This week we have got Aibo up and running. We have tried out a few different Open-R programs to see how to implement them and also successfully used TelNet to access the dog. We haven't yet got Tekkotsu to work but we have decided to give Urbi a shot or if that fails, to use Open-R for all programming purposes.

Furthermore we have had a discussion about what the other teams working with GoAibo have accomplished and what kind of obstacles they have encountered.

This has inspired us to direct the project into developing some sort of speedometer for Aibo which can be used for it to measure its own performance and adopt accordingly. Since this could be a pretty big task in itself we will mainly focus on this and not on developing a gait for a specific surface.