

**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:** IMU calculation | | | | | | **Activity nr:09** |
| **Starting date:** 11.03.2019 | | | **End date:** 12.04.2019 | | | |
| **Dependency:**  IMU | **Past Activities:** | | IMU | | | |
| **Following**  **Activities:** | | System identification  Actuator slack | | | |
| **Goal:** Reduce noise impact and calculate center of mass positions on the body frame | | | | | | |
| **Description:** Measure and reduce noise using digital or analog filters. Use measurements aquired from the accelerometer and gyro on the IMU to calculate positions and angles. | | | | | | |
| **Total Workload:** 330 hours | | | **Work distribution:**  Kristoffer  Endre  Henrik | 110 hours  110 hours  110 hours | | |
| **Expenses:** | | | | | | |
| **Resources:** | | | | | | |
| **Hazards:**  Motor torque | | | | | | |
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