Weekly Meeting Report

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1 Meeting overview

In this meeting, parameter estimation was discussed in detail. It was decided that a nonlinear least squares estimator would be used for estimating the parameters of the system. There weren't any questions regarding the mathematical model until now. The group is currently working on a simulation of the mathematical model provided by Roxy in the previous meeting.

The reading on the Kalman filter has been continuing on a good pace. The group understands Bayesian filters, and is ready to move on to one-variable Kalman filters.

The hardware has also arrived. Work on the physical model is expected to start next week. The group has already seen some possible designs for the hand grip trainer.

1.1 Conclusions from the meeting

- Nonlinear least squares estimation will be used for parameter estimation.

- The hardware has arrived. The group has already begun with the design of the physical model.

- Reading on the Kalman filter has been going on as planned.