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| **Date** | **Comment** |
| 1/5/2010 | Tony went over the CFP and noted things that need to be corrected.  Things to do for next meeting:  -correct and update CFP  -preliminary design of electrical/software components  -preliminary design of mechanical components  Tony will follow-up on Friday to check on progress. |
| 1/12/2010 | choose motor for “performance”  -compensate inefficiencies with transmission, etc  stepper motor  -motor force maybe insufficient to move against force of load  CFP  -“tweak” and append updated findings  Gravity compensation  -in analysis, find gravity as a function of theta  -weight maybe more or less neutral, look into disengagement mechanism for when surgeon wants to remove hand from tool |
| 1/19/2010 | -should check with Chris for what kind of control system he is looking for  -TAR  -analyze design parameters  -for PID, model the system and predict the error  -how to determine the damping?  -how to determine the accuracy?  -evaluation against evaluation criteria  -motor  -loads on the motor  -tool interaction , tool weight, friction, inertia, hard constraint  -steady-state/pulse limit?  -motor curves  -impacts of decisions on the evaluation criteria  -weight  -cost  -size  -went over interesting concept of a system’s parameter matrix |
| 1/26/2010 | -discussed about the choice of materials to use  -aluminum can be used if it is justified  -stainless is perhaps a better choice overall  -need to do FMEA to determine possible ways the device can fail  -control system can be implemented on a ARM 32bit microprocessor system |
| 2/9/2010 | TAR  -how the implant size drives the design size?  -where are the happiness charts?  -tradeoff between workspace and size?  -not enough proof  -adjustable mechanism for performing double uni-compartmental cuts  -mention but don’t pursue  -don’t paste spreadsheets as is!  -clearer diagrams  -eg. Label sagital view  -which way is gravity?  -gravity compensation  -f(theta)?  -graphs superimpose function to show comparison  -show that radial gravity compensation is optimal  -motor selection  -what assumptions based on?  -more details (conclusions) in captions  -use plots instead tables of values  Control system  -check how to get license for QNX  -check with Leo Stucco?  -OK with ordering beagleboard  Design  -discussed about preloading bearings and bearing orientations  -tony looked at the current design and gave suggestions on designing the links |