## Change Log

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| **Revision** | **Date** | **What** |
| V 0.1 | 06/20/2016 | 1. Replace including “ GPS.h” to “ <Adafruit\_LSM303\_U.h>” and “<Adafruit\_Sensor.h>”  2. Get heading value from LSM303 sensor  3. Normalize the heading  4. delete “Get a new sensor event from the magnitomitor” and “Calculate the current heading” and “Normalize the heading”  5. Comment “void Show(REAL x)” |
| V 0.2 | 06/21/2016 | Comment “#include <Matrix.h>”, add “#include <Adafruit\_LSM303\_U.h>  #include <Elcano\_Serial.h>” |
| V 0.3 | 06/23/2016 | Writing new routines for sending receiving information to other processors |
| V 0.4 | 06/24/2016 | Read low level C2 for getting information of the speedometer |
| V 0.5 | 07/06/2016 | Wrote code in different Mega board that will simulate random speed data and transmitting it to C6\_Navigator |
| V 0.6 | | 07/12/2016 | 1. Was able to fix the issue of transmission of the odometer reading to C6\_Navigator Mega. 2. Read about how Kalman filter is used with GPS data by going through the existing code. 3. Gathered data how we can use it to fuse magnetometer and speed data to get the estimated position. |
| V 0.7 | | 07/13/2016 | Comment the connect with C2 low level “ //pinMode(CYCLOMETER, INPUT);  //attachInterrupt (5, WheelRev, RISING);  ” |