

Miscellaneous

- Our focus should be mostly on the tiger design, not air muscle design.
- We should update our files as we go (risk assessment, specs, schedule, etc.).
- Keep the website updated.

Analytical

- Look at cat muscle attachment points. Nature has already figured out good attachment points.
- Follow up with Bill Spath about his analysis techniques with Minitab (Nova – lectures 4 and 5 in Bill's notes) that will help determine the most important variables and how the variables relate to each other.
- In our MATLAB simulation it will be useful to leave center of mass locations for each link a variable. COM locations will not necessarily be at the geometric center of the link.

Testing/Hardware

- We should have leg prototypes for the detailed design review (week 10).
- Ask the foot orthotic MSD group about the testing info (particularly about tube thickness).
- Check with Professor Wellin about his testing resources (Labview VI's, **load cell**).
 - Check with physics department for a load cell if Wellin doesn't have one.
 - Without a load cell, obtaining air muscle forces may be done by loading the muscle until the point that the muscle cannot lift the load.
- Use the plastic custom machined air muscle fittings from the ant; these fittings hold up well and schematics are available if more need to be made.
- Look into the Arduino board's frequency; will commands from the board be fast enough?
- If using parallel muscles on the each leg, consider placing one muscle on each side of the leg. This will help with the limited space available on each leg.
- To handle filling muscles in parallel, it may be useful to assign separate smaller tanks to each muscle.