Sprint 1 Goals

1. Implement sensor for retrieving environmental distance data. (Lidar)
2. Have Object Detection module generate array of scalar distances.
3. Collision Detection module
   A. Executes in continuous loop
   B. Compare if distance < standoff
   C. Activate Avoidance if compare == true.
4. Avoidance algorithm creates new path waypoint & inserts correctly in list.
5. Pathing module
   A. Executes in continuous loop
   B. Identifies next unvisited waypoint
   C. Initiates swarm movement
   D. Marks waypoints as "visited" when visited.