**Week 15**

**TEAM MEETING**

***Cameron,*** *Diogo, Jose, Samuel, Yujui, Lio*

## Notes from meetings throughout the week

**Electronics**

* Start clearing up some cables and organizing different components

**Software**

* Developed new calibration for weaker magnets

**Magnet**

* Developed non-holonomic magnet
* The result feels like a bouncy wall
* The motion control, seems like it’s would to be very complex

**Mechanical**

* Machining new links
* Making the structure more rigid

## Meeting with Professors

**Manufacturing/Mechanical**

We need to make the second arm work - even without the multi-touch… but how? Should one of the arms be back drivable

**Magnets**

* Put the shaft at the center for the non-holonomic repulsion prototype
* Try the electromagnet as a later option
* Non-magnet idea be the last idea

**Electronics**

* Rearrange cables and make the layout cleaner

**Embedded**

Idea of new demos: they need to make sense for one of the magnets to not be back drivable

* 1 puck full haptic reactic control
* 1 puck that drives around the screen without user haptics/ position control- hopefully backdrivable after the gear boxes are removed
* Idea 1: Spinning wheel with passive magnet - knob controls speed of the wheel and the other one is independently moved
* Idea 2:Angry bird type demo / spring effect followed by the robot moving the magnet to the impact placement
* Idea 3: Equation demo, where one of the magnets slides and the other follows the curver