Patterns of forces and positions for polishing.

No hardware, but hear Christopher.

Generate force and motion in matalb use GMM and see how simulation works. If works in simulation it can be extended to hardware.

Develop in matlab.

Structure of report will be announced at a later point in time.

Yitaek has text book about skill transfer learning. (DMP, SEDS)

Create forces with mass spring damper system in simulink.

Use 3d point cloud from CAD model to compute contact points.

Start with plane as model, then move to something with curve and then something with multiple curves.

How to make model of polishing task – Yitaek has paper that explains how to simulate.

Hybrid controller with alot of pid controllers at each axis.

Admittance controller can also be used.

Simulate admittance controller with 1 dof in matlab.

Modern robotics book.

Start by estimating contact forces.

Find threshold and constraints for forces.

1. Generate forces and positions
   1. We need a lot of demonstrations even in simulation (10). These should be very alike
2. Use DMP or like
3. Regenerate forces and positions
4. Create controller for robot

For demonstration we need to have it implemented on a real robot.

Contact Yitaek for acces to lab. Anytime.

Demonstration is pysical at the robot.

Practical issues? Contact Yitaek

Meetings every second week. Tuesday at 9

Write plan for every week. What do we want to achieve this week and next week?