Weekly Status Report 2009.04.07

Group One.
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Project: Smooth walker.
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Done this week.

- Finished the motions controlling function. We made a new OpenR object for reading commands from the web console and sending the commands to the MovingLeg object. Now we can send start, go, and stop commands to the robot. And the application is easily to be extended to have “Turn right”, “Turn left” and “Turn back” commands.
- Researched on the image analysis parts.

To do in the next Week

- Analyze the image to estimate how the current gait walks.
- Optimize our gait, try to let it work more stable and faster.
- Design turn left and turn right gaits.
- Research on how the accelerometer works and find out if it is good to use that in our solution.