Group LDA [Loic Barret, Divyam Garg, Aditya Goswami]
Acme Ackermann Steering Controller
Iteration Backlog 1

Unique ID	Task	Target time (minutes)	Actual Time	Status
1	**Plan and Design**	**245**	**353**	
1.1	Create skeleton code for Robot Class	15	45	
1.2	Create unit tests for all Robot methods	15	25	
1.3	Create skeleton code for PID Class	15	16	
1.4	Create unit tests for all PID methods	15	6	
1.5	Create skeleton code for AckermannController Class	15	29	
1.6	Create unit tests for all AckermannController methods	15	41	
2.1	Calculate vehicle speed and heading using wheel angles and velocities	30	45	
2.2	Calculate wheel velocities and angles based on required vehicle speed and heading	45	73	
2.3	Impliment solve method	60	33	
2.4	Impliment Main function	20	40	