Sinkers Progress Report 7-23

**Progress**

Finished up image detection code; will integrate with autonomy logic shortly

Connected autonomy logic, not fully fledged (fleshed) out, to sandshark; runs simulation but with hardcoded buoy angles to test. Basic vehicle control

Mission Reconstruction can create/save .csv files to save information. Not fully finished

**Need Help On**

Utilizing more of the information given to/by the sandshark.

First get\_state is always fully “None” for some reason

Pair buoys together (in the case that there is more than one pair of buoys) (maybe not, since camera logic finds the angles to only the brightest red and brightest green, instead of all)

**To do**

Take pictures with the pi camera or something [image processing]

Graph stuff with Mission Control