April	Monday	Tuesday	Wednesday	Thursday	Friday	Saturday	Sunday	TASKS	
									Find and modify automatic robot turning to previous
April 15-21	1:	5 16	17	18	19	20 - [Kinematics]	21	Buy 4 port radio OR buy ethernet hub	joystick position / heading: when
April 22-28	2:					27 - [Periodic Syncing, Auto drive 1 meter]	28	Delay Rasp4 bootup, wait until Radio	Greasing FrontLeft Swerve wheels
April 29-5	2	9 30	1	2	3	4 - [Study Odometry]	5	Publish closest game piece information from TPU onto network table	Test more custome positions
			8 - [Odometry, drive and turn and must be able to return to original position AUTOMATICALLY in one action] : Tested odometry, no automatic return to position, discovered innacuracy of + - In upon large and complex			11 - [Odometry] : Changed repositories to FRC2024, adapted FRC2024 to swerve2 and tested/funed odometry. Decent accuracy, +-2cm offset for linear 1 meter, +-50cm for small range complex movement and +-100cm for		In code, retrieve information from	Speed up pathplanner velocity and
May 6-12 May 13-19	1:		movement 15 - [Pathplanner] : Learned preplanned path again using path planner autos			repeating looping path 18 - [PathPlanner] : Got on- the-fly path working. Drive and travel a set path anywhere relative to the current position. Can be field-R. Try to find a way to stop the robot from turning back to its last	12	network table Extend pi camera cable	Rewire and organized electrical
May 20-26	2		22 - [Photovision] : Using photon vision to detect apriltag, using On-The-Fly path planning to			25 - [Photonvision] : same		mount for turret (is there space? the	Research or find a seperate power supply for rasp pi 4?
May 27-2	2'	7 28	29 - [Photonvision] : using Translation2d to calculate destination. High consistency at 1m/s, 20cm deviation from		31	1 - Put Neo onto Swerve 3	2	Integrate retrieved data into path planner OTF	If no note is picked up via auto, should look around and
June 3-9		3 4	5	6	7	8	9	Auto Intake Procedure, timed using sensor feedback, if missed,	Pathfinding (AKA pathplanner making paths
June 10-16	11	D 11	12	13	14	15	16	Auto Shoot Sequence, timed no feedback	re calibrate BW cam
June 17-23	1'	7 18	19	20	21	22	23	Make an april tag map, coordinates	steal another set of compliant wheels from arm
AUGUST	Mon	Tue	Wed	Thu	Fri	Sat	Sun	Seeing april tag only helps update	put camera case on
game piece wee	2	9 30	31 - Hongtac: buy 4 port radio from https://wcproducts.com/products/frc-radio Sean/Robin: write automatic intake sequence USING 07F, must face note initially and finally, drop intake and spin 1/2 way through path, retrieve intake and stop spin, check sensor -> if sensor return false, try again.	Robin: set up intake camera, delay rasp boot up, test intake sesnsor consistency	2 - Robin: retrieve TPU result, publish TPU information to network table	3 - Robin : retrieve information from network table	4 - Robin: Do Math and make data useful in CODE - how do you know whether you have detected a game piece or not (AKA valid data)?	Change gear ratio of intake	indicate on dash board or driver station when pi disconnected
april tag week	5 - Robin: Test accuracy of math		7 - Robin: Object Oriented Programming Note Multi detection	8 - Sean: test auto intake with vision data	9 - Robin: write auto shoot sequence using OTF, rev shooters during path, stop, confirm location and angle, shoot III (Robin: Final testing of intake sequence III Sean: Flashing Orange Pi	10 - Sean: mount orange pi, B/W camera, make sure photonvision is working, extract data from photonvision Robin: make digital april tag map object in code, remember that some not all april tag positions are accessible by robot, must have custom coordinates	11 - Robin : test shooting sequence & map capabilities	Test impact of gear ratio on intake	Emergency override of a path by driver via any control

12 - Robin: Use math to update odometry based on april tag, max out th map object	compatibility, Make another or	14 - Robin: Work on and test some more custom positions,	15 - Sean: Remove automatic turning robot to previous heading		17 - CAMPING	18 - CAMPING		turn climber into automatic button, no path included	
hitting Victor & David: turn climber motion into automatic button using encoder values (PID) fully closed and fully ou both motion toggled by (Y) BUTTON, no path planning	move camera from original location by a lot), make SURE the turning is removed and fully working not affecting driving features Chris (Sean's Dad):	diagram and key waypoints (poses), including when our robot is the most capable and when our robot is support III Robin	22 - Victor & David: Test automatic climbing button, can it climb? what are some restraints? Sean: Continue brainstorming autos	for Data Analysis for Note	24 - Robin: "Recalibrate" note detection, create turn->move two step command (remove curves from path), auto search command instead of try-again-after-miss command Sean: Making 1 types of auto (to center and shoot all notes back per alliance) preplanned path assuming 15s no notes are out of place	sunday, complete extrapolation method.	Test acceleration change impact on shooter	brainstorming 15s auto routines	
26 - Sean: Test 4 note auto again, and if possible upgrade the 4 autos to use OTF	27 - Robin: Integrate Harry's method	28 - 1325 FIELDS	29 - HARD DEADLINE	30	31			Configurate new Radios	
	David (busy 1 pm to 9pm) - week 4	Harry busy - week 4					Change intake PID Smart motion constants for smoother motion	Change TPU rasppi IP address to new radio	
	Sean open week 4	Victor open week 4					Make on the spot robot turning command using desiredChassisSPe ed	RE CONFIGURATE RADIOS	
							Make command that runs a path and only finishes when path is done		
							Calibrate Odometry	and PathPlanner E	Error