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This week I significantly cleaned up and rearranged the software modules that run the sensors and servos. Part of my aim was to link the modules in a more sensible and clearly hierarchical structure than my previous software's construction. I set up an output in the module that runs the sonars to print what's being read by the sensors, allowing for understanding of what the sensors are detecting. I also rearranged and extended the behavioral programming, giving the robot a movement pattern similar to what the end result should be. I began tuning the weightings for the navigational correction system, as well as sonar sensitivity as a means to adjust detection pattern, but it requires more work to operate smoothly and without some hiccups it still has occasionally.