Nikolai Thesis

* Control block diagram (p. 37)
* Algorithms
  + Halley’s root finder – 22us
  + Kinematic lookup table – 9us
* Desired control loop frequency – 1kHz
* Errors
  + Hall sensor
  + Harmonic drive backlash ~0.1 degree
  + Hand measurement
  + Joint looseness
* Optimizations (4.7.3) (5.9.1)
* Timing (p. 62)
* RR implementation/equations (4.5.3.2)
* Instability solution with 2nd encoder (4.5.5)
* Milling configuration/angle of attach (p. 92)