This week, I focused on completing the motor setup and enabling movement control through ROS2. I verified correct motor response through ROS2 topics and confirmed that the robot can now move reliably using command inputs. I also worked on resolving the camera streaming limitations by installing and configuring a different camera package, which now supports stable 1080p at 30fps (previously the system could not achieve this resolution and frame rate). Additionally, I independently researched the ROS YOLO package to understand its installation process, dependencies, node structure, and how it integrates with image topics for object detection. I reviewed documentation and example repositories to prepare for future implementation and testing within our system.