32 143 Mount columts to
the untable, tent test 3 days Thu 47.00 142 100 143 144 Mount columts to the untable, tent test 3 days Thu 47.00 142 144 145 Mount columts to the untable, tent test aginal 1 of days Tue 47.00 Thu 47.000 142 146 Test the column and evaluate and implement necessary improvems 5 days Thu 47.000 143 143 147 Assemble and mount camera head 38.25 days Thu 27.000 Non 47.000 143 143 148 Mount moore brain of test signals 10 days Thu 47.100 Non 47.000 143 143 143 143 143 143 143 143 143 14 | 39 Involute involutes and verse signal 1.13 dutys Involutes and verse signal 1.14 dutys Involutes and verse signal Involutes and verse | 39 Involusion and vesk signal 1.13 days Involusion 1.13 days
 | 133 Intel A Bridge and Leak signal 1.7.3 days Intel A J200 (a) 50 141 Mount the column 10 days Thu 4/208 (b) 51 15.4 days Thu 4/208 (b) 52 141 Mount the column 0.9 days Thu 4/208 (b) 51 Thu 4/208 (b) 51 142 Mount thm table 0.99 days Thu 4/208 (b) 51 Thu 4/208 (b) 52 143 Mount column to the tournable, then test 3 days Thu 4/208 (b) 12 Ved 4/809 (c) 12 144 Mount column to the tournable, then test 3 days Thu 4/208 (c) 12 Ved 4/809 (c) 12 145 Mount column to the tournable, then tost again 1 days Tue 4/709 (c) 170 (c) 170 (c) 12 Thu 4/809 (c) 12 146 Test the column and evaluate and Implement necessary improvems 5 days Thu 4/809 (c) 170 (| 38 | Mount the wheels and their motors, test motors (First moving part) | 28.88 days | Fn 2/20/09 | Mon 4/12/09 | 37 | - | |
| 40 Test the base and evaluate and implement necessary impoveriment values and implement necessary impoveriment necessary impoveriment values and implement necessary impoveriment values and implement necessary impoveriment necessary impoveriment values and implement necessary impoveriment necessary imp
 | Mount the column 10 days Thu 4/2/09 Thu 4/2/09 38 Mount thurs/table 0.9 days Thu 4/2/09 Thu 4/2/09 38 Mount motor and gears to base and turn-table, then test 3 days Thu 4/2/09 Thu 4/2/09 38 Mount motor and gears to base and turn-table, then test 3 days Thu 4/2/09 Thu 4/2/09 36

 | How the column Fund AFB bit Thus 4746 bit 41 Mount the column 0 days Thus 4746 bit 42 Mount threadle 0.96 days Thus 4746 bit 43 Mount threadle 0.96 days Thus 4746 bit 44 Mount thore and gears to base and turn-table, then test 3 days Thus 4746 bit 45 Mount concert and gears to base and turn-table, test motor again 1 days Ture 47760 H22 46 Mount encoder and test signal 1 days Ture 47760 H33 46 Test the column and evaluate and implement necessary improvem; 5 days Thu 47000 H33 47 Assemble and mount camera head to pinion 17.13 days Fit 22000 Thus 47000 H34 48 Mount concerts head to pinion 17.13 days Thu 47000 H34 49 Mount camera head to pinion 17.13 days Thu 47000 How 17.000 HA 49 Mount camera head to pinion 17.13 days Thu 47000 How 17.000 How 17.000 HA 50 Mount camera head to pinion 17.13 days Thu 1700 How 14.000 HA 51 Test the camere ¹¹ thow 10.000 capabilitis, implement necessary

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 | How The solution of the structure is a material intervention (a) for the solution of th
 | 41 Moute the column 10 days Int 41/08 Int 41/08 42 Moute the column 0.99 days Thu 42/08 Thu 41/08 43 Moute the column 0.99 days Thu 42/08 Thu 42/08 44 Moute motor and gens to base and turn-table, then test 0.99 days Thu 42/08 Thu 42/08 45 Moute motor and gens to base and turn-table, then test 3 days Thu 42/08 Thu 42/08 46 Moute nooder and test signal 1 day Tue 47/09 Viet 4/090 43 47 Assemble and moute camera head 10 days Thu 4/100 Thu 4/1008 43 48 Moute nooder and to philon 14 13 days Thu 4/1009 Thu 4/1008 45 49 Moute Concern head to philon 71 days Thu 3/1008 45 49 Moute Concern head to philon 71 days Thu 3/1008 46 50 Moute amore head to philon 71 days Moute 32009 47 51 Test the columera's motion capabilities, implement necessary improv 7 days Moute 41/508 50 52 Write doffecortor grash, test
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 | 41 Mourt the column 10 days Init v1200 Init v1200 Init v1200 42 Mount the column 0 days Thu 4/208 Thu 4/208 Init v1200 Thu 4/208 42 Mount thread and parameters bese and turn-table, then test 0 days Thu 4/208 Thu 4/208 Init v1200 Thu 4/208 43 Mount concert and gens to base and turn-table, then test 3 days Thu 4/208 Thu 4/208 Init v1200 Thu 4/208 Init v1200 Thu 4/208 Init v1200 Init v1200 Thu 4/208 Init v1200 Init v1200 </td <td>41 Mourt the column 10 days Int v1208 Int v1208 Int v1208 42 Mourt the column 0.99 days Thv 4/208 Thv 4/208 Int v1208 43 Mourt the column 0.99 days Thv 4/208 Thv 4/208 Int v1208 44 Mourt moor anglears to base and tum-table, then test 3 days Thv 4/208 Thv 4/208 45 Mourt column to the tum-table, test moor again 1 day Tuv 4/708 Wed 44009 43 46 Test the column and evaluate and implement necessary improvems 5 days Thv 4/708 Wed 44009 45 47 Assemble and mount camera head 10 days Fh1 2/2009 Thv 4/708 48 Mourt ancere head to pinion 14 13 days Fh1 2/2009 Thv 4/708 49 Mourt ancere head to pinion 17 13 days Thv 1/1508 Mon 22009 45 51 Test the camera's molic capabilities, implement necessary inprovemory 7 days Mon 22009 46 53 Determine signal lope and interfacing, choose a language 4 13 days Thv 1/1508 Fil 41708 54 Make PICs operational date signals.est 14 13 days Thv 1/1508 Mon 4/309</td> <td>41 Mourt the column 10 days Int v1208 Int v12008 Int v12008</td> <td>1 Mount the column 10 days Int under the column 41 Mount the column 0.99 days Thu 4/206 Thu 4/206 42 Mount the column 0.99 days Thu 4/206 Thu 4/206 43 Mount theore and gears to base and turn-table, then test 0.99 days Thu 4/206 Thu 4/206 44 Mount moor and gears to base and turn-table, then test 3 days Thu 4/206 Thu 4/206 44 Mount encoder and test signal 1 day Tuu 4/706 Wed 4/8008 13 45 Mount encoder and evaluate and implement necessary improvems 5 days Thu 4/800 14 46 Test the column and evaluate and implement necessary improvems 5 days Thu 4/800 14 47 Assemble and mount camera head 822 days Thu 4/800 14 16 48 Mount amere head to pinion 14.13 days Fit 22000 Thu 3/1500 15 49 Mount amere head to pinion 17.13 days Mou 3/2309 46 16 50 Mount encoders and test signal 10 days Mon 3/2309 Mon 4/3309 15 51 Test</td> <td>40</td> <td>Toot the bace and evaluate and implement percessory improvement</td> <td>7.15 days</td> <td>Mon 4/12/09</td> <td>Eri 4/17/05</td> <td>30</td> <td></td> <td></td> | 41 Mourt the column 10 days Int v1208 Int v1208 Int v1208 42 Mourt the column 0.99 days Thv 4/208 Thv 4/208 Int v1208 43 Mourt the column 0.99 days Thv 4/208 Thv 4/208 Int v1208 44 Mourt moor anglears to base and tum-table, then test 3 days Thv 4/208 Thv 4/208 45 Mourt column to the tum-table, test moor again 1 day Tuv 4/708 Wed 44009 43 46 Test the column and evaluate and implement necessary improvems 5 days Thv 4/708 Wed 44009 45 47 Assemble and mount camera head 10 days Fh1 2/2009 Thv 4/708 48 Mourt ancere head to pinion 14 13 days Fh1 2/2009 Thv 4/708 49 Mourt ancere head to pinion 17 13 days Thv 1/1508 Mon 22009 45 51 Test the camera's molic capabilities, implement necessary inprovemory 7 days Mon 22009 46 53 Determine signal lope and interfacing, choose a language 4 13 days Thv 1/1508 Fil 41708 54 Make PICs operational date signals.est 14 13 days Thv 1/1508 Mon 4/309 | 41 Mourt the column 10 days Int v1208 Int v12008 Int v12008
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| All Mount furn-table, test motor again 1/1/2 Thru 4/2/09 3/8 43 Mount furn-table, test motor again 1/1/2 Thru 4/2/09 3/8 43 Mount column to the furn-table, test motor again 1/1/2 Thru 4/2/09 3/8 44 Mount column to the furn-table, test motor again 1/1/2 Turu 4/2/09 4/2
 | Mount moto data implementation 0.98 days The #2005 The #2009 38 Mount motor and gens to base and turn-table, then test 3 days The #2009 174
d200 The #2009 38 Mount motor and gens to base and turn-table, then test 3 days The #2009 174 d200 The #2009 38
 | Income Income<

 | Mount turn-table 0.99 days Thu 4/200 10 42 Mount turn-table 0.99 days Thu 4/200 10 10 42/200 10 43 Mount column to the turn-table, test motor again 1 days Tur 4/200 10 10/200 10 44 Mount column to the turn-table, test motor again 1 days Tur 4/700 Tur 4/200 10 45 Mount encoder and test signal 1.01 days Tur 4/700 Tur 4/700 14/4000 (43 46 Test the column and evaluter and implement necessary improvem 5 days Thu 4/1000 Thu 4/1000 (45 47 Assemble and mount camera head 38.25 days Fil 2/2000 Thu 4/1000 (Tur 3/1200) (37 48 Mount encoders and lest signals 10 days Mou 4/200 Thu 3/1200 (Mount 4/100) (49 50 Mount encoders and lest signals 10 days Mou 4/1000 Mou 4/1000 Fil 4/1709 52 Write software and control 62 days Thu 1/1500 Mod 4/1709 Thu 1/1500 Mod 4/1700 53 Determine signal lype and interfacing, choose a l

 | 4 Mourt turn-table 0.99 days The 4/200 The 4/200 10 43 Mourt turn-table, test motor again 1 days The 4/200 The 4/200 10 44 Mourt column to the turn-table, test motor again 1 days The 4/200 Wed 4/800 4.3 45 Mourt column to the turn-table, test motor again 1 days The 4/200 The 4/200 He 44 Mourt column to the turn-table, test motor again 1 days The 4/200 The 4/200 Ha He 45 Mourt column to the turn-table, test motor again 1 days The 4/200 The 4/800 H3 The 4/200 Ha The 4/200 Ha <td>Mount turn-table 0.99 days Thu 4/209 Thu 4/209</td> <td>Mount turntable 0.9 days The 4/200 The 4/200 The 4/200 State <</td> <td>Mount turn-table 0.9 day Thu 4/200 Thu 4/200 Thu 4/200 Thu 4/200 State State</td> <td>42 Moart terretable 0.99 days The 4/200 The 4/200 State (11) 43 Moart motor and gears to base and turn-table, then test 3 days The 4/200 Yee 4/7/03 942 44 Moart column to the turn-table, test motor again 1 day Yee 4/7/03 Yee 4/7/03 942 45 Moart column to the turn-table, test motor again 1 days Tue 4/7/03 Weed 4/8/09 43 46 Moart ender and test signal 1 01 days Tue 4/7/03 The 4/8/09 43 47 Assemble and mount camera head 38.25 days Ftr 2/2009 Weed 4/8/09 45 48 Mount encoders and test signals 10 days Thu 3/1/209 70 70 49 Mount encoders and test signals 10 days Thu 3/1/209 Mon 4/8/09 40 50 Mount encoders and test signals 10 days Thu 3/1/209 Mon 4/8/09 40 51 Test the camera's motion capabilities, implement necessary improvemes 7 days Mon 4/8/09 Mon 4/8/09 41 43 53 Determine signal type and inte</td> <td>Mount structure 0.99 days The 4/200 The 4/200 Bit All 200 Bit All 200</td> <td>How the second second</td> <td>42 Moart turn table 0.99 days The 4/200 bit The 4/200 bit 43 Mourt motor and gears to base and turn-table, then test 3 days The 4/200 bit The 4/200 bit 44 Mourt column to the turn-table, test motor again 1 day Tur 4/200 bit Tur 4/200 bit 45 Mourt column to the turn-table, test motor again 1 day Tur 4/200 bit Tur 4/200 bit 46 Mourt ecoder and test signal 1.01 days Tur 4/200 bit Thu 4/200 bit 47 Assemble and mourt camera head 38.25 days Fri 122000 bit Tur 3/200 bit 48 Mourt ecoders and test signals 10 days Tur 3/200 bit Mon 2/200 bit 49 Mourt ecoders and test signals 10 days Tur 3/200 bit Mon 2/200 bit 50 Mourt ecoders and test signals 10 days Tur 3/200 bit Mon 2/200 bit 51 Test the camera's motion capabilities, implement necessary improv 7 days Mon 4/800 bit Mon 4/800 bit 52 Moart camera's motion capabilities, implement necessary improv 7 days Mon 4/800 bit Mon 4/800 bit</td> <td>Hourt turntable 0.9 days The 4/200 The 4/200 33 42 Mount motor and gears to base and turn-table, then test 3 days The 4/200 The 4/200 33 43 Mount column to the turn-table, test turnof again 1 day The 4/200 The 4/200 33 44 Mount column to the turn-table, test turnof again 1 day Tur 4/700 The 4/200 43 45 Mount column to the turn-table, test turnof again 1 day Tur 4/700 The 4/200 43 46 Mount column to the turn-table, test turnof again 1 days Tur 4/700 The 4/200 43 47 Assemble and mount camera head or pinon 1 days Tur 4/700 Thu 4/700 Thu 4/700 48 Mount encoders and test signals 1 days Thu 1/700 Mon 4/600 44 50 Mount encoders and test signals 1 days
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 | Mount turn-table 0.9 day Thu 4/200 Thu 4/200 Thu 4/200 Thu 4/200 State
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bit 45 Mourt column to the turn-table, test motor again 1 day Tur 4/200 bit Tur 4/200 bit 46 Mourt ecoder and test signal 1.01 days Tur 4/200 bit Thu 4/200 bit 47 Assemble and mourt camera head 38.25 days Fri 122000 bit Tur 3/200 bit 48 Mourt ecoders and test signals 10 days Tur 3/200 bit Mon 2/200 bit 49 Mourt ecoders and test signals 10 days Tur 3/200 bit Mon 2/200 bit 50 Mourt ecoders and test signals 10 days Tur 3/200 bit Mon 2/200 bit 51 Test the camera's motion capabilities, implement necessary improv 7 days Mon 4/800 bit Mon 4/800 bit 52 Moart camera's motion capabilities, implement necessary improv 7 days Mon 4/800 bit Mon 4/800 bit | Hourt turntable 0.9 days The 4/200 The 4/200 33 42 Mount motor and gears to base and turn-table, then test 3 days The 4/200 The 4/200 33 43 Mount column to the turn-table, test turnof again 1 day The 4/200 The 4/200 33 44 Mount column to the turn-table, test turnof again 1 day Tur 4/700 The 4/200 43 45 Mount column to the turn-table, test turnof again 1 day Tur 4/700 The 4/200 43 46 Mount column to the turn-table, test turnof again 1 days Tur 4/700 The 4/200 43 47 Assemble and mount camera head or pinon 1 days Tur 4/700 Thu 4/700 Thu 4/700 48 Mount encoders and test signals 1 days Thu 1/700 Mon 4/600 44 50 Mount encoders and test signals 1 days Thu 1/1500 Mon 4/600 44 51 Test the camera's motion capabilities, implement necessary improv 7 days Mon 4/600 Mod 4/1500 50 52 Withe softhware and control | Mount turnsble 0.99 days Thu 4/200 | 40 | Mount the column | 10 days | Thu 4/2/09 | Thu 4/16/09 | 1 35
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| 43 Mount motor and gears to base and turn-table, then test 3 days Thu 4/2/09 Tue 4/7/09 42 44 Mount column to the turn-table, test motor again 1 day Tue 4/7/09 Wed 4/8/09 43
 | Mount motor and gears to base and turn-table, then test 3 days Thu 4/2/09 Tue 4/7/09 42

 | 43 Mourt motor and gens's to base and turn-table, them test 3 days Thu 4/2009 Tue 4/700 Fue 4/700 42 44 Mourt column to the turn-table, test motor again 1 day Tue 4/700 Tue 4/700 42 45 Mourt encoder and test agraal 1.01 days Tue 4/700 Tue 4/700 43 46 Test the column and evalues and implement necessary improvem 5 days Thu 4/800 43 47 Assemble and mount camera head 38.25 days Fti 2/2000 Thu 4/800 43 48 Mourt encoder and test agraal 1.01 days Fti 2/2000 Thu 4/800 43 49 Mourt encoder and test signals 1.01 days Thu 1/300 Thu 1/300 32 50 Mourt encoders and test signals 10 days Thu 1/300 Mon 4/300 43 51 Test the camera's motion capabilities, implement necessary improv 7 days Thu 1/300 Fti 4/1308 50 52 Determine signal type and interfacing, choose a language 4.13 days Thu 1/300 Fti 4/1308 55 54 <t< td=""><td>43 Mourt motor and gents to base and turn-table, then test 3 days Thu 4/200 Tue 4/700 rue 4/400 ref 44 Mourt column to the turn-table, test motor again 1 days Tue 4/700 Tue 4/400 ref 45 Mourt column to the turn-table, test motor again 1 days Tue 4/700 Tue 4/400 ref 46 Mourt column to culturate and implement
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D Budget

The budget alotted includes the money provided by the department, \$1200.00, and the IEEE grant money, \$1500.00. When purchases included many small parts, such as electronics and nuts and bolts, the total purchase amount is a combination of all the items.

Income					
Date	Sponsor	Description	Budgeted Amount		Actual Amount
9/1/2004	Engr Dept	Seed Money		\$1,200.00	\$1,200.00
11/9/2004	IEEE	Grant Money		\$1,500.00	\$1,500.00

Total Income

\$2,700.00

Expenses						St	atus (Check	one)
Date	Vendor	PO #	Item Description	Status (Planned/ Pending/ Cleared)	Amount	Dept PO	PCARD	Reimbu rse ment
12/3/2008	Servo City	DDT560H	Direct Drive Cradle Tilt	Cleared	\$49.99		Х	
12/3/2008	Servo City	GDP785A-BM	Gear Drive Pan System	Cleared	\$60.00		Х	
12/3/2008	Servo City	33785S	HS-785HB Servo (Universal Connector)	Cleared	\$39.99		х	
12/3/2008	Servo City	32985S	HS-985MG Servo (Universal Connector)	Cleared	\$72.99		X	
12/3/2008	Servo City	5445	180 Rotation Modfication	Cleared	\$10.00		Х	
12/3/2008	Servo City	902MSD	Dual Manual Servo Controller	Cleared	\$49.99		х	
12/3/2008	Servo City	418-TR1506-12	6VDC, 1.5amp Linear Power Supply (2.5mm plug)	Cleared	\$24.99		Х	
12/3/2008	Servo City	180SS	180 Servo Stretcher	Cleared	\$19.99		х	
12/15/2008	RobotEQ	AX1500	Cost Optimized, 2 x 30A Brushed DC Motor	Cleared	\$288.00		Х	
12/15/2008	SparkFun Electronics	COM-00226	PIC 40 Pin 20MHz 8K 8A/D- 16F877A+shipping	Cleared	\$66.05		х	
12/15/2008	SparkFun Electronics	DEV-07830	Ethernet Web PIC+shipping	Cleared	\$55.35		Х	
12/15/2008	Monsterscooterparts	MOI-385	36V 1000W Direct Drive Electric Motor & Rear Wheel	Cleared	\$384.32		х	
12/15/2008	Servo City	6031K19	12" Ball Bearing Turntable	Cleared	\$25.90		Х	
1/15/2009	Robotmarketplace	SP-40FB19x.875	1/2 pitch Type B Sprocket-19 teeth, 7/8' bore+shipping	Cleared	\$23.93		Х	
1/15/2009	Robotmarketplace	CHA-40-HALF	#40 Roller Chain-10ft length+shipping	Cleared	\$13.40		X	
1/15/2009	Robotmarketplace	CHA-40-10	4, #40 Roller Chain offset link+shipping	Cleared	\$36.50		X	
1/15/2009	Bearing Agencies	BP5100850-20	DeWalt Motor/Gearbox+shipping	Cleared	\$56.99		Х	
1/15/2009	Mouser Electonics	AEAT-6010-A06	4 10 bit ABS Magnetic Encoder	Cleared	\$111.72		X	
1/22/2009	Triple S Steel		1'x1' 11 GA. X 24' Square Tubing	Cleared	\$26.40			Х
1/22/2009	The Home Depot	99167212838	18MMBirch	Cleared	\$26.56			Х
2/25/2009	Intertex Electronics		Micellaneous Electronics	Cleared	\$8.06			Х
2/26/2009	McMaster Carr	1710K4	3/4"-5 Platform Nut+shipping	Cleared	\$129.25		х	

2/26/2009	McMaster Carr	98940A361	3/4"-5 Acme 6' Rod+shipping	Cleared	\$113.90		Х	
2/26/2009	Digi-Key		Micellaneous Electronics	Cleared	\$26.71			Х
3/24/2009	Autozone	298374	24MD-DL Duralast Marine Deep Cycle Battery	Cleared	\$62.99			х
3/24/2009	Autozone	298374	Core Charge	Cleared	\$12.00			Х
3/24/2009	Autozone	570475	2 Duralast 4GA 19" Switch Starter Battery Cables	Cleared	\$8.98			Х
3/24/2009	Walmart	3399100211	FSD Dist. Block	Cleared	\$9.82			Х
3/24/2009	Purvis Industries	203PP030867	Fafnir	Cleared	\$22.70			Х
3/25/2009	Grainger	4PU79	2 Bearing, 3/4 In Bore	Cleared	\$117.28			Х
3/25/2009	The Home Depot		Tower Construction Misc. Parts	Cleared	\$20.00			Х
3/25/2009	Lowe's		Tower Construction Misc. Parts	Cleared	\$56.50			Х
3/29/2009	Robotmarketplace	SH-X-1400-RL	18 7/8" diameter keyed shaft+shipping	Cleared	\$46.59			Х
3/29/2009	Robotmarketplace	KEY-407-0300	3/16" key stock 12" long (shipping included above)	Cleared	\$2.87			x
3/29/2009	Lowe's		Tower Construction Misc. Parts	Cleared	\$46.41			X
3/29/2009	Home Depot		Tower Construction Misc. Parts	Cleared	\$28.18			х
4/1/2009	Intertex Electronics	IHD12.6.8	1x12V 6.8A Linear Power Supply	Cleared	\$08.03	v		v
4/1/2009	Robotmarketplace	IHD12-0.8	Georing	Cleared	\$96.03	л V		A V
4/1/2009	The Home Depot		Tower Construction Miss Parts	Cleared	\$17.89	Λ		x
4/1/2000		27501	CGJ General Safety Switch	Closed	\$20.02			v
4/1/2009	Sall & Ski Center	27501	w/lanyard	Cleared	\$20.95	••		<u>л</u>
4/1/2009	Intertex Electronics		Micellaneous Electronics	Cleared	\$53.92	Х		X
4/1/2009	Monsterscooterparts		24V 450W Electric Motor	Cleared	\$83.66	Х		X
4/1/2009	RoboteQ	AX500 SC	AX500 SC	Cleared	\$158.00	Х		Х
4/1/2009	Digi-Key	TLE 5205-2IN-ND	TO220-7	Cleared	\$7.57			Х
4/1/2009	Donated by Andy		Misc Used Electronic Parts	Cleared	\$1.00			
4/1/2009	Borrowed from Andy		Playstation Controller	Cleared	\$14.99			
4/1/2009	Donated by TU		Scrap Metal	Cleared	\$0.00			
4/1/2009	TU Engineering Dept		330 ohm resistor	Cleared	\$0.20			
4/1/2009	TU Engineering Dept		1.5k ohm resistor	Cleared	\$0.10			
4/1/2009	TU Engineering Dept		1 uF capacitor	Cleared	\$0.40			
4/1/2009	TU Engineering Dept		16 pin socket	Cleared	\$0.35			
4/1/2009	TU Engineering Dept		22 ga Wire (ft)	Cleared	\$2.00			
4/1/2009	TU Engineering Dept		DB9 male connector	Cleared	\$0.70			
4/27/2009	Ginny's		Final Report	Pending	\$ 26.28			

Total Expenses

Donations Budget Remaining

\$35.75

\$2,680.24 \$15.99

E Bill of materials & list of vendors

The bill of materials (BOM) serves as an itemized list of all the materials required to fabricate the design. The vendor from which the item was purchased is in the left most column; the contact information for all vendors is found following the BOM.

Vendor	PO #	Item Description	Qty.	Cost		Subtotal
Autozone	298374	24MD-DL Duralast Marine Deep Cycle Battery	1	\$74.99	per piece	\$74.99
Autozone	570475	Duralast 4GA 19" Switch Starter Battery Cables	2	\$4.49	per piece	\$8.98
Bearing Agencies	BP5100850-20	DeWalt Motor/Gearbox+shipping	1	\$56.99	per piece	\$56.99
Donated by Andy		8 pin connector	1	\$0.05	per piece	\$0.05
Donated by Andy		4 pin connector	1	\$0.05	per piece	\$0.05
Donated by Andy		3 pin connector	2	\$0.05	per piece	\$0.10
Donated by Andy		8 gauge wire (ft)	5	\$0.45	per piece	\$2.25
Donated by Andy		Playstation Controller	1	\$14.99	per piece	\$14.99
Grainger	4PU79	Bearing, 3/4 In Bore	2	\$58.64	per piece	\$117.28
Intertex Electronics	ST-40	40 pin IC socket	3	\$0.75	per piece	\$2.25
Intertex Electronics	CY20	20 MHz crystal	3	\$2.95	per piece	\$8.85
Intertex Electronics	7805T	5V Voltage Regulator	2	\$1.75	per piece	\$3.50
Intertex Electronics		100 uF capacitor	2	\$0.25	per piece	\$0.50
Intertex Electronics		10uF capacitor	2	\$0.20	per piece	\$0.40
Intertex Electronics	MAX232N	RS232/TTL Level Shifter	1	\$1.35	per piece	\$1.35
Intertex Electronics		22 pF capacitor	6	\$0.25	per piece	\$1.50
Intertex Electronics	1N4007	1N4007 diode	2	\$0.45	per piece	\$0.90
Intertex Electronics		9 conductor ribbon cable (ft)	15	\$0.15	per piece	\$2.25
Lowes		1/2"x72" Black Steel Pipe	2	\$12.17	per piece	\$24.34
Lowes		1/2" Floor Flange	4	\$3.27	per piece	\$13.08
McMaster Carr	1710K4	3/4"-5 Platform Nut+shipping	1	\$129.25	per piece	\$129.25
McMaster Carr	98940A361	3/4"-5 Acme 6' Rod+shipping	1	\$113.90	per piece	\$113.90
Monsterscooterparts	MOI-385	36V 1000W Direct Drive Electric Motor & Rear Wheel	2	\$192.16	per piece	\$384.32
Monsterscooterparts		24V 450W Electric Motor	1	\$83.66	per piece	\$83.66
RoboteQ	AX500 SC	AX500 SC Controller	1	\$158.00	per piece	\$158.00
RobotEQ	AX1500	Cost Optimized, 2 x 30A Brushed DC Motor	1	\$288.00	per piece	\$288.00
Robotmarketplace	SP-40FB19x.875	1/2 pitch Type B Sprocket-19 teeth, 7/8' bore+shipping	1	\$23.93	per piece	\$23.93
Robotmarketplace	SH-X-1400-RL	18 7/8" diameter keyed shaft+shipping	1	\$46.59	per piece	\$0.00
Robotmarketplace	KEY-407-0300	3/16" key stock 12" long (shipping included above)	1	\$2.87	per piece	\$0.00
Robotmarketplace	CHA-40-HALF	#40 Roller Chain-10ft length+shipping	1	\$13.40	per 10ft length	\$13.40
Robotmarketplace	CHA-40-10	#40 Roller Chain offset link+shipping	1	\$9.13	per piece	\$9.13
Robotmarketplace	CHA-25-10	#25 Roller Chain-10ft length+shipping	1	\$24.75	per 10ft length	\$24.75
Robotmarketplace	CHA-25-CONN	Roller Chain connecting link	2	\$1.00	per piece	\$2.00

Vendor	PO #	Item Description	Qty.	Cost		Subtotal
Robotmarketplace	SP-25FB	20x.75 1/4 pitch Type B Sprocket-20 teeth, 3/4 inch bore	1	\$24.38	per piece	\$24.38
Sail & Ski Center	27501	CGJ General Safety Switch w/lanyard	1	\$20.93	per piece	\$20.93
Servo City	6031K19	12" Ball Bearing Turntable	1	\$25.90	per piece	\$25.90
Servo City	DDT560H	Direct Drive Cradle Tilt	1	\$49.99	per piece	\$49.99
Servo City	GDP785A-BM	Gear Drive Pan System	1	\$60.00	per piece	\$60.00
Servo City	337855	HS-785HB Servo (Universal Connector)	1	\$39.99	per piece	\$39.99
Servo City	329855	HS-985MG Servo (Universal Connector)	1	\$72.99	per piece	\$72.99
Servo City	5445	180 Rotation Modfication	1	\$10.00	per piece	\$10.00
Servo City	902MSD	Dual Manual Servo Controller	1	\$49.99	per piece	\$49.99
Servo City	418-TR1506-12	6VDC, 1.5amp Linear Power Supply (2.5mm plug)	1	\$24.99	per piece	\$24.99
Servo City	180SS	180 Servo Stretcher	1	\$19.99	per piece	\$19.99
Sparkfun Electronics	PIC 16F877A	Microcontroller	3	\$8.95	per piece	\$26.85
The Home Depot		1/4"-20x1" Flat Head Slotted Acero Inoxidable	8	\$0.98	pkg 2	\$7.84
The Home Depot		#6-32x1/2" Round Head Slotted	8	\$0.36	per piece	\$2.88
The Home Depot		4x8 18MMBirch	2	\$13.28	per piece	\$26.56
The Home Depot		1/4"- 20x2" Hex bolts	2	\$4.28	pkg 25	\$8.56
The Home Depot		1/4" Hex Nut/Coarse Thread	1	\$5.77	pkg 100	\$5.77
The Home Depot		6-32x1-1/4" Combo Round w/Nut	1	\$1.18	pkg 10	\$1.18
The Home Depot		Angle Gauge-3'	1	\$8.97	per piece	\$8.97
Triple S Steel		1'x1' 11 GA. X 24' Square Tubing	1	\$26.40	per 20ft length	\$26.40
TU Engineering Dept		330 ohm resistor	2	\$0.10	per piece	\$0.20
TU Engineering Dept		1.5k ohm resistor	1	\$0.10	per piece	\$0.10
TU Engineering Dept		1 uF capacitor	5	\$0.08	per piece	\$0.40
TU Engineering Dept		16 pin socket	1	\$0.35	per piece	\$0.35
TU Engineering Dept		22 ga Wire (ft)	20	\$0.10	per piece	\$2.00
TU Engineering Dept		DB9 male connector	2	\$0.35	per piece	\$0.70
TU Engineering Dept		1/8"x 2 1/2"x 8"Steel Plate-Scrap Metal	2	\$0.00	per piece	\$0.00
Walmart	3399100211	FSD Dist. Block	1	\$9.82	per piece	\$9.82

Autozone

2223 Blanco Rd San Antonio TX 78212 (210) 737-1255 http://www.autozone.com

Bearing Agencies Inc.

277 7th St San Francisco, CA 94103 (415) 621-8363 Fax: (415) 621-7239

Digi-Key Corporation

701 Brooks Avenue South Thief River Falls, MN 56701 USA (800) 344-4539 Fax: (218) 681-3380 http://www.digikey.com

Grainger

5011 Rittman Rd. San Antonio, TX 78218-4638 (210) 654-4020 <u>http://www.grainger.com</u>

Intertex Electronics 1200 W.Hildebrand San Antonio,TX 78201 (800) 820-3908 Fax: (210) 820-3344 http://www.intertexelectronics.com

Lowe's 1470 Austin Highway San Antonio, TX 78209 (210) 828-6011 Fax: (210) 828-3866 http://www.lowes.com

McMaster Carr

200 New Canton Way Robbinsville, NJ 08691-2343 (609) 689-3000 Fax: (609) 259-3575 http://www.mcmaster.com

Monsterscooterparts

26262 Three North Road Unit 6 Mechanicsville, MD 20659 (800) 798-0325 http://www.monsterscooterparts.com

The Home Depot

435 Sunset Rd West San Antonio, TX 78209 (210) 824-9677 http://www.homedepot.com

Purvis Industries 611 N. WW White Road (210) 299-1010 FAX (210) 226-1790 http://purvisindustries.com

RobotEQ 8426 E. Shea Blvd. Scottsdale, AZ 85260 (602) 617-3931 http://www.roboteq.com/

Robot Market Place 5129A 53rd Avenue East Bradenton, FL 34203 1-877-ROBOT 99 Fax#(941) 753-5113 http://www.robotmarketplace.com Mouser Electronics 1000 North Main Street

Mansfield, TX 76063 (800) 346-6873 Fax: (817) 804-3899 http://www.mouser.com

Servo City 620 Industrial Park Winfield, KS 67156 (620) 221-0123 Fax : (620) 221-0858

www.servocity.com Triple S Steel 2042 Thompson Pl San Antonio, TX 78226

(210) 431-0088 Fax: (210)431-0701

http://www.sss-steel.com

Trinity University 1 Trinity Place San Antonio, TX 78212 (210) 999-7511 Fax#:(210) 999-8037 www.trinity.edu

Sail & Ski Center

141 Balcones North San Antonio, TX 78201 USA (210) 734-8199 Fax: (210) 734-8130 http://www.sailandski.com

Walmart

1430 Austin Highway San Antonio (E), TX 78209 (210) 637-1700 http://www.walmart.com

SparkFun Electronics

6175 Longbow Dr. Suite 200 Boulder, CO 80301 (303) 284-0979 Fax: (303) 443-0048 http://www.sparkfun.com