

Kayleigh Bishop: I was responsible for the sensory input processing for the robot. This included object classification and position estimation for all objects seen in the RGB cameras. Glenn and I also collaborated on each of the behaviors input into the central arbiter, which used output from sensing functions to make decisions about the best actions.

Glenn Zhang: I implemented a search function with the map that we had planned for long term searching. I also implemented fruit probability structures to better classify different colors of fruit with different functions. I later also worked a lot on tuning the parameter and constants we are using for the action functions. The collaboration with Kayleigh has also been mentioned above.

Evan Schott: I implemented a mapping API and a claw API that we had planned to use as an internal world model for the robot. I also implemented the base of the voting system and helped debug some code in the early stages.