Notes on Camarillo work

-Low level control loops (PD – 100 Hz): Got a motor position in radians. Wrote a motor speed (for a given time step), to move the motor. However since it was per time step it was basically a distance step.

-Motion control with pseudo Jacobian inverse. For each catheter first used Gimp and constructed vectors, then went into MatLab and did a polynomial fit. This gets curvature as a function of motor positions. (dcurve/dq)

Then use geometry to get change in position as a function of curvature. dx/dq = dx/dcurve \* dcurve/dq.

Finally, use np.linalg.pinv to get the Inverse (pseudoinverse).

-Integrate position data back into control ­