

## Session 17

When I wanted to start the upper arm, I encountered a problem with parasitic noise which made it work abnormally. That said, by reducing the number of cables and connecting the masses, we arrive at a more correct result. Then by continuing my research concerning the MIT inventor, the goal was to create a user interface to make it easier to control but I resolved to establish for the moment that a knowledge of Bluetooth via Arduino the MIT inventor requiring skills in web development, another alternative would be to use a joystick.

To improve the operation of the arm: I optimized the movement by adding a **motorSpeed()** function to the code which adjusts the speed of the motors according to the trajectory of the movements.

Then the current architecture is functional, but the rudders are to be changed every two week maximum due to wear, to counter this problem I started to model new parts which will then replace the motor-arm connections.

We're getting closer to merging the chassis with the arm, so for now we're only focusing on designing the case that will make the connection.