1. Bom
	1. emitters and detectors?
		1. server -> station / station -> server
		2. station queue test (move to home position for test)
		3. rotate to emitter i
		4. test emitter i
			1. -> turn on only light i
			2. <- done
			3. read
			4. -> turn lights off
			5. <- done
		5. rotate to detector i
		6. test detector i
			1. turn light on
			2. -> read
			3. <- data
			4. turn lights off
			5. -> read
			6. <- data
		7. go back to iii
		8. turn lights off
		9. send all data at once
		10. clean up?
	2. detector
2. IR Rangefiners
	1. max range and min range and linearity or loggishness
		1. station queue test (move to home position for test)
		2. Rotate to pos i (i = 1…5)
		3. k = 1…K
		4. set wall to position k
		5. -> read
		6. <- data
		7. if k%5 == 0 send data to server?
		8. go back to iii
		9. k = K…1
		10. set wall to position k
		11. -> read
		12. <- data
		13. if k%5 == 0 send data to server?
		14. go back to viii
		15. go back to ii
		16. flush rest of data
		17. clean up?
3. Motors
	1. max/min/turn on/ turn off
	2. relative accuracy
	3. linearity
4. Motors with new categorization
	1. velocity (PWM)
		1. station queue test (move to home position for test)
		2. i = 1…N
		3. -> set PWM
		4. <- wait steady
		5. multiple times
			1. measure encoder
			2. wait some time
			3. measure encoder
		6. go back to i
		7. i = N…1
		8. see above
		9. redo everything with the motors going backward
		10. redo everything with the other motor
		11. go back to vi
		12. send data
	2. encoder (position)
		1. station queue test (move to home position for test)
		2. multiple times
			1. -> turn motors on for (time)
			2. <- stopped
			3. ->read encoders
			4. <-data
			5. read encoders
		3. send data

Jobs

1. Robot Code (Mike)
	1. comm. (Evan)
2. Station Code
	1. hardware drivers (John)
	2. algorithms (Martin)
	3. comm. (server) (Martin)
	4. comm. (robot) (Evan)
3. Server Code
	1. Database (Emily)
	2. MATLAB (Emily)
	3. comm.(station) (Martin?)