**TEAM 2 - WEEK 7 REPORT - MARCH 13th - 408i SPRING 2022**

**Michael Delatte**

This week Michael had a lot of tests and projects to complete and had to spend most of his time on those assignments. He plans to make up for lost work over spring break.

**Wesley Catbagan**

In the lab this week Wesley changed the approach to the map to now use the IMU sensor to determine the orientation of the robot. The tests that he has done have been very successful and is now ready to work with Erik and Michael to combine the three different parts of the code. The lab this week will be spent trying to combine these into one main file and try to test and adjust the files so that they work cohesively together.

**Erik Bryson**

With smooth motor control and line tracking behind us, it was now time to turn direction towards adding smarts to the robot. Specifically, on the robot end, detecting what turns it has encountered, and then the following motor movements to navigate them. Right now the robot detect dead ends, dead rights, and open rights. It will not be too hard now the add the mirrored functionality for dead lefts, and open lefts. Then will come tees and open tees (4 way intersection). It is also imperative that I complete this module and provide it as a .H as soon as I can in order to provide an adequate development environment for the models of mapping and decision making that build upon this control module. We had a team meeting that outlayed how the modules will work together yet in separate development, allowing for versioning of the modules independently. I hope to have the control module done before spring break. I desperately wish to complete the module as a deliverable to my team so I can go back and spend some time house cleaning and consolidating the code for easy troubleshooting in the heat of trials should on-the-spot trouble shooting arise. Video Link —->

https://drive.google.com/open?id=1xh02db2Jxgwdk3SsRu-Az\_oOM1RSb6Ni&authuser=brysonerik%40gmail.com&usp=drive\_fs