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Group Project

**First Demonstration & Presentation Assessment Sheet**

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| **Group Name/Student Names: Group B****Supervisor: Dr Neil Cooke** |

The following sections are intended to provide feedback about your performance.

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| **Presentation Skills (25% of overall mark)** | 1+ | 1- | 2.i+ | 2.i- | 2.ii+ | 2.ii- | Fail |
| *Presentation, visual aids, etc.* |  |  |  |  | x |  |  |

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| **Technical Progress to Date (50% of overall mark)** | 1+ | 1- | 2.i+ | 2.i- | 2.ii+ | 2.ii- | Fail |
| *Demonstration of hardware built, software written, equations, etc.* |  |  |  | x |  |  |  |

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| **The Future (25% of overall mark)** | 1+ | 1- | 2.i+ | 2.i- | 2.ii+ | 2.ii- | Fail |
| *Technical merit of proposals for completing the project. Adequacy and appropriateness of workplan.* |  |  |  |  |  | x |  |

Total grade allocated [in 1+,1-,2.i+,2.i-,2.ii+,2.ii-,F]: 2ii+ .

# Comments And Advice

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| Rather a brief presentation but good use of visual aids overall. Some good technical progress and a moving platform constructed. Your idea about fixing the camera to the platform is interesting but it is not consistent with doing background subtraction to detect the boundaries of the broom. However, you should be able to think of a way round this issue. The demonstration of measuring the angle involved the use of the Hough transform. This is a tricky algorithm to tune and you might be able to think of a simpler more robust approach. You gave a good account of the inverted pendulum control algorithm but you didn’t say how this translated to the design of the control system.You briefly discussed future development plans but not much mention of how you planned to use the outputs of both cameras in your control algorithm. You also said little about system integration which will form a major part of next semesters work. |
| Project Team Assessor(s): MS, ES, NC Date: 10/12/13 |