**Presentation of problem:**
We have chosen the project rough terrain, which is a part of the IT project HUGE. Their project is about developing an autonomous rescue robot, which main purpose is to localize victims in a simulated environment. This project has been ongoing for several years and one of their main problems has been the motor control. This problem has been outsourced to our group, with more knowledge in automatic control. Some of the main problems is the listed below:

- The robot can't identify when sliding occurs.
- The robots emergency brake is not implemented.
- etc.

Our solution is based on using more information for the feedback loop, e.g. current consumption, gyro etc.

**Accomplished so far:**
We have set up the development environment, and are currently waiting for one more computer. We have discussed the problems with the IT-group and received information and documents about their project and the motor control card. We are suppose to get our own stripped robot with only the important features, such as wheels and motor control card. This has not happened yet, due to problems with assembling the parts. Hopefully we can begin our testing on wednesday 18/2. We have also started to study the C-code for the motor control.

**Action points for next week:**
1. Receive the stripped robot.
2. Understand the CAN-bus system and begin working with AVR Studio.
3. Understand the old code.
4. Simulate the problem and state a problem description.

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