TEAM 8

PROJECT 3

TEAM ORGANIZATION EVALUATION AND PLANS.

Date: May 2, 2003.
Josh Guice
Neelam Chauhan
Troy Humphrey
Mark Woehrer

Objective.

We are required to submit a document evaluating our team based on how well our team organization worked and our future plans depending the conclusion derived from this evaluation.

Overall appraisal.

Our aim, with the assigned team organization and task allocation, was to improve our performance than the previously demonstrated project. From the previous projects we concluded that it was difficult to solve differences between the peers. To solve this problem we modified the team organization by having the concept of a team-leader, who we selected by voting. He was responsible for the following tasks:

1. Solve any differences that arose between other team members.
2. Make a decision when more than one options were available.
3. Assign tasks to other team members.
4. Last but not the least, come up with a plan if things do not go as scheduled.

This organization worked well for us for several reasons stated as following:

1. There was no confusion about the task assignment since team leader, as required, assigned the tasks.

2. There was a team-leader to decide on the timings for meetings, which was a big problem before since no times were convenient for all.

Overall, our performance was satisfactory since we did not score any negative points. For this project we had great ideas and good design/model but at the end we ran out of time to implement all the goodies. Our intention was to make the robot intelligent enough to look in its World Model for the clues. As it can be seen from our other documentations, mainly hardware and software documentations, we had a strong base for success. We started off very well but later on, one of our team members could not contribute towards the project and that hindered our progress.

Modifications needed?

We unanimously agree that this team organization worked well for us, so we do not plan to change the team organization for future projects, but we would change the allocation of tasks to the members and shuffle the people around to different areas (hardware/software).

Final word.

Even though we are not completely satisfied with our demonstration, we would say that it went well with the class since there are some teams who scored negative points. After this project, we realize that for the robot to be intelligently autonomous, the most important (and most challenging) issue to deal with is getting important information from the World Model and also simultaneously keeping track of the sensory information too.