- Rule suggestions sent to the global list, there's been no discussion so far
- Ran a semi-complete test run on Friday. Everything went well and is (almost) into SVN.
- We'd like to confirm with Jim that we should get a coop student in fall if possible.
- Marius made several comments from last week's meetings that the rest of the team should spend some time checking over:
  - He wrapped player into ROS by converting a similar wrapper for the erratic robot. The package is called powerbot_player and it's in a new ROS packages repository which I added to out SVN. He created a page on the wiki with a short howto on how start using this repository: https://bugs.cs.ubc.ca/cgi-bin/twiki/view/LCI/SettingUpROSInstallation
  - The instructions on the wiki probably won't work on the department computers (Suse) without some adjustments. They should work ok on ubuntu.
- Most of this meeting was spent discussing new goals for our system in 2009. Well, mostly, this ended up being sort of a mix of high-level goals and specific project ideas and design suggestions. But here is the list we brain-stormed, with the team members who've expressed particular interest noted with *[]:
- multi-view recognition *[Dave/Ankur]
- integrate new laser scanner *[Dave or catherine]
- using 3D data
  - exploration *[Dave]
  - recognition *[Scott]
- integrate recognition with exploration
- better training data
  - filtering
  - alignment
  - meta-data
- testing framework (automated) *[James + all]
- integrating ROS *[Marius et al]
- universal category recognition *[Ankur]
  - more features (colour, contour, HoG)
  - guessing (size, context)
- pre-contest training
  - download and clean images for common classes
  - guess based on location
  - Twitter
- wordnet
- replace cannon camera *[Scott]
  - Things from prior weeks which still need to be looked at:
    - Bumblebee driver in ROS still needs to be done [Marius and Dave and Catherine]
    - Catherine investigated Gigabit router and will get it soon
    - Look at how to add the robot into Gazebo [Dave and Thomas]
      - Marius noted that there are some examples in ROS for this. Look at the erratic_gazebo and erratic_defs packages.
    - Buy another several bumblebee cables [Dave]