**Week 16**

**TEAM MEETING**

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

## Notes from meetings throughout the week

Recently Completed Tasks

* Put electronics down to a plate
* Added Acrylic walls on top and front
* Tightened gearboxes
* Finalized arm links
* Finalized Demos: Equation Feel and Knob
  + Equation Feel: The weak haptic magnet is constrained to a line, basically the “x axis”. The user can freely slide on the line but not away from it without experiencing haptic feedback. As the user translates the weak magnet on the line, the strong, non-haptic magnet stays at the same x value as the weak magnet, while it fluctuates on the y-axis to demonstrate the shape of an equation.
  + Knob: may be fleshed out slightly more: user can move “freely” with the weak magnet along the edge of a knob, which will click into detents every so often. The strong magnet is across the circle from the weak magnet, dragging the user along with it.
* Finalize the calibration strategy: physical fixture

To-Do based on discussion with professors, Tasklist moving forward.

* Manufacture physical fixtures for calibration
* Assemble new arm links onto robot
* Square-up robot
* Add additional protection on sides(could be cardboard/foam core/anything
* Implement software for calibration
* Implement software for both demos(Lio will start working on GUI as the robot finalizes)