Week 0

First meeting with group, select team leader, discuss plan of action, dived group members, discuss platform for communication, discuss meetings.

Write together info from meeting, sett up google drive, discuss with hardware group

Research on wat technologies to use for mower and communication between Arduino and raspberry.

Estimated 20h

Week 1

Plan meeting and send out invite to meeting   
Meating Tuesday

Thursday programming functions and researching how to connect different parts.   
Meating with Husqvarna

Meating Friday   
Hardware breakdown project

Estimated 20h

Week 2

Meeting planning and rewrite meetings document.  
Meeting with Husqvarna

Fix communication between mower and raspberry.  
Work on virtual coordinate system and check wats needed to calculate position of mower

Estimated 20h

Week 3  
Meeting planning and rewrite meetings document.  
Meeting with Husqvarna

Try implementing the lidar for usage in the coordinated system.

Estimated 20h

Week 4

Meeting planning and rewrite meetings document.  
Meeting with Husqvarna

Continue with the work of implanting lidar in the coordinate system, much problem with getting the right information from lidar.

Estimated 20h

Week 5

Meeting planning and rewrite meetings document.  
Meeting with Husqvarna

Take a break from lidar, to implement movement function in raspberry, creating connection with the application and making both manual and autonomous drive work.  
  
Estimated 20h

Week 6  
Meeting planning and rewrite meetings document.  
Meeting with Husqvarna

During this week we finished with the communication with both backend and application.  
Started working on a new coordinate system.  
Fine tuning communication between Arduino and Raspberry pi.

Estimated 20h

Week 7

Meeting planning and rewrite meetings document.  
Meeting with Husqvarna

We finished the coordinate system and the moment functions.  
Collected and finished all documentation.  
Created a start-up script for the raspberry pi to start our program.

Estimated 20h