

# RNM Project Plan (Group Thursday)

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## Team

- group leader: Alexander Busch
- ROS interface coordinator: Berk Ali Cam

## Vision Team

- group leader: Alexander Busch
- members:
  - Yu Tung
  - David Sattler
  - Alexander Busch
  - Ahmad Saigol

## Assigned tasks

- hand-eye / camera calibration (Work Package 3, 4): Yu Tung, David Sattler, Ahmad Saigol, Junaidali Surti
- Model Recording and Registration (Work Package 5): Alexander Busch, David Sattler
- Needle Path Planning: David Sattler, Alexander Busch

## Robotics and Robot Movement Team

- group leader: Berk Ali Cam
- members:
  - Can Ongun
  - Berk Ali Cam
  - Mahek Panchal
  - Junaidali Surti

## Assigned Tasks

- Direct, inverse kinematics: Mahek Panchal, Junaidali Surti
- Work Package 2 (Trajectory Planning): Can Ongun, Berk Ali Cam

## Time Plan

Week	Milestone	Work Packages and Planned Work
1.5 - 7.5	Direct kinematics	Work Package 1, Explore APIs, simulation of robot, exploring: Point Clouds, OpenCV image processing framework, algorithms
8.5 - 14.5		(Work Package 1), (WorkPackage 2), concrete interface and message specifications, decision on data structures and program structure

Week	Milestone	Work Packages and Planned Work
15.5 - 21.5	implementation of inverse kinematics and camera calibration	(Work package 1), (Work Package 2,3,4,5), inverse kinematics
22.5 - 28.5	<b>Inverse kinematics</b>	(Work Package 2, 3, 4, 5), camera calibration
29.5 - 4.6	camera calibration	Not yet specified
5.6 - 11.6	first lab ;	--
12.6 - 18.6	trajectory planning, hand-eye calibration	--
19.6 - 25.6	model recording and registration	--
26.6 - 2.7	planning of feasible needle paths	--
3.7 - 9.7	Project finalization	--
10.7 - 13.7	<b>Project presentation</b>	--
15.08	<b>Project report</b>	