By examining programs and articles that involve UAV communication, I will show that it is possible to effectively implement communication with a boat and a UAV because:

* Communication between any UAV and vehicle is an adaptable language
  + Communication with a boat and a UAV is essential for having a dynamic landing point,
  + Mission objectives do not change for a UAV, so events inside of the objectives will allow for more adaptability
* PID control of a UAV will allow for mission parameter updates:
  + If the variable being tested inside a PID comes from data from a boat, then a constant data stream will need to be established
  + The overall trajectory of the boat could indeed be controlled/updated based upon video feed analysis with a PID