

**Department of Engineering Cybernetics,   
Automation Technology Programme**

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| **Course: TELE3001 Bachelor Thesis** | | | | | | **Date:** 24.01.2019 |
| **Project:** Instrumentation of bipedal robotprototype | | | | | | |
| **Activity:** Microcontroller | | | | | | **Activity nr:08** |
| **Starting date:** 11.03.2019 | | | **End date:** 12.04.2019 | | | |
| **Dependency:** | **Past Activities:** | | Joint control  Power supply | | | |
| **Following**  **Activities:** | |  | | | |
| **Goal:** Move all measurements and joint controls over to microcontroller | | | | | | |
| **Description:** Decide placement for microcontroller on the robot frame. Wire all controls and measurement intstruments to the microcontroller pins. Program microcontroller to do the same tasks as dSpace using desired language. | | | | | | |
| **Total Workload:** 220 hours | | | **Work distribution:**  Jakob  Jonas | 110 hours  110 hours | | |
| **Expenses:** | | | | | | |
| **Resources:** Arduino Mega ADK, ADK mounting bracket, wiring | | | | | | |
| **Hazards:**  Motor torque,Voltage | | | | | | |
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