Weekly reports are to be emailed to atbecker@uh.edu by 5:00pm on Tuesdays. The purpose of a weekly report is to: (1) give you text and images for your papers, thesis, and dissertation, (2) document progress, (3) identify if you are stuck or need resources.

Weekly report

1. **My *Goals* from last week**
2. Still need to debug for correct representation of Heuristic 1.
3. Redefine the main condition for pA=pB set for the overlapping particles.
4. Implement Heuristic 2 and 3 with new physics engine for MATLAB
5. Work out the issue with video feedback integration with manual control in real system.
6. Try the code on actual particles now that system is ready for input.
7. **Non-overlap code focus and implementation**

**My *Accomplishments* this week**

1. Running code for large map crashes the program because of too many particles.
2. Fix will be to not track all the particles at the same time.
3. pA=pB should be omitted. Gathering will be done as a function of image feedback- area of clusters, roadmap function and size of target area.
4. Progress on video for frictional movement:

Clear acrylic top for board to made by Jarrett.

The magnetic sliders work well.

Minor adjustment to workspace obstacle pieces.

1. **My *Goals* for next week**
2. Finish matlab code for current practical setup.
3. Work on javascript and ARGoS for simulating large swarms.
4. **What I need Dr. Becker to do:**
5. Suggest how to eliminate particles when they reach goal location. I am hoping to reduce target ROI as robots get there and also eliminate the robots as they reach. This is important to implement heuristics discussed before.