* Our reason for this project

* What controllers we have used
  + Impedence controller
  + Admiddance controller
* Estimate the friction terms
* UR doesnt allow us to use the tool command
  + Only partition command and joint command ( use admiddance controller first)
* Use DMP to record human demonstration
* Use the two skills to make a new trajectory
* Keyboard idea is good
  + Evaluate with speed of pressing a sequence
* Use two different methods
  + Gaussian mixture models
  + Gaussian process
  + DMP
  + Dynamical systems
* No need for neural network

* Optimize sequence based on methods
* He'd like some graphs (Fig 2)
* No big difference in using a small or a big robot
* Start with simulation in matlab, or go with python or c++ if we want

* For exam, we need to explain our work well

* Todos:
  1. Implement admiddance controller
     1. Specifiy project first
        1. Alteast three skills and two types
        2. Optimization - deterministic (least squares or QP)
     2. Toy example with mass-spring-damper with 1 degree of freedom and demonstrate with cosine function

* Any questions - make appointment atleast one day ahead and write the agenda and questions.