# To Do:

* Choose gearing ratio and operating RPM to fall within motor torque range.
* Jason:
  + ~~Extract required torque profile from solidworks model~~
  + Account for friction in required torque model
* Noah:
  + ~~Get wiring for IMU purchased~~
  + ~~Prepare Arduino code for IMU and PID control~~
  + ~~Model Tragectory using matlab~~
  + ~~Requested purchase of Voltage regulator to use drone batteries and balls~~
  + ~~Calibrate DC Voltage Regulator with Oscilloscope~~
  + Sauder Leads to Voltage regulator board.
    - Test with power supply on motor
* Garret
  + Get preliminary cad rolling and cut

# Motor Specs:

1.7 kg\*cm = 0.1229ft\*lbs

Calculation for max power from motor being 9.4 W and motor RPM of 1700 geared down to 30 rpm

Graphical user interface, application

Description automatically generated

Max Efficiency Torque Values

Graphical user interface, text, application

Description automatically generated

# Torque Required:

* Without friction less than 1 lbf\*in
* With friction