MEEn 537

Craig Bidstrup, Jae Lee

Objectives that would define success   One arm of Baxter successfully track and reach close enough to a participant's hand to handshake. Be able to follow the participant's hand motion.

Pitfalls or concerns   We will have to figure out how to use Baxter's head camera to guide the arm so that the target is in the field of view of the wrist camera. We are concerned that distance from the wrist camera to a participant's hand will be difficult to discern. Another unknown is a good motion planning algorithm to get the wrist from its current position to the target position without undesireable motions.

Timeline and role

1. OpenTLD using ROS - Nov 15(Jae)

2. Working Gazebo simulation of Baxter - Nov 15(Craig)

3. Implement motion planning algorithm - Nov 17(Craig, Jae)

4. Integrate OpenTLD with Gazebo - Nov 22(Craig, Jae)

5. Migrate to the Real Baxter - Dec 1(Craig, Jae)

6. Generate report and presentation - Dec 5(Craig, Jae)