I. Summary of this week
   • Discussed our calibration method, the rectangular plane/plate method
   • Developed an outline of this method
   • Started to identify individual steps of this method, and list them

II. Overview of next week
   • Further develop the plane method and determine feasibility
   • Meet with Dan Spieker to determine if our method is acceptable
   • Install and wire the sensor into a robotic system
   • Perform basic power and I/O tests on the sensor.

III. Team meetings and project work next week (10/13 - 10/17)
   • Monday: 5:00-7:00 @ CSU
   • Wednesday: 5:00-7:00 @ CSU
   • Friday: 1:00-5:00 @ Wolf

IV. Upcoming deadlines and deliverables
   • Wire and mount sensor - 10/17

V. Comments
   This week we only had a few hours to spend on our project as Asa and Kaden had a midterm on Friday during our usual project time. We did manage to come up with a method for calibrating a TCP for the sensor. The method uses a rectangular plate placed roughly perpendicular to one of the robot's base coordinate axis. Then using the distance data from the sensor, rotate several times to determine rotational position. After rotation has been calibrated, the robot can use the midpoint of the plate to calibrate the position, and pass in 5 points to the ABB routine that calibrates a TCP. Extensive testing and feasibility studies will have to be conducted to see if this method will be accurate and efficient. -Kevin B.