At the high level, the Hindbrain runs different code based on which boat is selected. That code commands actuators, gathers sensor data, and may do some filtering. The following sections are determined by the “Boat Type” variable.

1. **Damn Yankee**
   1. **Sense**
      1. There are a series of queues, one for each bit of sensor data. Damn Yankee Sense reads the raw data and stuffs in directly in a queue
   2. **Think**
      1. DYThink (Damn Yankee Think) reads those queues, does some basic filtering (this section of code should be expanded upon) and writes the sensor data to notifiers.
      2. **Architecture point:** We would like to filter out all obviously bad data. This is really important because then the rest of the code can assume that the data is good and we don’t have to do error checking every time a variable is used.
   3. **Act**
      1. DYAct checks whether it should be paying attention to the MyRIO or the remote control, then commands the Dynamixels
         1. The code that reads the remote control is FPGA code, called (at the moment) DamnYankeeFPGA. A bit of code called a Read/Write Control inside of DYAct is reading that FPGA code.
2. **Simulation**
3. **Little Boats**
4. **Blackbody Radiation**
   1. There is currently nothing here