Semester	Tasks & Milestones
Fall 2017	 Software Development: Design and modeling of variety of prototype systems which would benefit from tethered motions to use in simulation Exploration of ways to best model cable interactions on rough terrain in variety of gravities
Spring 2018	 Software development: Finalize prototype systems and physics simulation Investigate efficiency of sampling-based motion planners on variety of systems with different complexities
Fall 2018	Design and testing of several control policies for efficacy in maneuvering tether
Spring 2019	 Publish results of low-level control policies for physically-realistic tethered systems Explore planning in low dimensional state space projections
Fall 2019	 Investigate machine learning approaches for dimensionality reduction in planning Publish initial low dimensional state space results
Spring 2020	 Analyze results; Finalize low dimensional strategy Software development: integrate appropriate low level control policies with rudimentary sensing data in simulation Closing the loop: Integrating all parts of the coordinated solution
Fall 2020	 Simulating and analyzing benefits on variety of systems. Writing dissertation
Spring 2021	• Finish dissertion