29th May, 2016
11.15 am-2.10 pm IST

# MINUTES OF MEETING

- Resolution Vs Frame Rate to buy a camera.
- Trust numbers, compare with numbers.
- How to debug the problem of Nao giving a yaw angle?
  One solution: make it do slow static walking in which there will be no moment of inertia.
- Debugging method: Think of some hypothesis for your problem. Come up with some experiments to validate your hypothesis. If you can't validate then think of something else.
- Focus on and answer to what is being asked rather than explaining what you did uptill now.
- Find out the resistance of each Herkulex motor.
- Keep back up for the circuit.
- Factory of safety in mechanical system - 1.5X.
- Communication manner: Co-ordinates of camera frame wrt world frame in the world frame.
- Matrix (NXM) is basically an operator which when operated on an mx1 vector, spits out an nx1 vector.
- Optimization Algorithms: Gradient Descent/Ascent-gives the closest local minima/maxima.
- Profiling: Finding out execution time of functions in my code, for optimisation.

## Action Items:

Humanoid Team:

- Setup Gitlab
- Hurocup video and paper
- Wiki.
- Circuit's board file and components ordering.

Robosot Team:

- Localisation using on-board camera.
- Implementaion of basic GPU operation.
- Setup Gitlab
- Controller design and implementation.
- Comparison with ground truth.