**SINKERS**

**Vehicle Control/Dynamics**

Bria, Naomi

**Image Detection + processing**

Aidan, Naomi

**Autonomy Logic**

Aidan, Bobby

**Software Integration**

Bobby, Matthew

**Mission Reconstruction**

Bria, Matthew

Labs to be completed:

Bria - Lab 14

Naomi - Lab 14

Aidan - Lab 10

Bobby -

Matthew -

**Vehicle Control/Dynamics**

Parsing method in both front and back seats.

**Image Detection + processing**

Somehow get the images and buoy angles. Self.\_\_vehicle in the Frontseat.py

I don’t exactly know where we can get the images and angles, but I would think in the “run” function in the front seat.

**Autonomy Logic**

Auv\_Controller.decide()

Change calls in BackSeat.py only

**Software Integration**

Parsing methods in both front and back seats.

**Mission Reconstruction**

Create new class (new .py file, probably), calls functions in FrontSeat.py