Weekly Summary (3rd Week)

What I did:

- Complied the previous readings into a log sheet.

- Collected data on the number of readings being picked up by catcher.m in one second

- Information on different orientations and offsets at each setting

- Applied butter filter on pitch obtained from the raw acceleration sensor data

- Tried to combine data from both gyro and accelerometer as a way to filter the fluctuations

Problems I faced:

- The values of yaw, pitch and roll keep on changing even if I keep the sensor stationary. This issue must be resolved before starting with measurements.

Possibilities for future tasks:

- Completing the BOSCH device deflection measurements for 14.3 Kgs

- iPhone recordings of 8.1 Kgs and 14.3 Kgs with and without weights at an extension range of 112 cm to 157 cm

- Start measurements using Arduino and look for ways to calibrate it

- Look for the best possible position for Arduino placement to get the least possible error

- Compile the previously done Arduino measurements in a log sheet

Plots and pictures: