No worry about translating human movement

Identify arm models that closely resemble human arm.

Baseline of code skeleton.

The skeleton oscillates back and form between two points.

Look at kalman filters

Disturbance in kineck can be jump distuance.

Smoothering filter do not work too well, may still jump.

If you use other filter.

Look up on internet, for KALMAN FILTER FOR kinekt.

ELBOW CAN BE 1 degree of freedom.

Same # degree of freedom as human arm, but maybe different structure.

Map trajectory of human arm, to trajectory of robotic arm.

If there is a 1 to 1 mapping than we do not have a problem.

Go to all the model in the tutorial, and see what sort of arm are closely resembled human arm.

Then we can either modify that, or trajectory translation.

What is Input / output structure of this COPPELIA model.

OpenCV of kinect.

How to give input of COPPELIA from something else.

#1 Capture joint angles, from kinect

#2 do we have to capture all joint angles, so that the robotic.

Can a subset of data, be enough for the algorithm.

Come up with a SOFTWARE flow, architecture, from the beginning.

Have a placeholder,

You may need to map coppelia’s trajectories.

Prepare slide, How is referene relevant.

How does it fit