DATE: \_\_\_\_\_\_\_\_\_\_\_

**INDIVIDUAL PROGRESS**

|  |  |  |  |
| --- | --- | --- | --- |
| Member Name | Accomplishments | Next Week’s Goal | TA Comments |
| Kevin Bradshaw | Designed power system regulation with a new buck converter because the motors were drawing too much current when they were tested at expected high load.  Tested minimum and maximum pulse length ranges for the main three motors controlling the shoulder and elbow. | Connect the entire power system.  Test the minimum and maximum pulse length ranges for the last two motors. |  |
| Fuhua Song | Designed the method of wireless communication between the Kinect, Myo, and Pi to computer.  Was able to remote access Pi through laptop over computer server. | Trying to setup 3rd party DNS service since the university server won’t provide a static IP. Will try to send packages as will through this network. |  |
| Yuan Tian | Designed the Graphic User Interface that can display the tracked skeletal data. Designed the algorithms mapping the human arm movements to the robotic arm movements. Designed the calibration protocols that define and save the range of the mapping process. | Refine mapping algorithms based on tests. Start to research and design the development of interrupt subroutine for the automated movements. |  |
| Zhengshuai Zhang | Be able to control the stepper motor rotating clockwise or counterclockwise at the specific degree from user’s input through raspberry pi. | Trying to control stepper motor from laptop and set up Myo gesture recognizing code. |  |

DATE: \_4/15/16\_\_\_\_\_

**PROJECT STATUS SUMMARY**

**MAIN ACCOMPLISHMENTS**

|  |
| --- |
| * Overall system is built. * We have two Raspberry Pi’s that are being tested successfully with wireless and control codes. * Subsystems are on track to meet Preliminary Test Plan Goals. |

**MAIN PROBLEMS/ISSUES**

|  |
| --- |
| * PWM Driver only works in Python. May switch control for PWM by GPIO pins only. * TAMU network doesn’t provide with at static IP address for connected devices. * The vector calculation for the Kinect is taking a lot of time and testing with different methods. Not sure if we’re processing the best accurate representation available. |

**TEAM DYNAMICS**

**Answer Y or N to each question**

|  |
| --- |
| * Are all members on schedule with their respective tasks? \_Yes\_ * Are all members contributing equally to the efforts of the team? \_Yes\_\_ * If any member is behind schedule, has this occurred consecutively more than one week? \_No\_\_ * Would you like to schedule a meeting with any of the TAs to address issues related to team dynamics? \_No\_\_ |