**Present:**

Daniel Williams, Prof. Eric Kerrigan, Ian McInerney

**Outcomes:**

Investigate contracts for followers to stick to their zones.

Should the leader plan with full knowledge of follower poses, or do the trajectory optimization using knowledge of the contracts?

Should the contracts remain static or change over time? If so, the leader must communicate with followers.

This weekend: ICLOCS tutorials

Next week: ICLOCS-ROS for single agent

End of term: ICLOCS-ROS for multiple agents, trajectory planning for KAUST control scheme