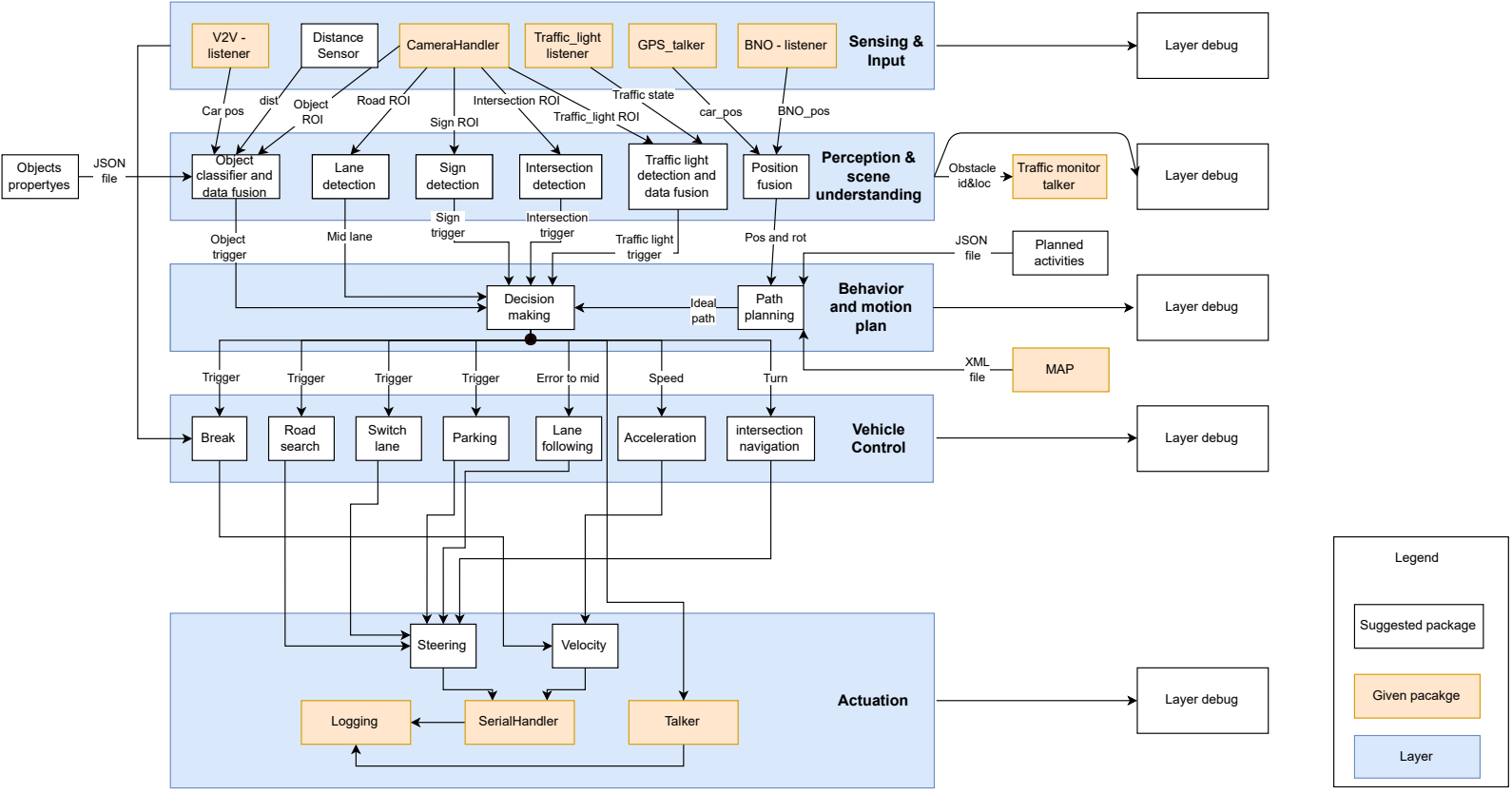
Working Weeks	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20	21	22	23	24	25
Start of the week	22-nov.	29-nov.	6-dec.	13-dec.	20-dec.	27-dec.	3-ian.	10-ian.	17-ian.	24-ian.	31-ian.	7-feb.	14-feb.	21-feb.	28-feb.	7-mar.	14-mar.	21-mar.	28-mar.	4-apr.	11-apr.	18-apr.	25-apr.	2-mai	9-mai
Sensing and input working package	Documentation on the given guides and projects. Chose main languages and technologies Create/adapt project plan Members tasks asignation	Camera handling, preprocessing, noise cancelling, ROIs definition										Define other necessary sensors, define use-case, integration (IMU, distance), preprocessing, noise cancelling.													BFMC
													Define use-case and test given servers information												
																		Induce noise on all sensors and systems				Other functionalities and optimizations			
Perception and scene understanding working package		Lane detection						Intersection detection			Traffic sign detection			Traffic light detection											
													Position fusion					Traffic lights detection & classification							
														Define objects properties file				Object detection & classification							
														Environmental server interaction											
																						Other functionalities and optimizations			
Behaviour and motion plan working package		Define project architecture and communication between packages										Define path planning and validation		Define robustness and safety measures											
												Define decision making --> priorities of actions and state flow													
																		Induce noise on systems to valdiate robustness (loss of image, burned image, road search, undefined objects and states)				Other functionalities and optimizations			
Vehicle control working packages					Lane following and speed control							Intersection navigation			Simple action taking maneuvers (parking, stop for traffic sign, stop for traffic light, stop for pedestrian)			Complex action taking maneuvers (swith lane for static and mobile car, road search)							
																						Other functionalities and optimizations			
Final result & Demo	Team can control the phisical car remotely and the virtual car on the simulator.	Robot can keep a lane, can make a curve										Robot can navigate in intersection		Robot can go on a pre-determined path, stop at stop sign, park at parking sign, slow at crosswalk				While detecting and calculating it's position, the robot can dynamicaly go to specified checkpoint, react to traffic lights, interact with other cars and send environemt data)							
		Team defines and creates it's own phisical testing environment									Team defines a way of parallel developing and testing														
		Team installs the virtual testing environment																							
																						Other functionalities and optimizations			
Deadlines				19-dec.					23-ian.				20-feb.				20-mar.				17-apr.				15-mai
Checkpoint				1st report	Christmas brake				2nd report				3rd report				Mid-term quality gate				4th report				Finals


V2V - listener
Distance Sensor
CameraHandler
Traffic_light listener
GPS_talker
BNO - listener
Sensing & Input
Layer debug
Car pos
dist
Object ROI
Road ROI
Intersection ROI
Sign ROI
Traffic_light ROI
Traffic state
car_pos
BNO_pos
Objects propertyes
JSON file
Object classifier and data fusion
Lane detection
Sign detection
Intersection detection
Traffic light detection and data fusion
Position fusion
Perception & scene understanding
Obstacle id&loc
Traffic monitor talker
Layer debug
Object trigger
Mid lane
Sign trigger
Intersection trigger
Traffic light trigger
Pos and rot
JSON file
Planned activities
Decision making
Ideal path
Path planning
Behavior and motion plan
Layer debug
XML file
MAP
Trigger
Trigger
Trigger
Trigger
Error to mid
Speed
Turn
Break
Road search
Switch lane
Parking
Lane following
Acceleration
intersection navigation
Vehicle Control
Layer debug
Steering
Velocity
Logging
SerialHandler
Talker
Actuation
Layer debug
Legend
Suggested package
Given pacakge
Layer