

	2014-8				2014-9				2014-10				2014-11				2014-12				2015-1				
	32	33	34	35	36	37	38	39	40	41	42	43	44	45	46	47	48	49	50	51	52	1	2	3	4
<b>Colony</b>	<b>Colony</b>																								
Battery Level Indicator																									
Improve library error codes																									
Better sanity check for invalid BOM type																									
XBee/Wireless Initialization																									
get all the library inti's and functions (...)																									
Xbee Documentation																									
xbee baud rates																									
Wireless - core send, ack functions																									
Wireless - xbee.c																									
xbee id																									
Conclusion on filter design	Assigned 0%																								
Figure out rangefinders group	Assigned 0%																								
Complete SURG form	Assigned 0%																								
Check/Order robot battery clips	Assigned 50%																								
Line Follower Collimator																									
Redo robot pants																									
Get Colony videos onto VideoTron. Embed in (...)																									
Clean up repository branches																									
Add Line Following to Library																									
Profile different mapping surfaces																									
Make Hunter-Prey Ref More Verbose																									
Clean up Colony-New and prepare for next (...)																									
Implement Intersection Behavior																									
wl_basic_do_default(int *length) doesn't (...)																									
Schedule Fleet Maintenance Day																									
Discuss and Contact about Extra Colony III (...)																									
Colony - Hardware																									

<p><b>Investigate how to use the JTAG ICE</b></p> <p><b>Colony - Library</b></p> <p><b>Make sure all robots program the correct (...)</b></p> <p><b>Colony Scout</b></p> <p><b>Colony Environment</b></p> <p><b>Software Architecture</b></p> <p><b>Reflow Oven Temperature Regulation</b></p> <p><b>Update Boards on Eagle</b></p> <p><b>Research PCB Assembly Costing</b></p> <p><b>Website Work Log</b></p> <p><b>Video for Scout Intro</b></p> <p><b>Create ROS Node: Buttons</b></p> <p><b>Create ROS Node: Timer</b></p> <p><b>Create ROS Node: IMU</b></p> <p><b>Create ROS Node: Accessory</b></p> <p><b>Create ROS Node: Encoders</b></p> <p><b>Create ROS Node: Wireless</b></p> <p><b>Create ROS Node: USB Serial</b></p> <p><b>Create ROS Node: Cliffsensors</b></p> <p><b>Create ROS Node: BOM</b></p> <p><b>Create ROS Node: Analog</b></p> <p><b>BOM Interference Testing</b></p> <p><b>BOM Driver Code</b></p> <p><b>Sonar Wiring</b></p> <p><b>Sonar Position Tracking</b></p> <p><b>Send Sonar Readings to ARM</b></p> <p><b>Automate Stepping and Sonar Reading</b></p> <p><b>Sonar on ARM</b></p> <p><b>Make ARM command Sonar on AVR</b></p> <p><b>Read IMU values and send to ARM</b></p> <p><b>Pose Estimation</b></p> <p><b>Control Motors (ARM)</b></p> <p><b>Track Encoders</b></p> <p><b>Charging Base</b></p>	<p><b>Colony Scout</b></p> <p><b>Assigned 100%</b></p> <p><b>Assigned 100%</b></p> <p><b>Assigned 0%</b></p> <p><b>Assigned 100%</b></p> <p><b>Assigned 100%</b></p> <p><b>Assigned 0%</b></p> <p><b>Assigned 80%</b></p> <p><b>Assigned 100%</b></p> <p><b>Assigned 90%</b></p> <p><b>Assigned 0%</b></p> <p><b>Assigned 0%</b></p> <p><b>Assigned 0%</b></p> <p><b>Assigned 0%</b></p> <p><b>Assigned 0%</b></p> <p><b>Assigned 10%</b></p>
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<b>Create Scout Chassis</b>	<b>Assigned 0%</b>
<b>IMU on ARM</b>	<b>Assigned 0%</b>
<b>ROSSERIAL on ARM</b>	<b>Assigned 0%</b>
<b>CliffSensor on ARM</b>	<b>Assigned 0%</b>
<b>Create Transmitting Protocol</b>	<b>Assigned 0%</b>
<b>Wireless on ARM</b>	<b>Assigned 10%</b>
<b>Cliff Detection</b>	<b>Assigned 0%</b>
<b>Buttons on ARM</b>	<b>Assigned 0%</b>
<b>USB Serial on ARM</b>	<b>Assigned 0%</b>
<b>Power Up Rest of Scoutfly</b>	
<b>Get Old Boards and Funding Info</b>	
<b>Test AVR on ARM</b>	<b>Assigned 0%</b>
<b>Get Sonar Stepping and Reading</b>	<b>Assigned 0%</b>
<b>"Automated" Turning</b>	<b>Assigned 0%</b>
<b>Add Fuel Guage and Protection circuit (...)</b>	
<b>BOM returns values even when IR LED (...)</b>	
<b>File Error Service call</b>	
<b>Colony Scout - 1.0</b>	
<b>BOM Send/Receive Functions</b>	
<b>Assembly Instructions</b>	
<b>Fix Encoder pinout on breakfly</b>	
<b>Colony Scout - 1.2</b>	
<b>NanoRK Wireless Library</b>	
<b>Look @ Robostix AVR&lt;-&gt;ARM Comms (...)</b>	
<b>Electronics Purchasing, OCT-08</b>	<b>Assigned 0%</b>
<b>Colony Scout - Development</b>	
<b>System Wiring</b>	
<b>Look into accelerometer speed</b>	
<b>Email Red W</b>	<b>Assigned 0%</b>
<b>Create roboclub demo</b>	<b>Assigned 50%</b>
<b>Design SmartFly Smart Accessory (...)</b>	
<b>Mechanical Work Log</b>	<b>Assigned 20%</b>
<b>Check speaker magnet interference (...)</b>	
<b>HyLo</b>	<b>HyLo</b>

<p>type proposed proposal</p> <p>Meeting</p> <p>Mechanical Logic Gates</p> <p>Update - website</p> <p>You Tube + Display Case</p> <p>Website - host on roboclub</p> <p>Wishlist</p> <p>Compressed Air System</p> <p>Quadrotor</p> <p>Fix the Quadrotor</p> <p>Point Cloud Display</p> <p>Design aluminum frame for Quad1</p> <p>Make private repository</p> <p>Email Harrison to Order Parts</p> <p>USB to micro USB cable</p> <p>RobOrchestra</p> <p>Model Solenoids for brassbot in Solidworks</p> <p>Get Pianobot modelled with the piano</p> <p>Tooltron</p> <p>Write tutorial about network programming</p> <p>Tooltron - 1.0</p> <p>script for network programming</p> <p>notifications of tool boot packets in (...)</p> <p>Document the Network Bootloader</p> <p>Document the States of the toolbox/cardbox</p> <p>Server dies when internet is out</p> <p>update server docs</p> <p>Tooltron - 1.1</p> <p>timeouts not working correctly</p> <p>remove server hacks</p> <p>organize repo</p> <p>Document new Error codes on Cardbox</p> <p>order more boards and replace drill-press (...)</p> <p>Tooltron - 2.0</p>	<p>Assigned 0%</p> <p>Mechanical Logic Gates</p> <p>Assigned 0%</p> <p>Assigned 0%</p> <p>Assigned 0%</p> <p>Quadrotor</p> <p>Assigned 0%</p> <p>RobOrchestra</p> <p>Assigned 0%</p> <p>Assigned 0%</p>
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<b>MySQL Stored Procedures</b> <b>Underwater Swarm Bots</b> <b>FTDI cable</b> <b>WCTU</b> <b>WCTU - WCTU Version 1.0</b> <b>Create v1.0 JS Client Revision 1</b>	<b>Underwater Swarm Bots</b> <b>Assigned 0%</b> <b>WCTU</b> <b>WCTU -WCTU Version 1.0 50%</b> <b>Assigned 0%</b>
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