* Bang bang camera method
  + Divide into 3 sections, adjust pitch and yaw to keep object centerpoint within middle division
* Need to bounce from nuc, to pi, to pixhawk
* Software defined radio plugs into NUC, issues command to start camera software
  + Nuc will send relevant data to pixhawk over pi
  + Pixhawk interprets the data
* NUC can send 5 values
  + Left
  + Right
  + Middle
  + Open arm
  + Close arm
  + Stop
* Workflow
  + NUc to pi (**most importante**)
  + Pi to pixhawk
  + Pi controlling the arm
* Remember nuc is just a computer, so use ethernet