Requires computer lab

* Abstract does not exist
* 3.3 Figure 14 – make ‘+’ bigger
* 3.5 needs notation to be revisited
* 3.6.1 needs math added
* 4.2
  + 4.2.2.1 at the end add info on spec of stepper motor used and image of the stepper label
  + Software needs expansion but need feedback
* 4.3 needs work/feedback
  + 4.3.1 FBDs to show what forces each set of joints will see?
* 5 Needs expansion on most of the tests
  + 5.2 Velocity testing does not have results
  + 5.4 “wobble” section is empty
  + All testing needs to have conclusions drawn
* 6 conclusion needs to be written
  + here is what I did
  + here are the results
  + here is how it can be improved
    - Future investigations type thing
      * Lower joint assembly non-parallel to base plate to minimize likelihood of singularity
* Appendix A Need to generate doxygen manual
  + need to make sure code is in correct format
* Appendix B Need Matlab Code with instructions
  + center of mass within reasonable boundaries
  + actuator not perpindicular to base plate (within a variable angle)
  + test each point with image rotation=0 and +/- variable angle
  + test leg lengths are valid
* Appendix C Need to output drawings of any parts I made
  + Motor Adapter Plate
  + Motor adapter spacer
  + Updated shaft couplers
  + 8020 frame
* Need to make tense and capitalization consistent throughout the paper
* Stuff I don’t know where to put:
  + Limitations of current/future system
    - Numeric for current system
    - Future:
      * Only reach a limited area of sky (alt az)
      * Maximum exists for length of tracking due to limit on image rotation
  + “Not sure where's the best place to mention it, but there are many reasons why the mount will usually not be aligned with (0 , 0 , 0 ), including the difficulty of putting a portable mount at a precise angle and the fact that for most astronomical uses, the Meridian toward the South is prime observing territory, so that 0 = 180 for what is most likely the closest to an ideal configuration.” - ridgely