	Customer Requirements	Engineering Requirements	Backup Control System	Controller Range	Controller Logic to Control Motors	Drift When Stationary	Drop Height Survivability	Functional Rotational Speed	Heading Deviation	Invertible	Max Rotational KE Stored	Modular	Shock Load Resistance	Spin Up Time to 60% KE	Weight	Completed
1.1	A translational drift style combat robot of a standard weight class														I	yes
2.1	Robot will use absolute positioning to determine heading (no LED front)								I							no
2.2	Accurate in determining heading															no
2.3	Stable when stationary					I		I		I	I					yes
1.2	Robot and system should be reasonable able to compete in and survive a match with another combat robot			I			I	I					I	I		no
3.1	The system should be easily modifiable to adapt to other size robots											I				yes
3.2	The control system should be able to run in standard relative (LED front) mode should the absolute positioning system fail		I													yes
2.4	The controller should also determine its orientation in the same way as the robot so the robot effectively drives based on the orientation of the controller		I	I	I											no