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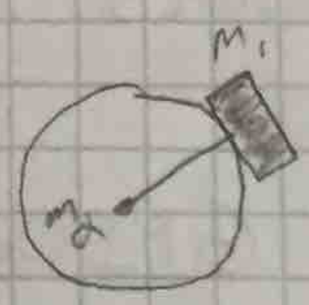
- figure out control system (type)
- figure out motion



$I_1 = m_1 r^2$

$I_2 = \frac{2}{5} mr^2$ (solid)

$I_2 = \frac{2}{3} mr^2$ (Hollow)

Dynamics of motion

$m_1 >> m_2$

$m_1 > m_2$

$m_1 \gtrsim m_2$ ☆

$m_1 < m_2$

$m_1 << m_2$

Inertia of Bucket Ball

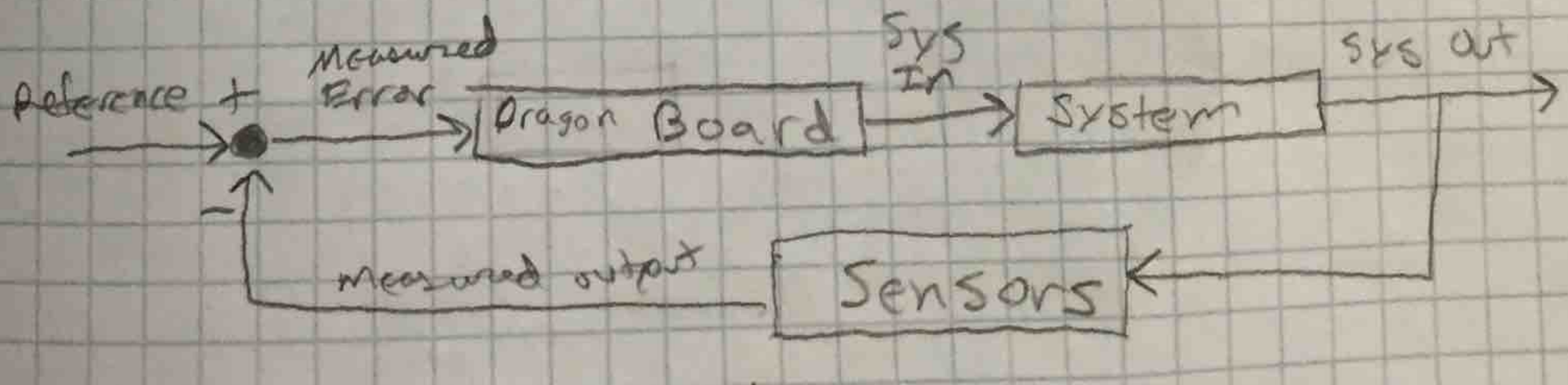
$I_2 = \frac{2}{3} mr^2$

$m = 0.625 kg$

$r = 0.24 m$

$I_2 = 0.024 kg m^2$

Negative Feed Back loop



Controller - Dragon Board

System - motors, movement

Sensors - gyro, accelerometer, tilt sensor

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update:

- negative feedback (control system)
- In process of working on Dynamics
- Dragon board is setup
  - just need to fix the GPIOs
- Sensors:
  - tilt sensor
  - gyroscope
  - accelerometer > IMU

- Is python fast enough?
  - maybe use C