

Project Plan

1 General Information

1. Project Name: IGVC - Intelligent Ground Vehicle Competition
2. Team members:
 - Viet Dung Nguyen (CSE) (dnguyen2016@my.fit.edu)
 - Jinwen Zhang (jzhang2015@my.fit.edu)
 - John Light (jlight2016@my.fit.edu)
 - Sijin Yang (yangs2017@my.fit.edu)
 - Peter Tarsoly (ptarsoly2016@my.fit.edu)
3. Faculty Sponsor: Dr. Marius Silaghi
4. Client: Dr. Ken Gibbs
5. Meetings with the Client:
 - 08/30/2019

2 Goal and Motivation

The goal of the project is to build an unmanned autonomous robot to compete in IGVC in Michigan. The objective of the competition is to have the robot complete an outdoor obstacle course under a prescribe time within the speed limit of 1-5 mph while remaining on the lane and avoiding obstacles.

3 Approach:

The key features of the software components are:

- Lane detection

- Obstacle detection and avoidance
- Mapping
- Motion planning

The robot must be able to follow the path specified by the competition. The boundary of this path will be illustrated by dashed or continuous white lines. Lane detection is necessary for the robot to detect these boundaries.

Within the course, there will be natural and artificial obstacles. Obstacle detection and avoidance allow the robot to detect obstacles and move around them. Avoiding obstacles is a key factor of the competition.

Mapping let the robot construct a virtual map of the obstacle course using the data from lane detection and obstacle detection. With mapping, the robot can remember the collected data and avoid redundant data collection. In addition, the robot can remember the where it has been and avoid backtracking.

Motion planning is a crucial feature of the robot. Using motion planning, the robot can construct the shortest path to the checkpoints from the data illustrated in the map. Efficient motion planning is essential for finishing the course in time.

4 Technical Challenges:

- Legacy code is not well documented.
- Motion planning is not implemented
- Team members have no experience with Arduino.
- Team members have no experience with lane and obstacle detection.

5 Milestone 1:

- Examine the legacy code in order to reuse.
- Examine the options available for motion planning.
- Establish best practices (code format, document style) for the project.
- Create requirement document
- Create design document
- Create test plan

6 Milestone 2:

- Implement automated testing.
- Refactor the legacy code.
- Test for regression.

7 Milestone 3:

- Implement and test motion planning.

8 Approval from Faculty Sponsor:

- I have discussed with the team and approve this project plan. I will evaluate the progress and assign a grade for each of the three milestones."

Signature

Date