7/23/05:

Yoyo control was implemented in the 3 scenarios in file sound_faf05_jul22_14_day1_2_sec1.mat.

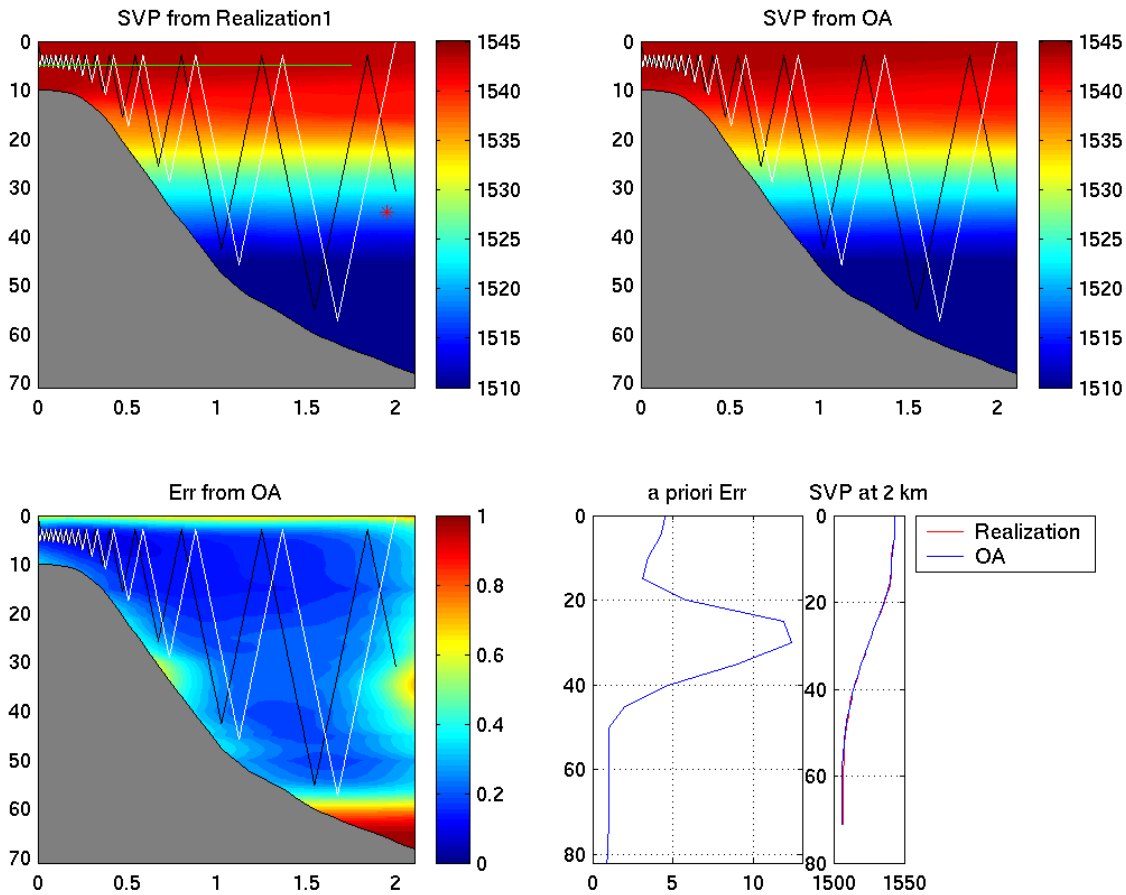## Optimal: points=30, threshold=1000 for morning 7/23/05

Figure 31: Yoyo control implementation. Morning 7/23/05. sound_faf05_jul22_14_day1_2_sec1.mat. Black line is the forward path; White line is the backward path; Red star is the sound source location; Green line is receivers' location. Note that to avoid bottom AUV turns around at 5 m above bottom.

Optimal: points=30, threshold=0.1 for afternoon 7/23/05
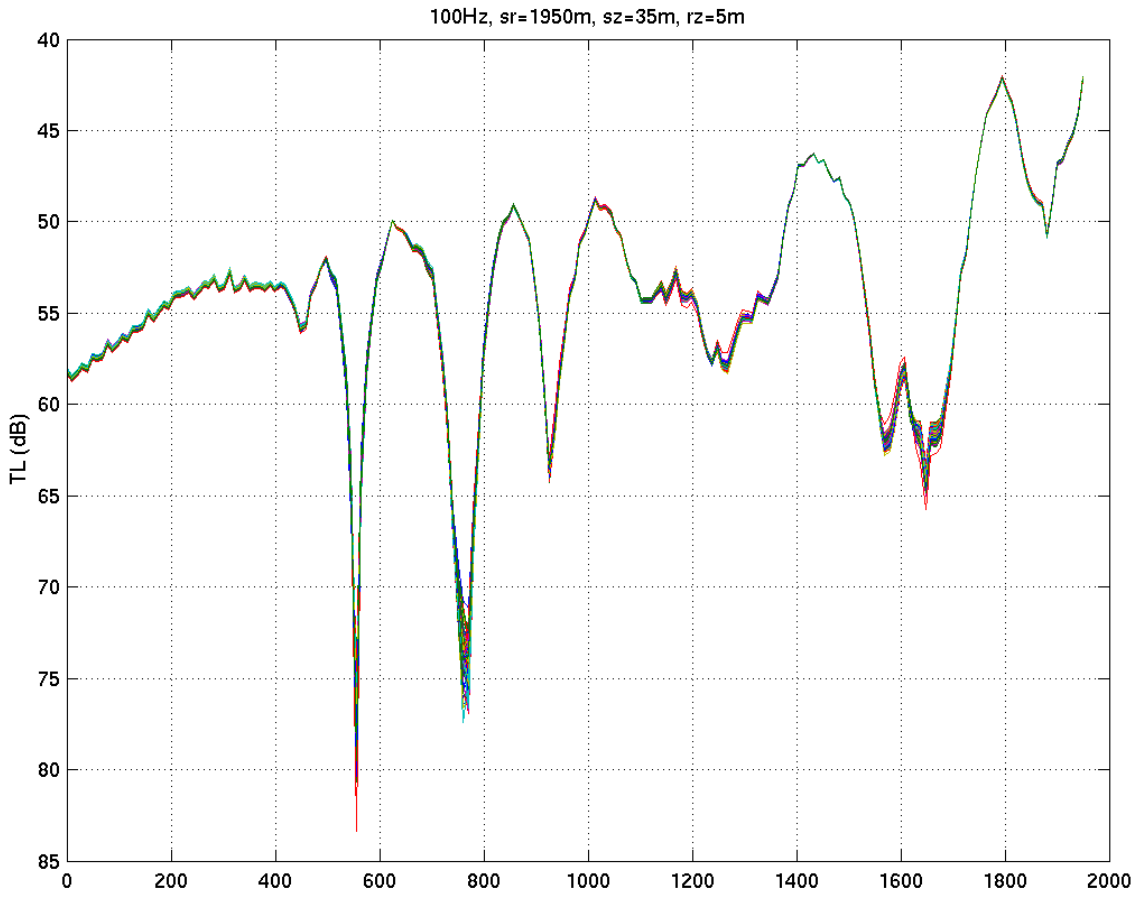**Optimal: points=30, threshold=0.5 for morning 7/24/05**

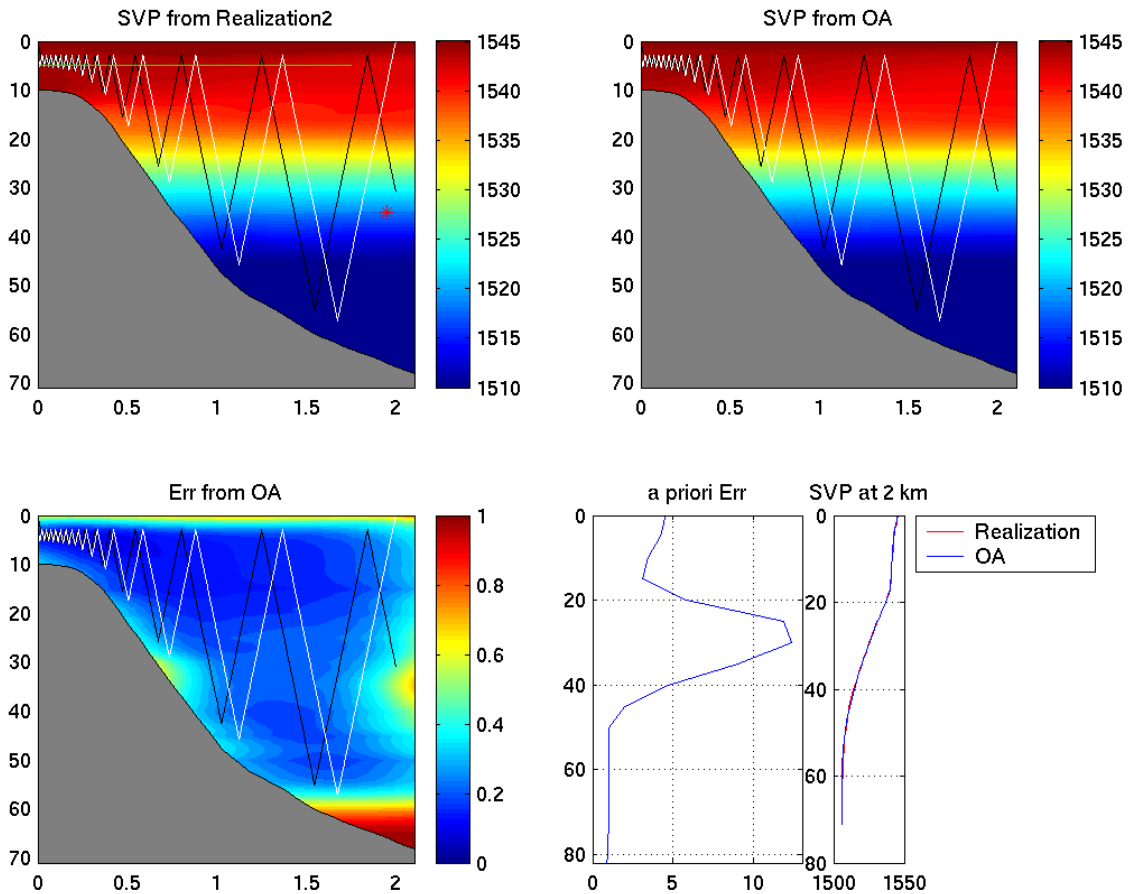Figure 32: Morning 7/23/05. sound_faf05_jul22_14_day1_2_sec1.mat.

Figure 33: Yoyo control implementation. Afternoon 7/23/05. sound_faf05_jul22_14_day1_2_sec1.mat. Black line is the forward path; White line is the backward path; Red star is the sound source location; Green line is receivers' location. Note that to avoid bottom AUV turns around at 5 m above bottom.
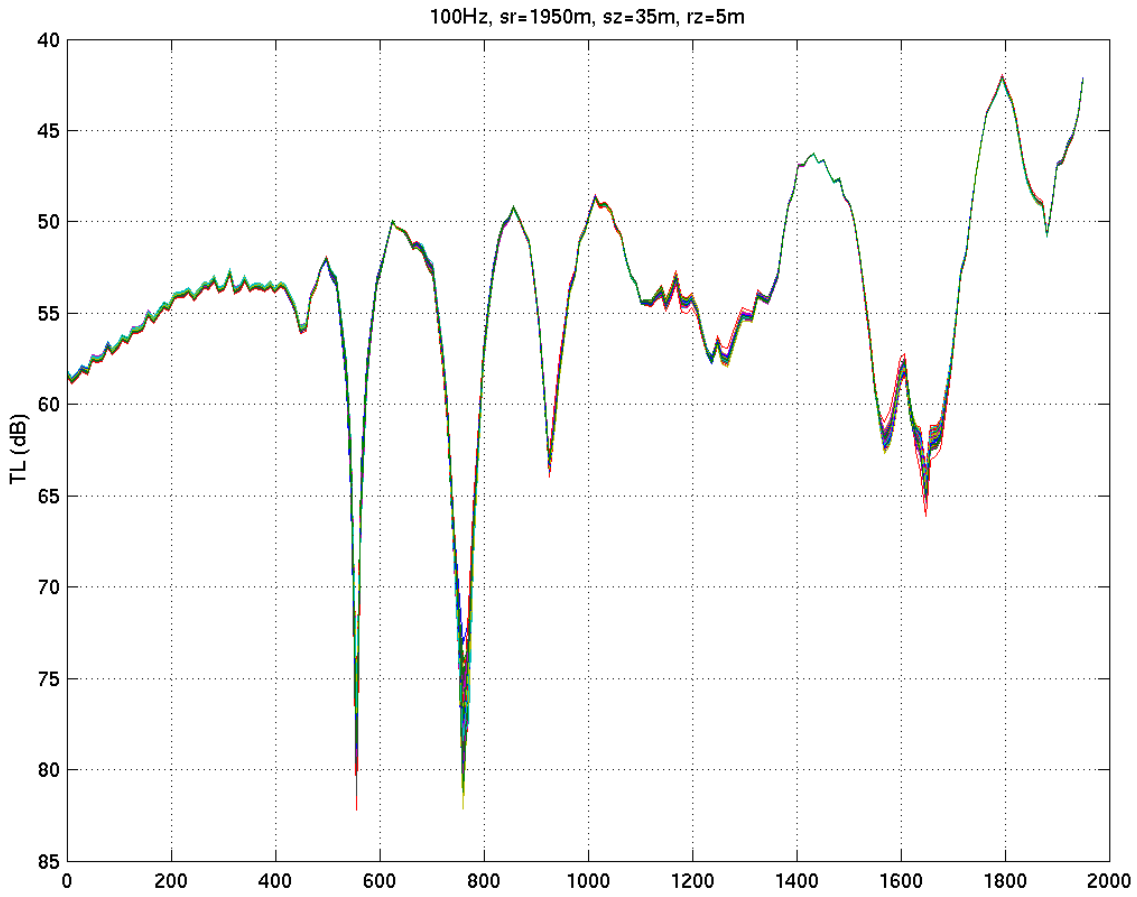
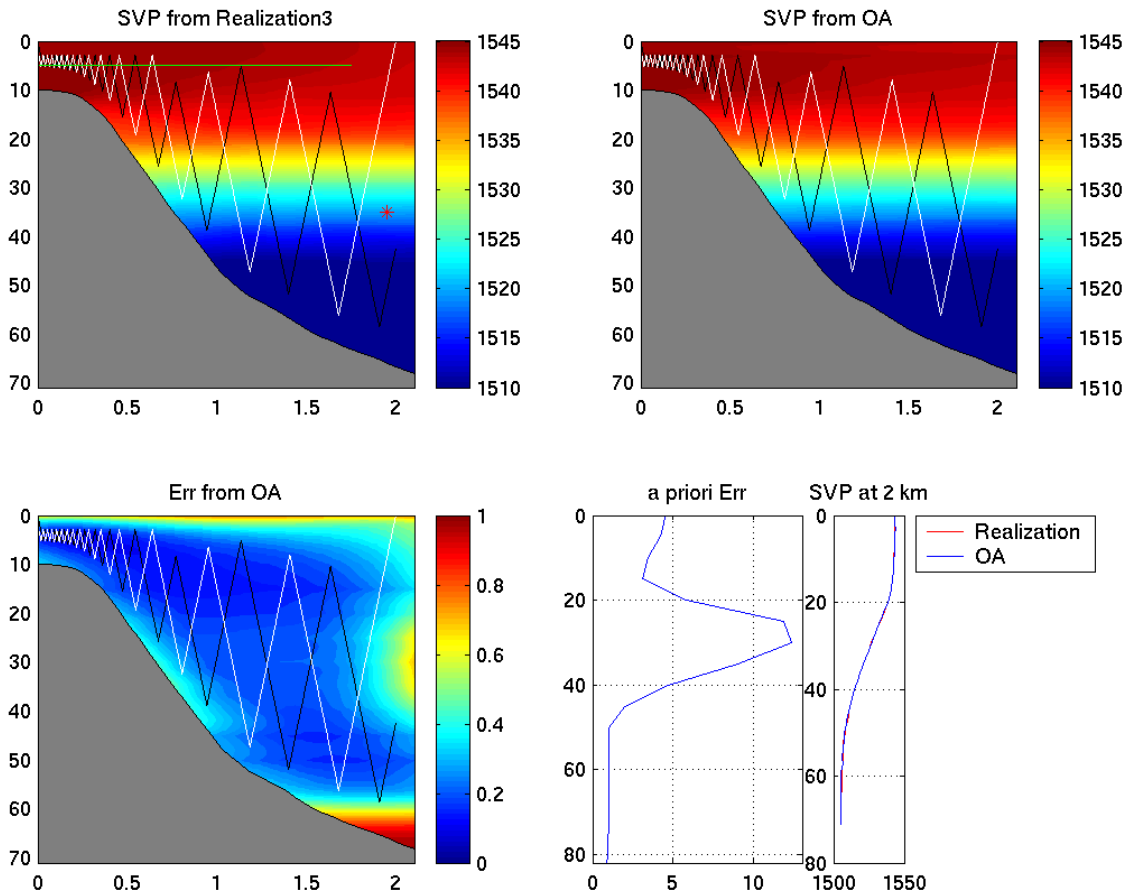Figure 34: Afternoon 7/23/05. sound_faf05_jul22_14_day1_2_sec1.mat.

Figure 35: Yoyo control implementation. Morning 7/24/05. sound_faf05_jul22_14_day1_2_sec1.mat. Black line is the forward path; White line is the backward path; Red star is the sound source location; Green line is receivers' location. Note that to avoid bottom AUV turns around at 5 m above bottom.
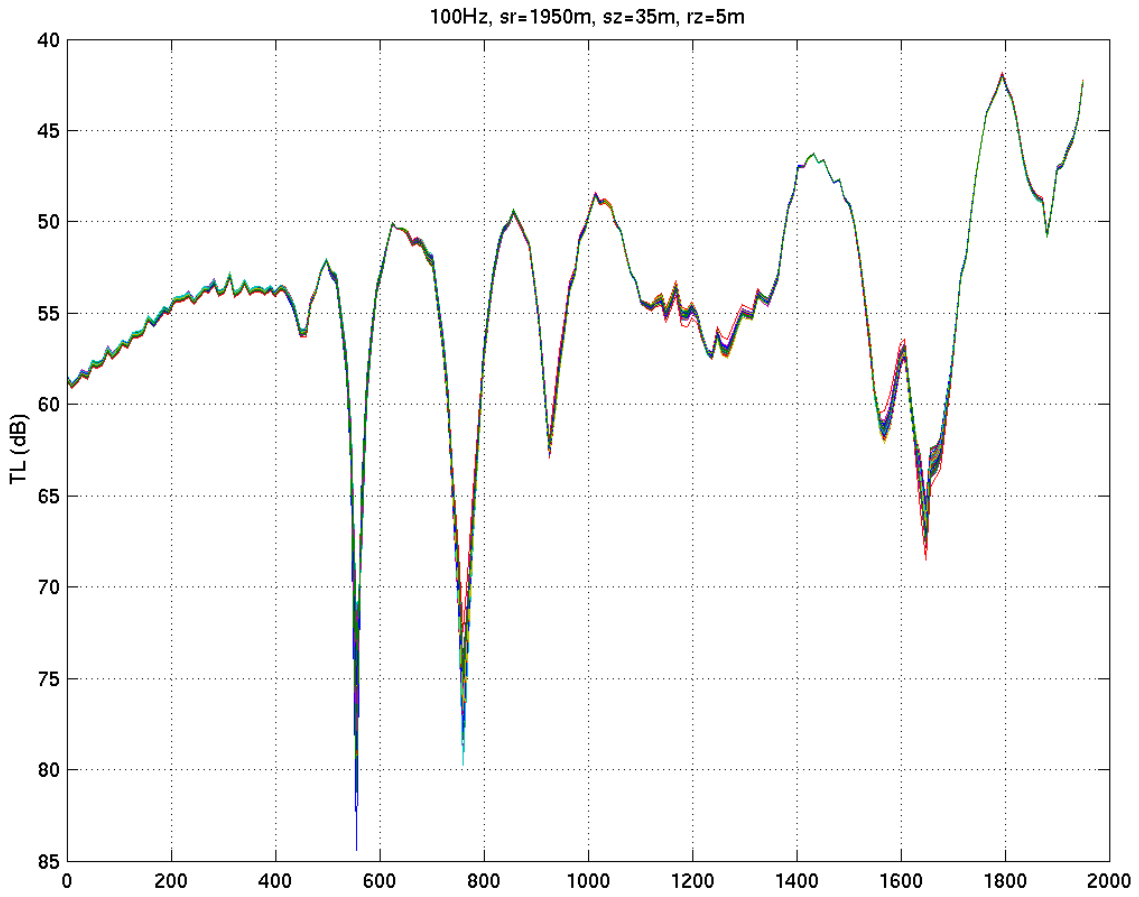
Figure 36: Morning 7/24/05. sound_faf05_jul22_14_day1_2_sec1.mat.