Task Name	Group Member	Finish by Date/Due	Sep-	Oc	t-15		Nov-15			Dec-15	Т	Jan-16	Feb-16	Mar-16	Apr	r-16	
			1 8 15	22 29	6 13	20 27	3	10 17	24	1 8	15 22	29	5 12 19 26	2 9 16 23	1 8 15 22 2	29 5 12 1	19 26
Individual Behavior															I		
Research Kilobot Sensors	Jared	September 28, 2015													I		
Research Kilobot Communication Protocol	Jared	October 12, 2015													I		
Research Q-bot Image Processing	Ryan/Greg	October 5, 2015													I		
Research Q-bot Sensors	Ryan/Greg	September 28, 2015													I		
Reseach Q-bot Communication Protocol	Ryan/Greg	October 19, 2015													I		
Reseach E-puck Sensors	Brittany	October 26, 2015	1												I		
Research E-puck Communication Protocol	Brittany														I		
Individual Communication			l											ļ	 		
Research/Test Kilobot - Kilobot	Jared	October 19, 2015													I		
Research/Test E-puck - E-puck	Brittany	December 14, 2015								Т					I		
Research/Test Qbot - Qbot	Ryan/Greg	November 2, 2015								Т	_				I		
Integrated Communication														ļ			
Test Kilobot - E-puck	Jared/Brittany	December 14, 2015	i												I		
Test Kilobot - Qbot	Jared/Ryan/Greg	November 16, 2015	i							Т	•				I		
Test E-puck - Qbot	Brittany/Ryan/Greg	December 14, 2015	i												I		
Algorithm Design			l							T	_						
Design Linear Based Model	All	December 14, 2015													I		
Integrated Behavior		,								T							
Formation Control Behavior															I		
Localization	All	January 25, 2016	i												I		
Point Convergence	All	January 25, 2016													I		
Leader Follower	All	January 25, 2016	i												I		
Flocking Behavior							_			Т					I		
Neighbor Repulsion	All	February 1, 2016	i											4	I		
Enpoint Attraction	All	February 1, 2016								Т				4	I		
Heading	All	February 1, 2016	i							Т				4	I		
Testing										T							
Software Implementation	All	March 7, 2016															
Hardware Implementation	All	March 7, 2016															
Deliverables	-	,								Т						_	-
Project Proposal - Oral Presentation	All	October 1, 2015													I		
Project Proposal - Document	All	October 15, 2015													I		
Webpage Release	All	October 28, 2015													I		
Fall Progress Presentation	All	November 19, 2015	i												I		
Fall Performance Evaluation	All	November 19, 2015	i												I		
Fall Performance Review	All	December 3, 2015													I		
Spring Progress Presentation	All	Feburary 18, 2016								г					I		
Student Expo Abstract	All	March 18, 2016	i											, i	ı		
Progject Demostration	All	March 24, 2016															
Final Presentation	All	April 7, 2016	i												,		
Student Expo Poster Printing Deadline	All	April 11, 2016															
Student Expo Poster Setup	All	April 12, 2016	ı							I] !	I		
Sudent Expo Poster Setup	All	April 14, 2016	ı		1		1		- 1	1					I		
Final Report (Draft)	All	April 14, 2016	ı							I							
Final Report	All	April 28, 2016	ı							I							
Final Web Page	All	April 28, 2016 April 28, 2016	ı							I] !	I		
Advisory Board Poster Printing Deadline	All	April 28, 2016 April 28, 2016	ı		1		1		- 1	1					I		
Advisory Board Poster Printing Deadline Advisory Board Poster Presentation	All	April 29, 2016 April 29, 2016	ı							I] !	I		
Auvisory Doard Poster Presentation	All	April 29, 2010			1		<u> </u>			_1_				1			

Jared has continued work on localization with the Kilobots. Brittany has also continued work on the E-pucks. She has tried to enable the disabled E-pucks, but is finding more problems. She is going to start work on an algorithm. This algorithm will include creating a coordinate system with the E-puck and then moving to a specific point on the coordinate system. This past week, Greg and Ryan attempted to program a Qbot to move in a sinusoidal motion based on the sample time. We were able to get a general shape of a sine wave, but it would flatten out at the end. All adjustments to the movement equations only resulted in speed changes. As the semester is coming to end, work on communication between platforms needs to be established. This would ensure that next semester algorithm designs for formation control and flocking behaviors can be established.