## Group LDA [Loic Barret, Divyam Garg, Aditya Goswami] Acme Ackermann Steering Controller Work/ Time log

Process Enactment		Pair Programming Roles						Interrupt		l
Task	Comment	Driver	Navigator	Design Keeper	Date	Start	End	#	Time	Clean tin
Iteration 1										
1.1	Create skeleton code for Robot Class	Divyam	Loic	Aditya	10/18/2020	16:40	17:25			0:45
1.2	Create unit tests for all Robot methods	Divyam	Loic	Aditya	10/18/2020	18:55	19:20			0:25
1.3	Create skeleton code for PID Class	Divyam	Loic	Aditya	10/18/2020	19:20	19:36			0:16
1.4	Create unit tests for all PID methods	Divyam	Loic	Aditya	10/18/2020	19:36	19:42			0:06
1.5	Create skeleton code for AckermannController Class	Divyam	Loic	Aditya	10/18/2020	19:45	20:14			0:29
1.6	Create unit tests for all AckermannController methods	Divyam	Loic	Aditya	10/18/2020	20:20	21:06	1	:05	0:41
2.1	Calculate vehicle speed and heading using wheel angles and velocities	Divyam	Loic	Aditya	10/18/2020	21:10	22:55			1:45
2.2	Calculate wheel velocities and angles based on required vehicle speed and heading	Divyam	Loic	Aditya	10/18/2020	23:00	0:13			1:13
2.3	Impliment solve method	Divyam	Loic	Aditya	10/18/2020	0:14	0:47			0:33
2.4	Impliment Main function	Divyam	Loic	Aditya	10/18/2020	0:47	1:27			0:40
2.5										
2.6										
2.7										
2.8										
Iteration 2										
iteration 2										