MT08 - Markose Jacob, Pooja Kabra
Acme Ackermann Steering Controller
Work/ Time log

	Process Enactment		Pair Programming Roles						Interrupt		
Task	Comment	Driver	Navigator	Design Keeper	Date	Start	End	#	Time	Clean time
Iteration 1											
1.01	Link github repo with travis CI	Markose	Pooja	Pooja						
1.02	Link github repo with Coveralls	Markose	Pooja	Pooja						
1.03	Create skeleton code for Sensor class	Markose	Pooja	Pooja						
1.04	Write constructors and destructors for Sensor class	Markose	Pooja	Pooja						
1.05	Create unit tests for Sensor class	Markose	Pooja	Pooja						
1.06	Write getters for Sensor class	Markose	Pooja	Pooja						
1.07	Write setters for Sensor class	Markose	Pooja	Pooja						
1.08	Create skeleton code for RobotKinematics class	Markose	Pooja	Pooja						
1.09	Write constructors and destructors for RobotKinematics class	Markose	Pooja	Pooja						
1.1	Create unit tests for RobotKinematics Class	Markose	Pooja	Pooja						
1.11	Write getters for RobotKinematics class	Markose	Pooja	Pooja						
1.12	Write setters for RobotKinematics class	Markose	Pooja	Pooja						
1.13	Inspect source code	Pooja	Markose	-						
1.14	Create skeleton code for Controller class	Markose	Pooja	Pooja						
1.15	Write constructors and destructors for Controller class	Markose	Pooja	Pooja						
1.16	Create unit tests for Controller class	Markose	Pooja	Pooja						
1.17	Write getters for Controller class	Markose	Pooja	Pooja						
1.18	Write setters for Controller class	Markose	Pooja	Pooja						
1.19	Create skeleton code for ForwardKinematics class	Markose	Pooja	Pooja						
1.2	Write constructors and destructors for ForwardKinematics class	Markose	Pooja	Pooja						
1.21	Create skeleton code for InverseKinematics class	Markose	Pooja	Pooja						
1.22	Inspect source code	Pooja	Markose	-						
1.23	Inspect unit test	Pooja	Markose	-						
1.24	Update readme	Pooja	Markose	-						
Iteration 2											
2.01	Implement calculateHeadingError method	Pooja	Markose	Markose						
2.02	Create unit test for calculateHeadingError	Pooja	Markose	Markose						
2.03	Implement calculateSpeedError method	Pooja	Markose	Markose						
2.04	Create unit test for calculateSpeedError	Pooja	Markose	Markose						
2.05	Inspect source code	Pooja	Markose	Markose						
2.06	Implement solve method	Pooja	Markose	Markose						
2.07	Create unit test for solve	Pooja	Markose	Markose						
2.08	Inspect source code	Pooja	Markose	Markose						
2.09	Implement calculteWheelSpeed method	Pooja	Markose	Markose						
2.1	Create unit test for calculateWheelSpeed	Pooja	Markose	Markose						
2.11	Implement calculateWheelAngles method	Pooja	Markose	Markose						
2.12	Create unit test for calculateWheelAngles	Pooja	Markose	Markose						
2.13	Inspect source code	Pooja	Markose	Markose						
2.14	Implement Main function	Pooja	Markose	Markose						
2.15	Create visualization	Pooja	Markose	Markose						
2.16	Tune parameters	Pooja	Markose	Markose						
2.17	Update readme	Pooja	Markose	Markose						