

ACM @ Purdue

President: Logan Gore



Purdue Chapter
Association for Computing Machinery

Who we are

SIGAPP

SIGART



siggd

SIG
SAC



Learning with large projects

Community Service Award

National ACM Award

Work with official Purdue app



PROS: used by over 2000 teams worldwide



High School Coding Competition

Probably our most exciting event of the year

29 teams competed at Purdue

Similar to official ACM-ICPC format

Students had a blast

ExactTarget 24 Hour Hackathon

Smaller hackathon for Purdue students only

About 10 teams competed

Fun event in the “Hackathon off-season”

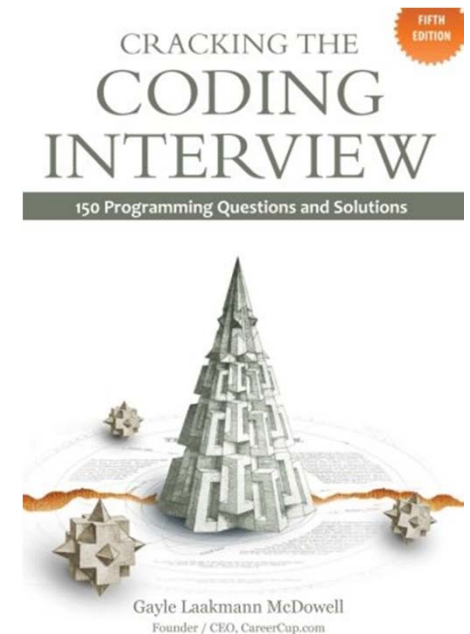


Interview Night with USB

Roughly 30 students

Mostly freshmen and sophomores

Focus on technical side of interviews



Isilon Student Appreciation

End-of-semester party in the Fall
Cookie party for CS252 class after first exam



What's next?

500 Miles Tech Talk
SMU Guildhall Tech Talk
More interview prep
Some more focus on hackathons

500 Miles





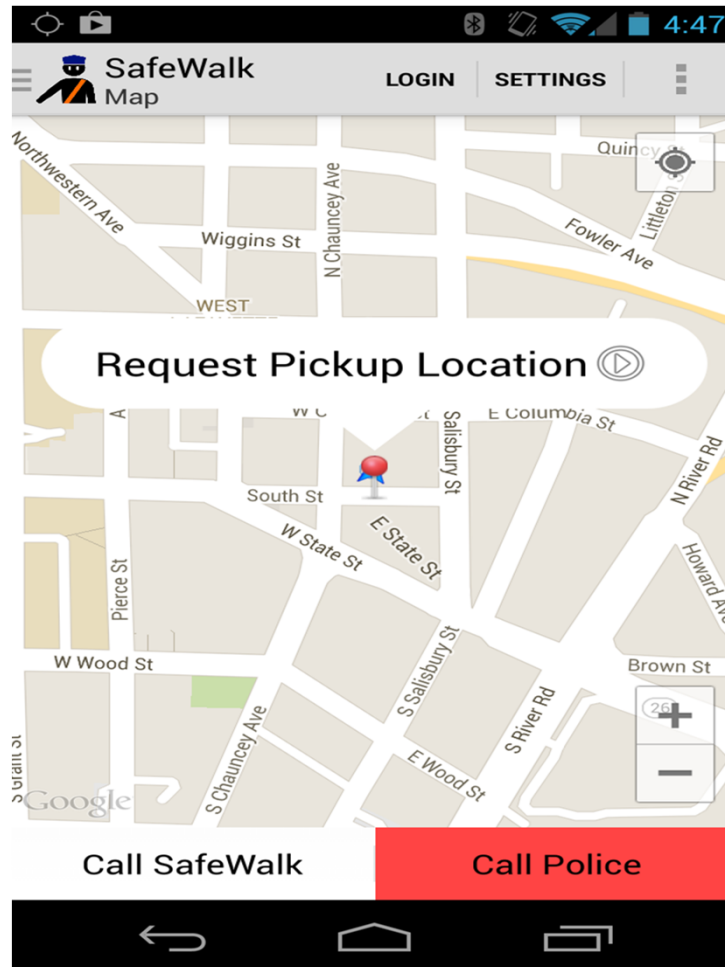
Applied Computer Science

Eric Templin

David Tschida

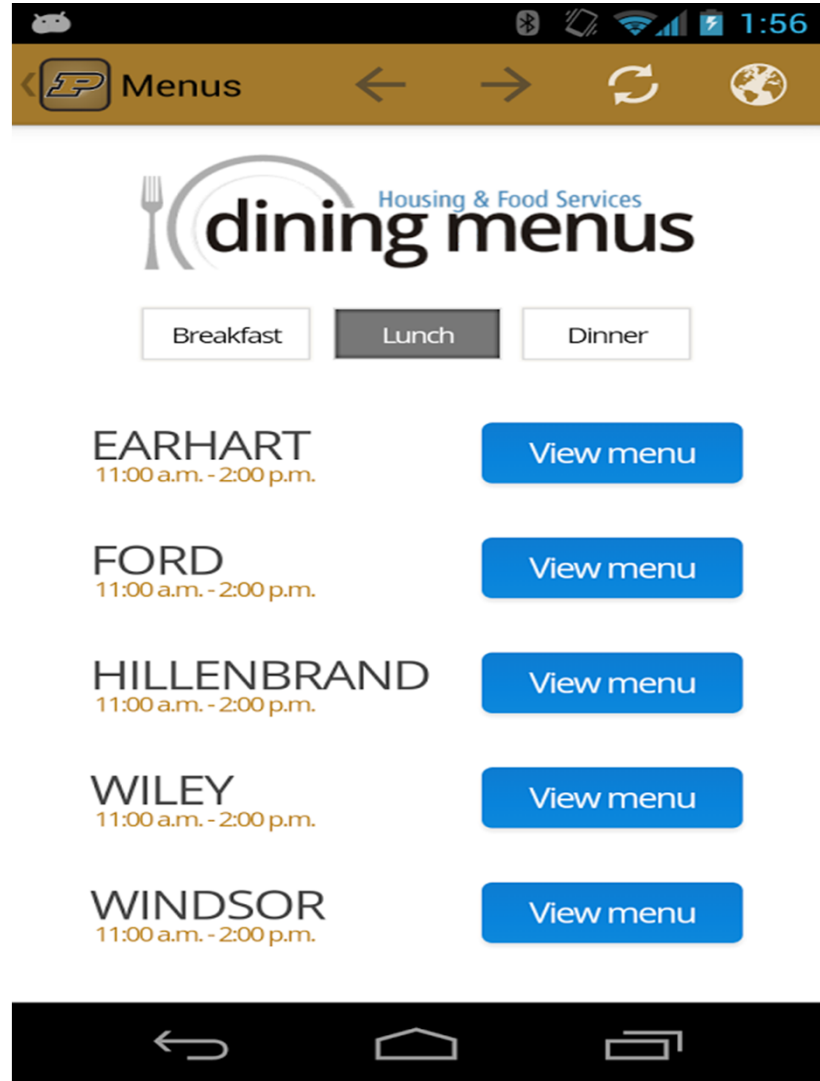
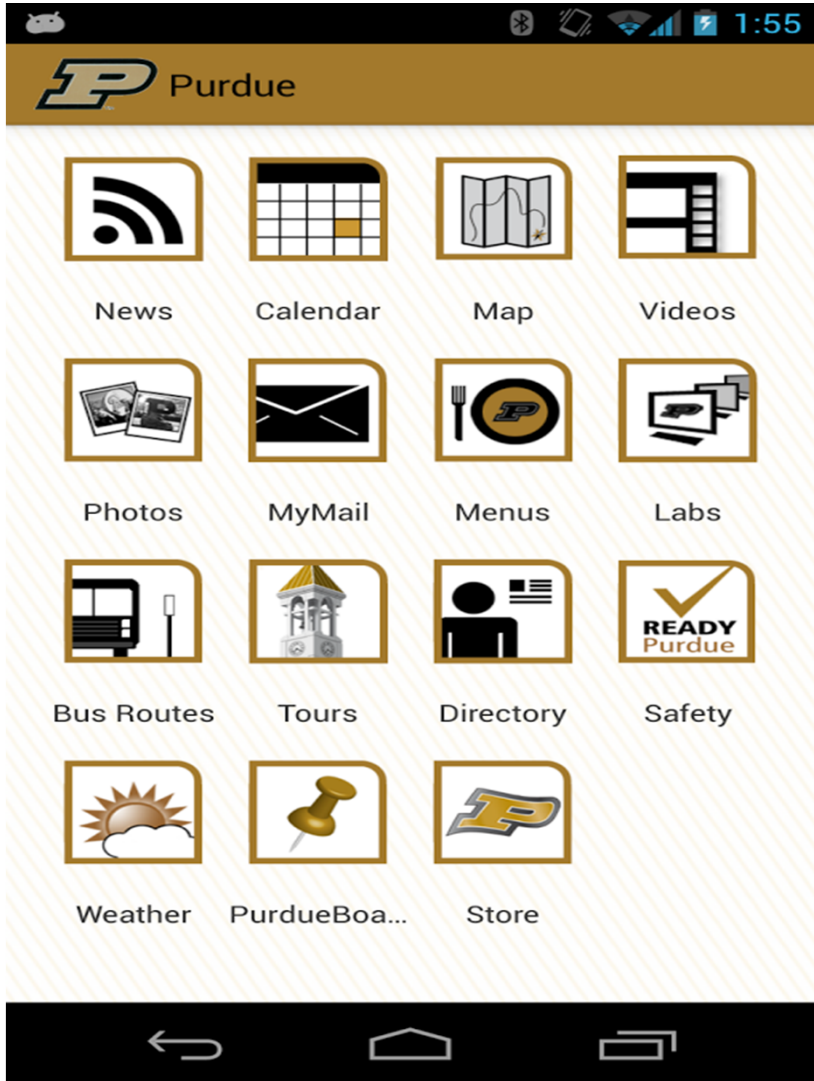
Michael Hockerman

SafeWalk



Purdue App

The image shows a screenshot of the Google Play Store page for the 'Purdue' app. At the top, the Google Play logo and search bar are visible. The app's name 'Purdue' is prominently displayed next to its logo, which is a stylized 'P' in gold and blue. Below the name, it says 'Purdue University - August 25, 2014' and 'Education Education'. There are 'Install' and 'Add to Wishlist' buttons. A note states 'This app is compatible with your device.' Below that, there are star ratings and a '+3 Recommend this on Google' button. On the left, a navigation menu is open, showing 'My apps', 'Shop', 'Games', and 'Editors' Choice'. At the bottom, four preview images show the app's interface: a home screen with various utility icons, a 'dining menus' screen with a list of campus locations and 'View menu' buttons, a 'Map and building information' screen with a map, and a 'Bus Routes' screen with a map showing routes.



This year

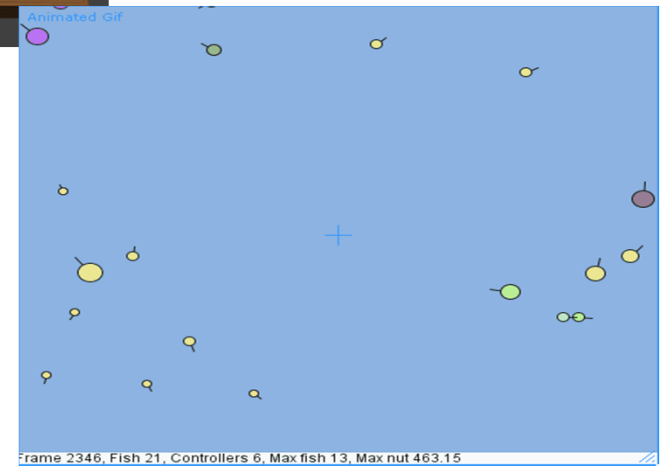
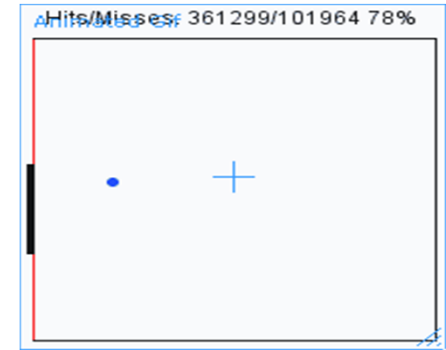
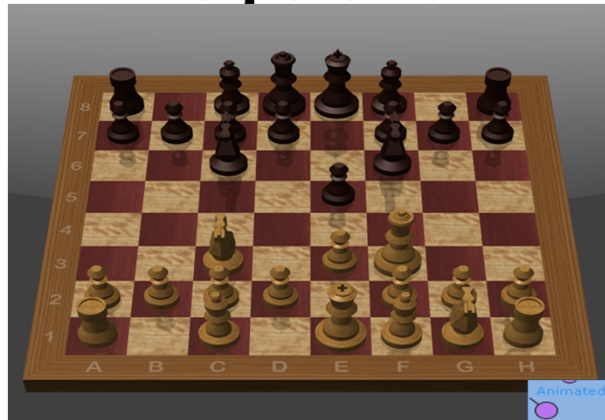
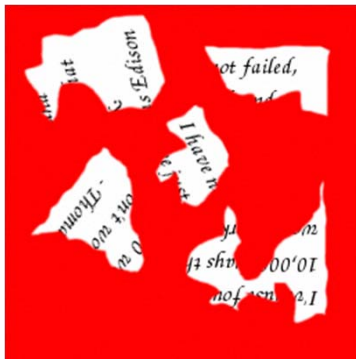
- Tutorials
Android, iOS, Web Service Development,
GoLang, NodeJS, and more
- Made Purdue app fully native
- Redesigned backend components of Safewalk

SIGART

Artificial Intelligence

Special Interest Group for Artificial Intelligence

Projects



This semester

- Chess AI competition sponsored by Interactive
- Teams competing against each other




siggd

Lee Anne Opfer, President

Game Developer's Conference

First time in SIGGD's history

Great experience to see unique ideas

Hoping to send more members next year

Game Jam

36 hour hackathon

Teams of 3

Used Unreal Engine 4
to quickly prototype games



SIG
SAC



Matthew Gotteiner, President

SIGSAC

Reverse engineering binaries in Linux

Capture the Flag

Cryptocurrency seminars

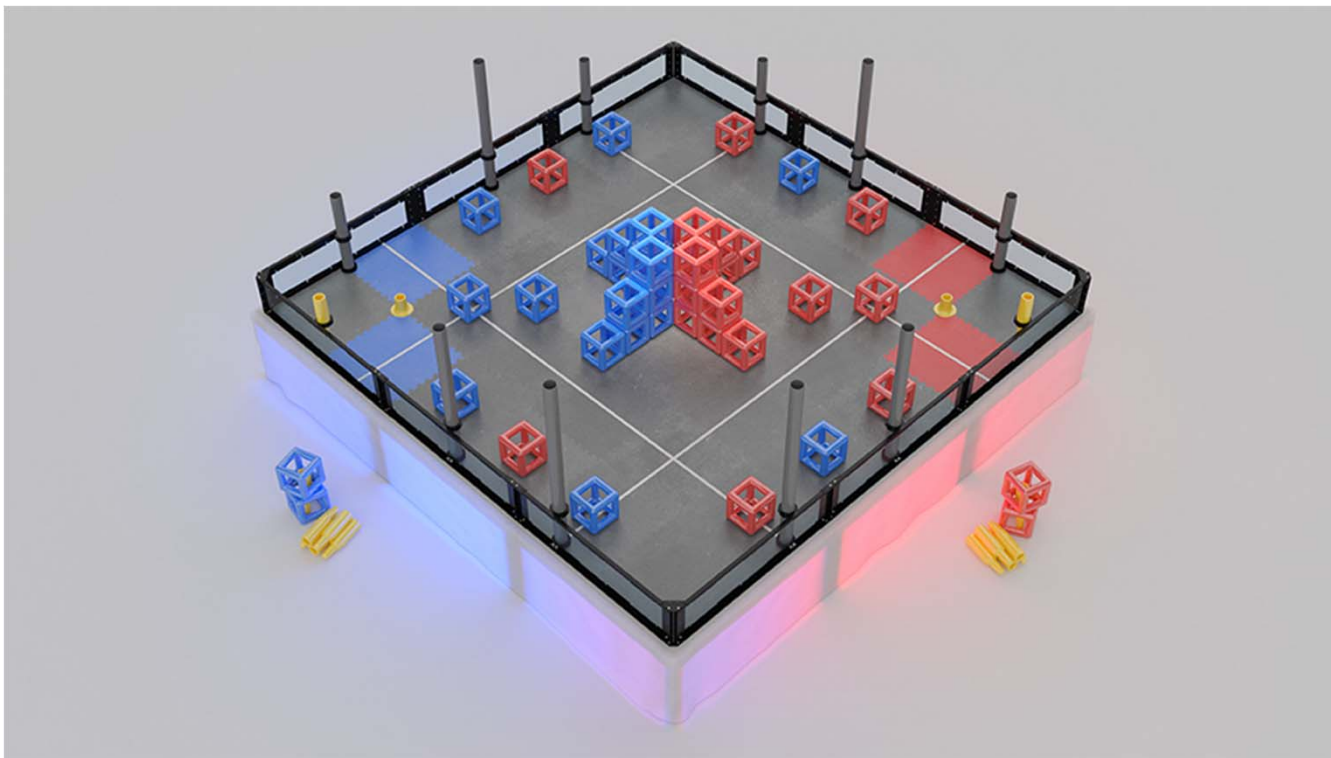
Network security



SIGBOTS



VEX Skyrise



Major Goals

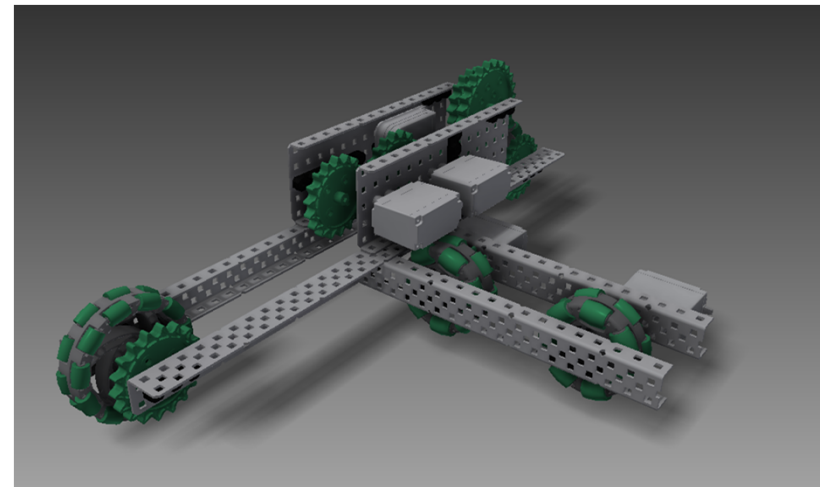
- Create mechanical reusability
- Increase reliability through controls
- Fine tune software with rapid prototyping
- Develop inter-robot communications

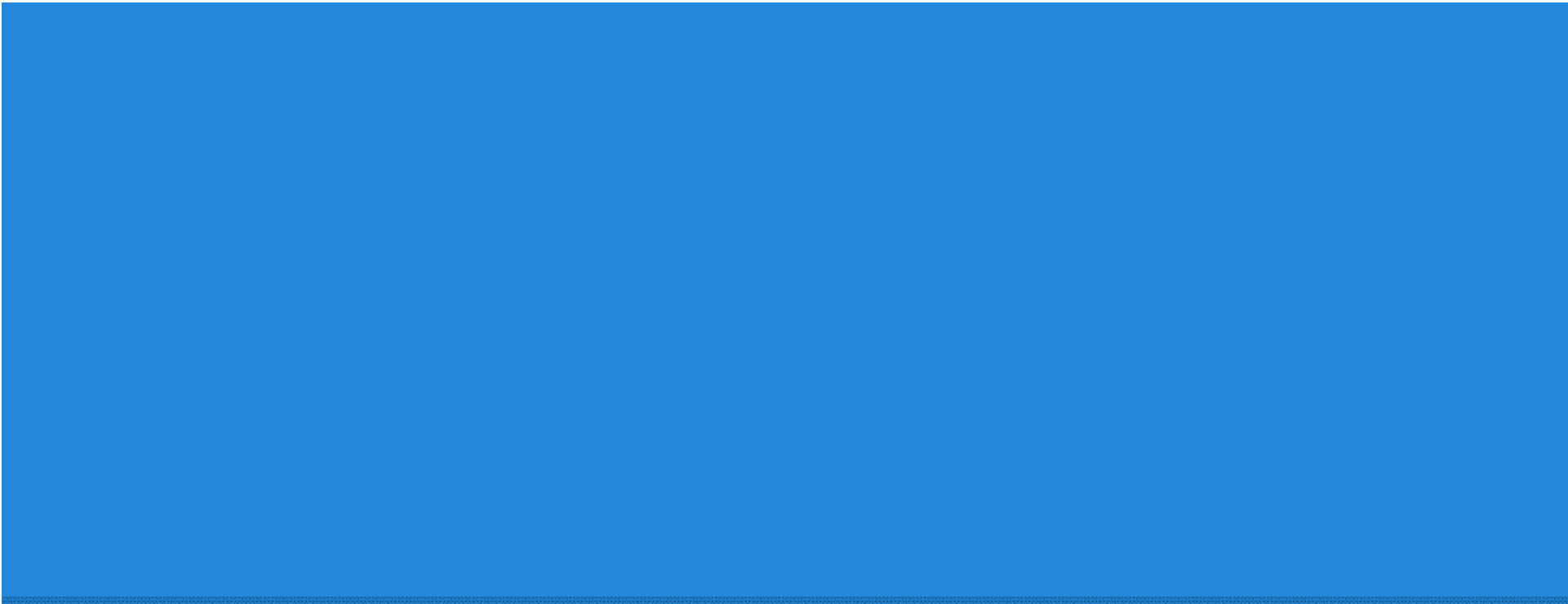


Mechanical Reusability

Configurable Drivetrain

- Optimal gear ratio achieved through swapping sprockets
- Scalable to large and small robots





Controls

Liberal Use of PID Controls

- Lift
 - P control to set height
 - PD control to sync left and right sides
- Drive
 - PI control for driving straight
 - PD control for rotation
- PD control on Skyrise builder arm



Rapid Prototyping

Real-time Scripting (RTS)

The screenshot shows the Real-Time Scripter application window. At the top, there is a menu bar with 'Mode', 'Load', 'Export', 'Port', and 'Help'. Below the menu bar, the 'Robot Name' is 'Westinghouse' and the 'Robot ID' is '4848'. The main interface is divided into three sections: 'Available Commands', 'Input Commands', and 'Previous Commands'.

Available Commands:

No.	Command	# of args	Arguments
1.	DRIVE	1	[-2000, 2000]
2.	STRAFE	1	[-2000, 2000]
3.	TURN	1	[-180, 180]
4.	DELAY	1	[0, 45000]
5.	ARMPOS	1	ground, max, sky1, sky2, sky3,....
6.	BUILDER	1	zero, bsky1, bsky2, bsky3, bsky4,....
7.	INTAKE	1	initialpos, cube1, cube2, cube3

Input Commands:

```
1 drive,200
2 delay,2200
3 intake,cube1
4 turn,90
5 strafe,360
6 intake,cube2
7 turn,180
8 drive,180
9 armpos,sky5
10 drive,160
11 intake,initialpos
```

Buttons: Send, Clear, Switch Bottom Panel

Previous Commands:

```
3 state( DRIVE, 200 );
4 delay( 2200 );
5 state( INTAKE, CUBE1 );
6 state( TURN, 90 );
7 state( STRAFE, 360 );
8 state( INTAKE, CUBE2 );
9 state( TURN, 180 );
10 state( DRIVE, 180 );
11 state( ARMPOS, SKY5 );
12 state( DRIVE, 160 );
13 state( INTAKE, INITIALPOS );
```

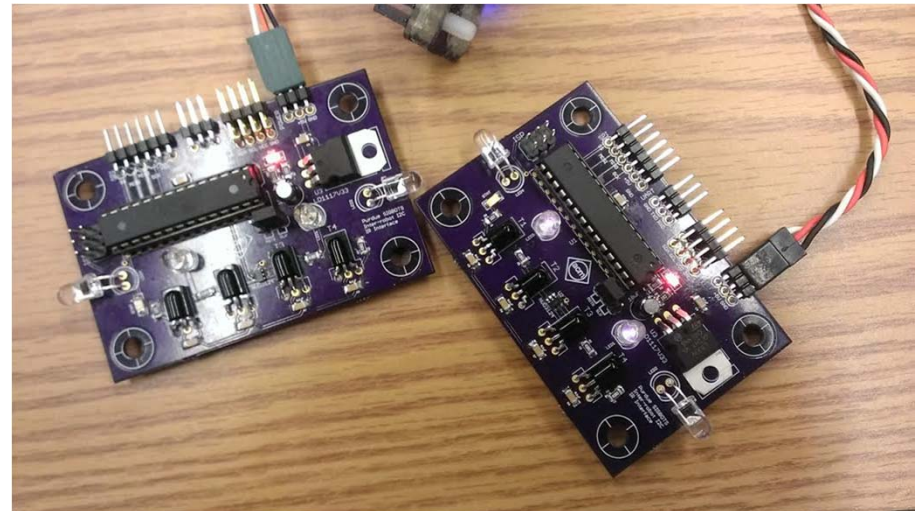
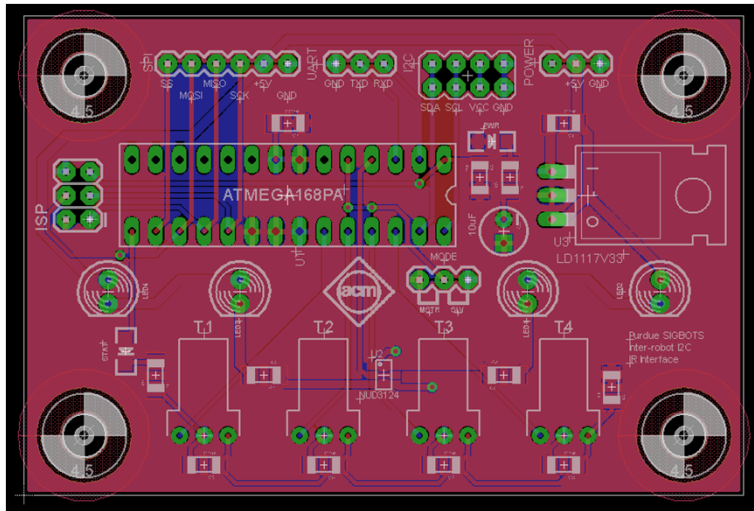
Real-time Scripting (RTS)

- Takes ~30 seconds to flash code to the robot
- Flash once, run as needed
- Create autonomous scripts and tune PID controllers
- Reduce development time by more than 50%



Inter-robot Communications

Four Is



Four Is

- Inter-robot I2C Infrared Interface
- Achieves UART-level baud rates
- Enables development of synergetic autonomous operation

Growing Up

- The game as a catalyst for our learning
- Members get industry-like experience not taught in the classroom
- Team is cross-discipline, all majors reap the benefits

Destination: Louisville



Watch online
4/16 - 4/18

