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**Weekly Report (WEEK 8)**

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In this week, we decided to write our codes in a modular way. We divided some tasks related with coding, and then we assigned these to our group members. We made researches individually and started coding. In Table 1, it can be seen what these parts are and whom they are assigned to.

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| Motor driver: *Abdullah Aslam* |
| Ultrasonic sensor: *Anar Abdullayev* |
| LED antenna sensor: *Bulut Ulukapı* |
| Feedback control: *Syed Saad Saif* |
| Flags: *Umut Can Serçe* |

Table 1. The list of modules and their assignments

In addition to the equipment and components that are purchased in last weeks, we purchased a chassis for tests and trial.

There was also a standards committee meeting. Before the meeting, we communicated with the other group and made an informal meeting. After these informal and formal meetings, some decisions are made. The agreements which are made on these meetings can be seen on the Table 2.

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| * If a leave command is given while turning, the optimal direction for leaving must be decided. |
| * Minimum radius of the curvature for turning is 100 cm. |
| * Maximum speed of the mock up robot is 12 cm/s. (previously it was 20cm/s) |
| * Distance between the center of the rectangle (visibility marker) on the robot and ground needs to in between 12 cm and 16 cm. |
| * Infrared LED’s needs to be horizontal. |

Table 2. The decisions made in the standard committee meeting 3