Meeting 2:

* Admittance control is to record human demonstration
* Motion control is in the robot, so we dont have to create the motion control

Tasks:

Make smooth motions (pick, place and move) using the optimization from merging pos and ori primitive motions.

Optimize the path between pick and move.

Next step is human demonstration

And meanwhile someone else can make the blending

Two different recording methods: DMP and Gaussian mixture models

Last person looks at blending motions

Matlab we can look at the problems in matlab

* We are behind on schedule
* Implement Admittance controller in robot
* Create DMP
* Create GMM
* Create Blend of several skills (start with basic QP or least squares method)
* Deadline is may 12

We have to transform from code from C++ / python to the robot, and how to execute the python script on the robot: You just call it via TCP / IP

UR RTDE (Real time data exchange)

Use move L command using the desired posed at the end of the function.

UR has built in sensor force we can use.