**Present:**

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**Outcomes:**

Open-loop implementation of single-agent QUAV repositioning (minimize control input squared): sound results, very slow to execute.

* Fix the time tf
* Smoothen the obstacle’s representation in the path constraint
* Consider the use in the code of finite differences vs derivatives for dynamics, inputs and constraints functions
* Calculations should last on the order of milliseconds.

Closed-loop control for single-agent QUAV repositioning (cost as per open-loop):

* Consider the role of sampling times in the Simulink model
* Use two chained integrator blocks for [x,-,y,-,z,-]
* Resolve issues with open loop before running

Closed-loop control for dual-agent QUAV transportation:

* Keep work in MATLAB and ROS from KAUST; want to swap out PID controller for ICLOCS next term
* MATLAB feeds setpoints via interface to ROS-Pixhawk, ROS-Pixhawk feeds state to MATLAB
* What is the interface that ICLOCS would require?
* *When everything is sorted, make a schematic diagram for the software subsystems*