



WPI

Assistive Guitar Plucking Device and User Interface

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Abstract

Every individual should have the opportunity to experience musical creation; however, not everyone can play instruments as they are designed. Music provides people an avenue to express their emotions and has been shown to stimulate the brain in uniquely beneficial ways. Very few products exist in the marketplace that enable accessible means of music playing; yet, millions of individuals in the United States live with physical disabilities. The goal of the project was to develop a wireless, battery-powered device with a plucking mechanism and a wearable user interface (UI) that would enable individuals with physical disabilities to play a guitar. The device is to be used in conjunction with a guitar fretting device built by the project sponsor, Kurt Coble. The plucking mechanism, mounted to an adjustable frame around the guitar, has 3D printed plectra to actuate each guitar string, driven by servo motors. The inertial measurement unit based UI is comprised of two wearable devices that calculate which strings to pluck, by using sensor fusion to track user motion and device orientation. With devices that are wireless and battery-powered, they may be used in a variety of settings. This project provides an opportunity to create music for individuals who have not previously had access to this experience.

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Introduction

For people all around the world, music is a way to express oneself and one's emotions. Many cultures have a rich musical history that includes different styles of playing or unique instruments. Unfortunately, many individuals struggle to play more complex and traditional instruments because of a physical or cognitive impairment. Currently the assistive technology devices available for sale are either expensive, very limited in functionality, or were designed for a very specific type of impairment that limits who may use them.

Kurt Coble, a professional musician from the greater New York City area, has explored assistive technology in the past. His first device was built as a demonstration for children, which consisted of a puppet that used string to pull a bow across a violin. From the success of the puppet violin, the Partially Artificial Musicians Band (P.A.M. Band) was born (Coble, 2015). Since 2007, Mr. Coble has traveled around the world demonstrating his multitude of creations, which include adapted violins, drums, guitars and more.

While Mr. Coble has created a device that can play chords and strum a guitar, he does not have a device that provides an individual the ability to pluck individual strings. This project's goal is to fill that gap by creating a single assistive device that will allow a user the ability to both strum and pluck enough notes that they will be able to play songs such as "House of the Rising Sun", as performed by Eric Burdon and The Animals (Burdon, 1964). This assistive device will consist of two parts, the user interface and guitar plucking device. This will be paired with Mr. Coble's existing fretting device such that the user can play chords, strum, and pluck a guitar.

Background

In order to effectively design an assistive guitar, several subjects must be considered. This chapter will discuss music, especially the operation of guitars, to understand how a mechanical solution will play the guitar in a way simulating a human user. Then the nature of disabilities and the methods by which assistive technologies are designed will be presented to ensure that the design will fit the needs of the intended users. Finally, existing technology is reviewed for insight into ways to solve the problem of an assistive guitar.

Guitars and Music

Although there are many types of guitars, varying greatly in physical construction and sound produced, the guitar used for this project is a wooden, six stringed, acoustic guitar. For that reason, some of the information presented is specific to this style of guitar. A basic diagram of a guitar is shown below in Figure 1. This labels the components of a guitar that will be discussed throughout this report.

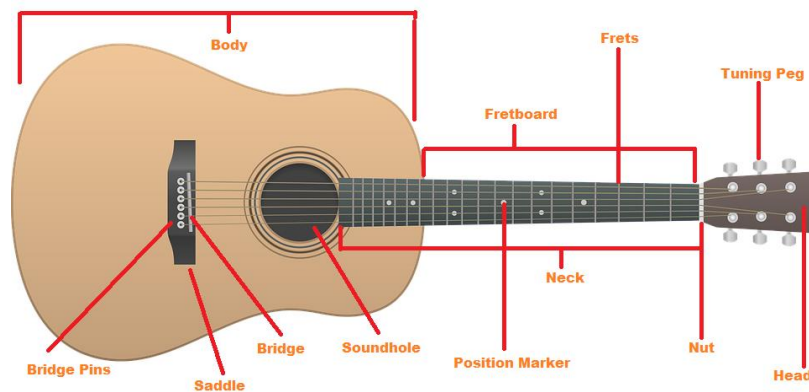


Figure 1: Guitar Diagram (Tabuena, 2018)

Sound

Guitar music, as with other sound, is created via vibrations. Vibration of the guitar string creates a pressure wave in the air by pushing air out of the space it occupies and leaving behind a partial vacuum. Pitch is the perceptual manifestation of frequency. The tension, length, and thickness of a string change the frequency of the pressure wave, therefore affecting the sound produced. Amplifying the sound can be accomplished with more force and larger displacement of the string. Longer or thicker strings vibrate more slowly and create a lower frequency of sound. Strings with higher tension vibrate more quickly and create higher frequency sounds (MIT OpenCourseWare, n.d.). This concept allows the guitar to be tuned by winding more or less tension into a string.

The pressure wave created by a vibrating guitar string is not large enough to create the magnitude of noise that the ear hears when a guitar is played. The soundboard of a guitar allows the vibrations of the tensioned strings to displace enough air to produce a sound with sufficient volume. The energy of a vibrating string is transferred through the saddle to the body of the guitar. The saddle also acts as a selective filter, permitting only certain frequencies to pass. The structure and placement of the saddle are very important to passing the proper frequencies. The soundboard that makes up the body of the guitar then vibrates, displacing enough air to give the guitar its volume. The characteristics of the saddle and soundboard are important to the quality of the sound produced. The air within the cavity of the guitar and the support structures also influence this sound. The pressure waves reflect off the back of the guitar body so the acoustic properties of this panel are also important (Graph Tech News, 2017). Although wood is the most popular material, fiberglass and other alternatives are also used.

Introduction to Guitar Music

Guitars are traditionally played with both hands. One hand excites vibrations in the strings near the sound hole by either plucking or strumming. The other hand controls the chords that are being played via fretting. Plucking is a technique typically used on one or more strings to produce a single note. Strumming is three or more strings (usually all six) played consecutively in one continuous motion. Strumming patterns involve motions in both directions perpendicularly across the strings and parallel to the face of the guitar and can be used in combination with plucking. One common example of this is where the base note of a chord is plucked while the rest of chord is strummed. Typically, both techniques are used in tandem through a piece of guitar music. Fretting is used to control the sounds produced when a particular string is excited. The wavelength of the harmonic is changed by depressing a string against the fretting board, thereby changing the length of the string under tension, and consequently the frequency of the sound produced.

The device used to interact with the guitar string is known as a plectrum. As the vibrations of the string will be amplified through the body of the guitar, the details of this interaction are important to the sound. One important aspect of the plectrum is the flexibility of the material and thickness of the plectrum. The more flexible and thinner the plectrum is, the less force the plectrum exerts on the string. This would cause less displacement and less sound clarity (Tuttle, 2007).

As previously mentioned, playing music can be a powerful tool of expression. Guitars are a versatile instrument and be used to play diverse music. The instrument is most easily played by individuals who have well-developed motor control and the ability to understand complex timing relationships between notes. These user requirements leave some individuals with physical or cognitive disabilities unable to play the guitar.

Disability Classifications

A disability is a condition that affects a person's day-to-day life activities and may be present at birth or acquired later in life. Disabilities can be highly specific and unique to individuals; however, this coding leads to six general types: physical, visual, hearing, mental health, intellectual, and learning (WHO, 2011). For this project, a user interface supporting those with physical limitations that would prevent them from playing the guitar will be prioritized. This encompasses several different impairments; potential users may have missing portions of or limited dexterity in their upper limbs. Such conditions may be caused by a variety of conditions including such as birth defects, illnesses, injuries, strokes.

Benefits of Playing an Instrument

How Music Stimulates the Brain

When researchers tested how a brain reacts to listening to music, the result was significantly different from tests of other tasks, such as reading or computing math problems, as the brain displayed activity in more areas. All this activity is due to the cognitive processes that happen as an individual processes the sound, dissects it to comprehend the rhythm and melody, and then unites it back together into music (Anderson, 2016). Listening to music is a complex process that involves many different brain regions such as the auditory cortex, frontal, temporal and parietal lobes as well as the subcortical regions. By causing activity in these regions, music is able to have a wide range of effect on cognitive functions, like attention and memory, and motor functions.

Benefits of Playing Music

After observing the effects of *listening* to music on the brain, scientists then began studying what happens to the brain while a person *plays* music. They observed that listening to music stimulates multiple parts of the brain, while playing music causes the brain to experience a significant increase in activity. Many parts of the brain are used because of the cognitive demands of playing the instrument, which include motor skills, linguistic and mathematical precision. Studies have shown that musicians are more likely to exhibit enhanced memory function, such as planning, attention to detail and strategizing (Anderson, 2016).

Using Music for Rehabilitation

Due to all its stimulating effects, music is often used in neurological rehabilitation. Many people suffer from damage in one or several areas of the brain that can make it hard to respond, or difficult to process information. With patterns emerging between musicians and increased cognitive functions, as well as the elevated brain activity produced when playing instruments, scientists began to delve further studying music therapy. There are two types of music therapy. With passive music therapy, the patient only listens to music that is selected for them by their therapist. Active music therapy is usually a musical improvisation that occurs between both the patient and their therapist. This can either be done vocally or with instruments (Vinicola, 2001).

Due to the cognitive and physical demand that comes from playing a musical instrument, music therapy for rehabilitation of cerebral palsy (CP) patients is becoming popular. CP is a classified as a group of disorders that affect a person's ability to control his or her muscles correctly. Symptoms vary from person to person; however, all people with CP have issues with both movement and posture. There are many that also have other related conditions such as intellectual impairments, recurring seizures, problems with seeing or hearing, or even spine

issues (Basics About Cerebral Palsy, 2018). It is believed that active music therapy can be an efficient way to help with the development of motor skills for people with this early brain damage, which in effect will help people who suffer from certain types of CP see improvement in their daily movement (Alves-Pinto et al., 2016).

Music therapy is also very popular for stroke recovery. One of the long-term consequences that could occur after a stroke is reduced and impaired arm function. Studies have shown that repetitive and high-intensity task training is most likely to improve arm function; however, it is extremely physically challenging for patients to practice long enough for the technique to be successful. In order to combat the demanding nature of these repetitive tasks, some rehabilitation programs implement rewarding activities such as playing music (Wijck et al., 2012).

Assistive Technology

Assistive technology is an umbrella term covering both newly developed products and modifications to existing products that are developed to help people with disabilities complete tasks related to daily living activities, employment, education and recreation.

Design Methodology

There is no set methodology for the design of assistive devices. Case studies reveal a variety of methods are prevalent (Magnier et al., 2012). The seemingly most universally used method is User-Centered Design (UCD). UCD is the approach of considering the user throughout the design process. The goal of this process is to find a solution custom to the individual's needs and avoids traditional solutions that may be "heavy and embarrassing" and "reinforce isolation feelings and the people's inadequacy with disability, contributing to their stigmatization" (Mallin and de Carvalho, 2015, p. 5571). What sets UCD apart from other design

methodologies is that the user is a part of the design process and provides feedback throughout the design process rather than providing feedback when the process has been finished, as shown in Figure 2. Procedures to follow for UCD include specifying context of use, specifying user and organizational requirements, producing designs, and completing user-based assessment (Mallin and de Carvalho, 2015). UCD allows for designs that maximize a user's comfort and ease in using a product; however, UCD typically minimizes the number of users it may appeal to as the designs become so specialized.

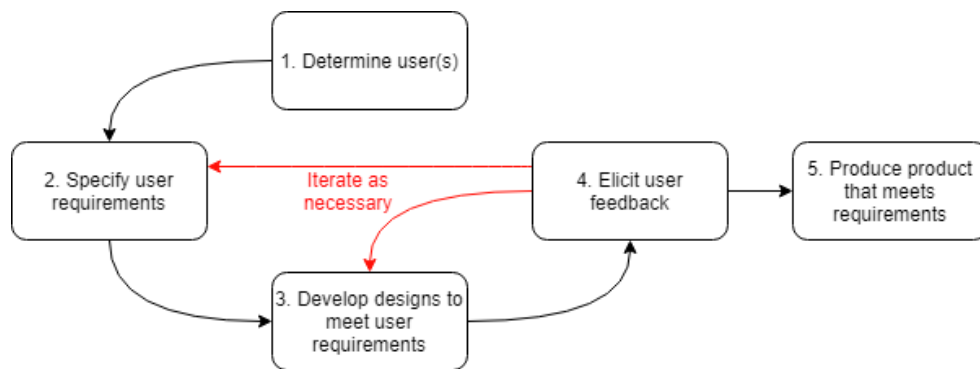


Figure 2: User-Centered Design Process

Motion analysis is another common method of developing accessible technology that may lead to more universal designs. Motion analysis requires the investigation into the types of actions performed throughout a task, often through observation. From there, movement difficulties can be identified, and substitutions can be made. In a case study about a hair washing device for individuals with limited shoulder mobility, it was determined that the motions required throughout the process included frontal flexion and horizontal extension. With lessened shoulder mobility, users felt lumbar and neck pain when bending to compensate. In this study, the feedback about user discomfort helped the engineers determine that the device needed to be operable when the users are in a more natural position (Wu, et al., 2009). Motion analysis does have the drawback that designs are often developed that still require users with strong motion

control, as the substituted motions generally still require the same precision as the original task. For guitar playing, traditional motion analysis will not be an adequate solution as the task is set, and cannot be easily modified without affecting the resulting sound. However, a hybrid motion analysis can be performed such that the device will be designed to mimic a human pluck and then the user's motion capabilities are accounted for in the interface.

Considering Mr. Coble's previous users, UCD and motion analysis both provide relevant design tools for this project. UCD must be used in moderation, as the project's goal is to enable a variety of users to use the device. UCD is still important to developing the project, as taking feedback from a variety of potential users throughout the design process will help determine the best designs. Motion analysis of plucking a guitar string will be essential to developing a device that can create a natural sound. Motion analysis of the range of motion of users will also be important to find an appropriate setup for the user interface. It is important to understand how users move to make the system as comfortable to use as possible.

Digital Music Devices

A number of devices currently exist to allow individuals with disabilities to play music. One of the more common methods is through digital music software and MIDI-compatible user interfaces. MIDI data encodes specific notes rather than tones or sounds, so the same set of inputs can be used to play any tonal instrument, typically virtually. However, a computer must interpret the data from the user interface, so any MIDI device would require additional processing to operate a mechanical instrument, which eliminates real-time music playing.

The Soundbeam is an interface device designed to adapt to different ranges of abilities (The Soundbeam Project, 2018). It uses an ultrasonic distance sensor to translate the user's position, velocity, and acceleration into MIDI inputs, which are then converted into melodies and

played by an attached computer. However, a single sensor and touchscreen controller, without the ancillary equipment, costs £2500 (roughly US\$3200), putting it well outside the price range of most potential users.

A solution that is more commonly presented is a form of eye tracking, with camera systems that detect the focal point of the user's eye on a screen, in conjunction with some method of clicking. This allows individuals with no limb motion to control computers, and, theoretically, instruments. One such device, the Eyeharp, has one portion of its user interface, called the Step Sequencer (Figure 3) devoted to constructing chords and arpeggios, and the other portion, the Melody Layer (Figure 4) used to play melodies in real time (Ramirez & Vamvakousis, 2015). Notably, while the device can play complex songs, large portions of the performance must be prepared beforehand in the chord interface, as the eye-tracking system can only register one input at a time. This is a fundamental limitation of the eye-tracking system, which makes more complicated music difficult to achieve; the user can only focus on a single point on screen at any given time, so eye-tracking systems can only register one input at a time.

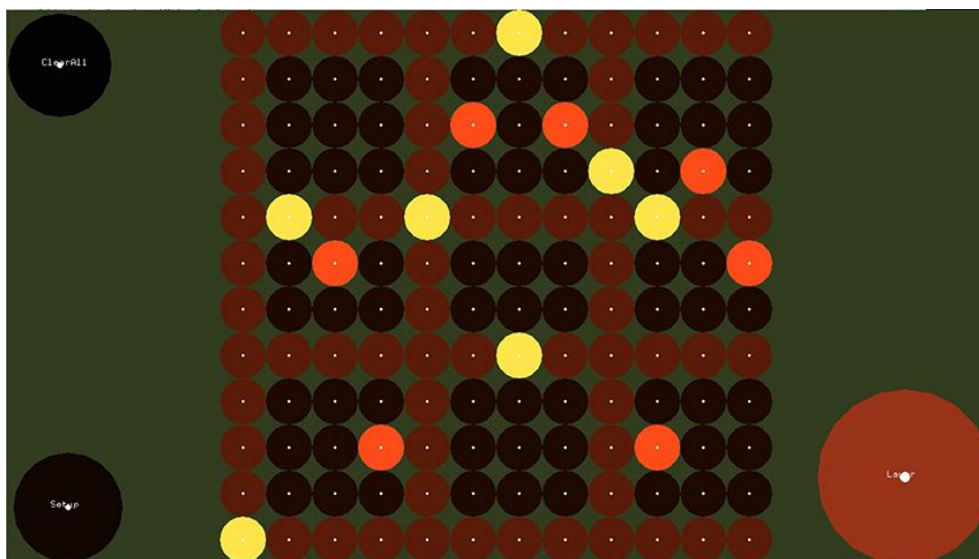


Figure 3: Eyeharp Step Sequencer Layer (Ramirez & Vamvakousis, 2015)

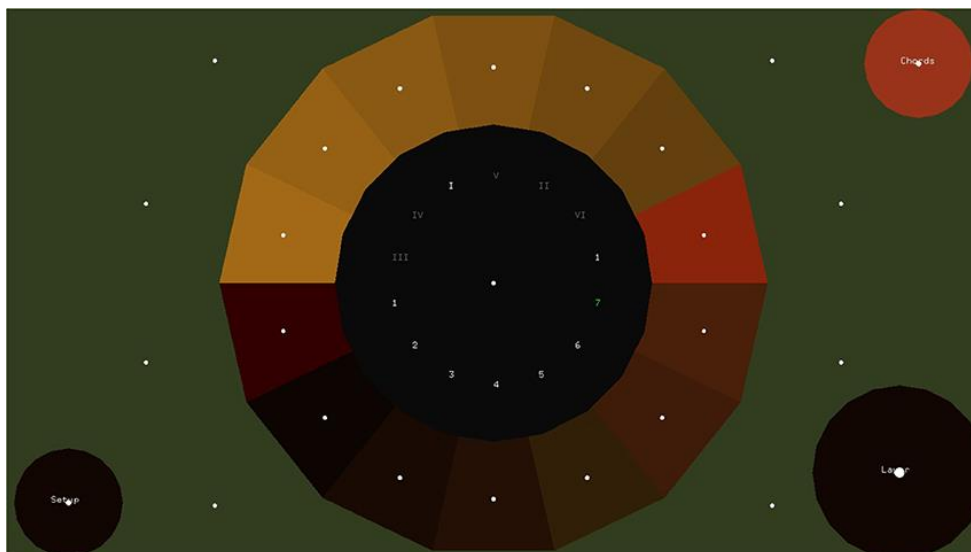


Figure 4: Eyeharp Melody Layer (Ramirez & Vamvakousis, 2015)

Strumming Devices

In order to play a guitar, a strumming motion is often required; strumming involves moving a plectrum relatively rapidly across multiple strings. One possible mechanism to achieve this effect was developed by Michael Cooper (1991), Figure 5. The design shown uses two foot pedals (28, 30) as controls, with cables (32, 34) used to move the plectrum horizontally and vertically, respectively. The strumming device consists of a small frame mounted above the strings of the guitar (20, 22, 24). The frame supports a rod housing (36) which is suspended on tension springs (54, 56). The cable (34) is attached to the rod housing (36) as well as the lid (26) such that tension in the cable raises the rod housing (36), and with it the rod (42) and the plectrum (48), disengaging the plectrum from the guitar strings (12). Therefore, the pedal (28) can be depressed to apply tension to the cable (34) and prevent the plectrum (48) from strumming. The second cable (32) is connected to the plectrum rod (42), moving the plectrum (48) across the strings (12) horizontally. A compression spring (44) returns the rod and plectrum to their original positions when the pedal (30) is released, releasing the tension in the cable (32).

If the rod housing (36) is in its lower position, this horizontal motion strums across the strings; by modifying the speed the pedal is pressed with, the speed of the strum can be controlled, while adjusting the distance the pedal is pushed allows strumming a subset of the strings. Disengaging the plectrum from the strings by engaging the other pedal (28) allows the user to repeatedly strum in the same direction without a reverse motion. To modify the device to operate on motor control, the cables could be replaced by linear motors; in theory, the springs used in the patented design could be used to reset the strummer when the motors were not active, so one-directional solenoids could be used rather than linear servos, potentially reducing costs. Alternatively, the cable system could be retained, with rotary motors to pull or release spools holding the cables. This system has the benefit of simplicity, and with sufficient precision, could be used to pluck single strings. The disadvantage of such a system is the complexity and precision needed; the motor would need to move very specific distances and with very specific timing so as not to strum unwanted strings.

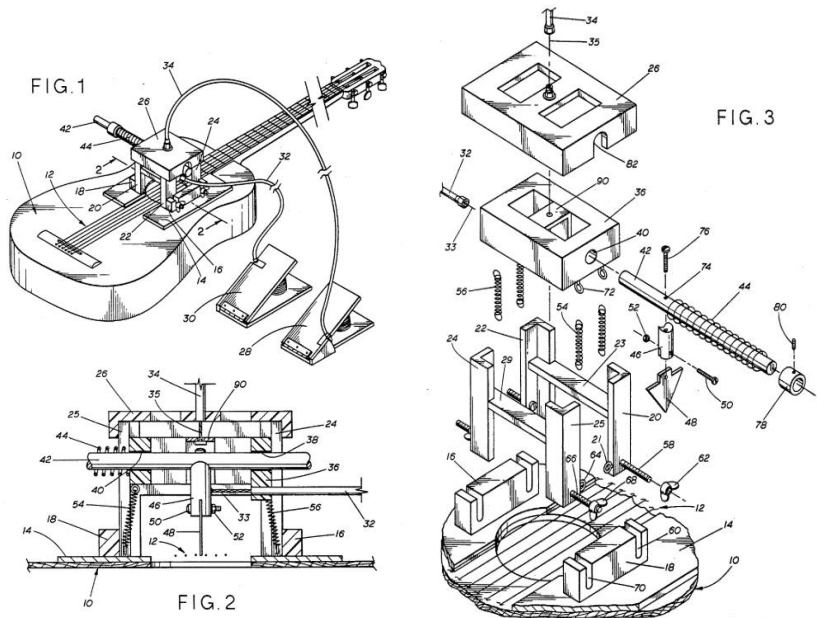


Figure 5: Mechanical Guitar strummer (Cooper, 1991)

A similar concept was demonstrated by a team from Duke University (Lee, Leung, & Topel, 2008), using a pair of linear solenoids to drive a plectrum across the strings of a guitar; when the solenoid was activated, it drove the plectrum perpendicular to the strings, strumming the guitar, while the second solenoid reversed the motion and reset the strummer, Figure 6. The key innovation of this design was in the design of the strummer bar; rather than use a single plectrum, the strummer had six, as shown in Figure 7. This allowed the device to effect a strum with significantly less motion of the solenoid, allowing faster strumming with a slower driving motion than other designs.

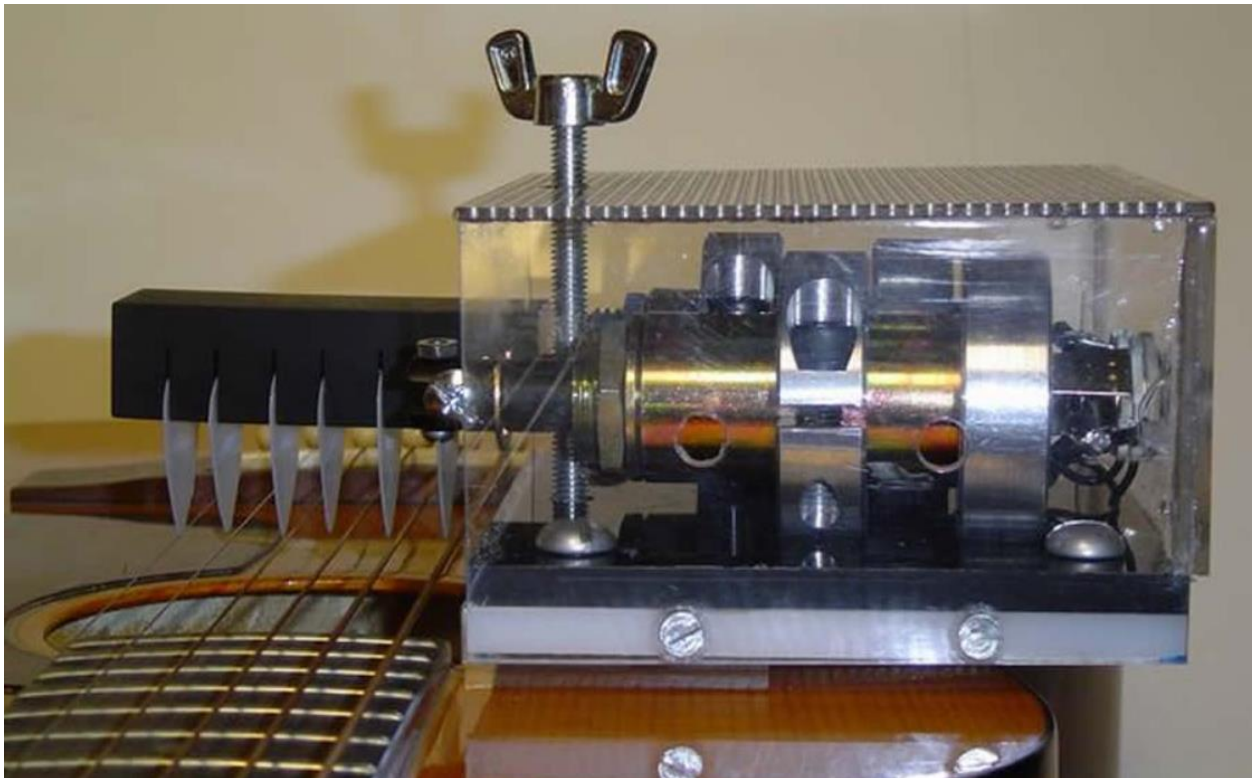


Figure 6: Strumming Device (Lee, Leung, & Topel, 2008)

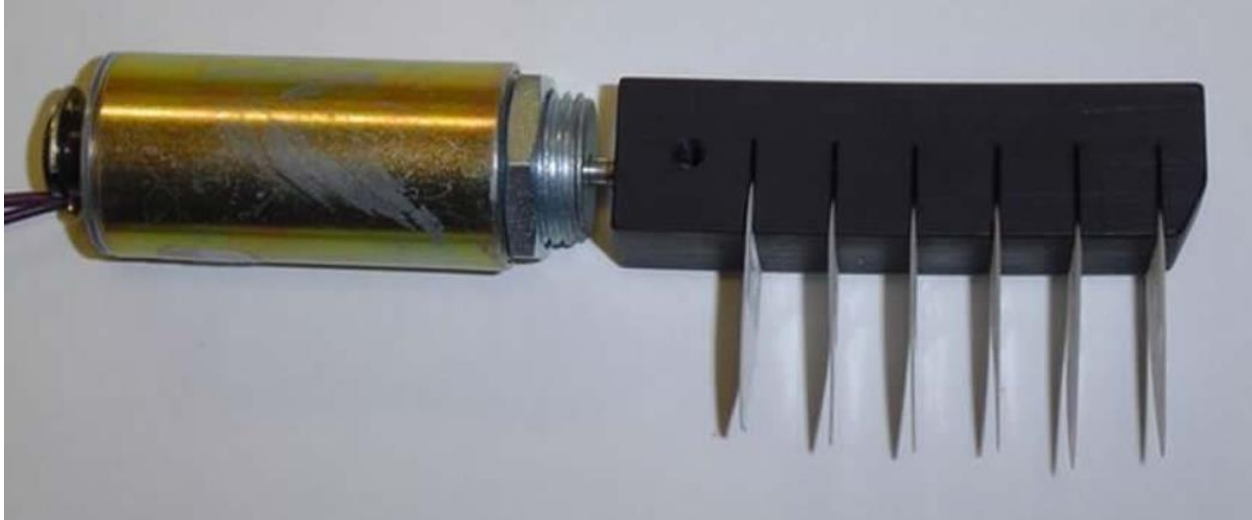


Figure 7: Six-plectrum Strummer Bar (Lee, Leung, & Topel, 2008)

An alternate strumming method is used in the assistive guitar designed by Christina White and her team (2005), shown in Figure 8. The design has a strumming device (10) mounted over the soundhole of a guitar (11), which rests in a frame (14) that raises the guitar off of the tabletop.

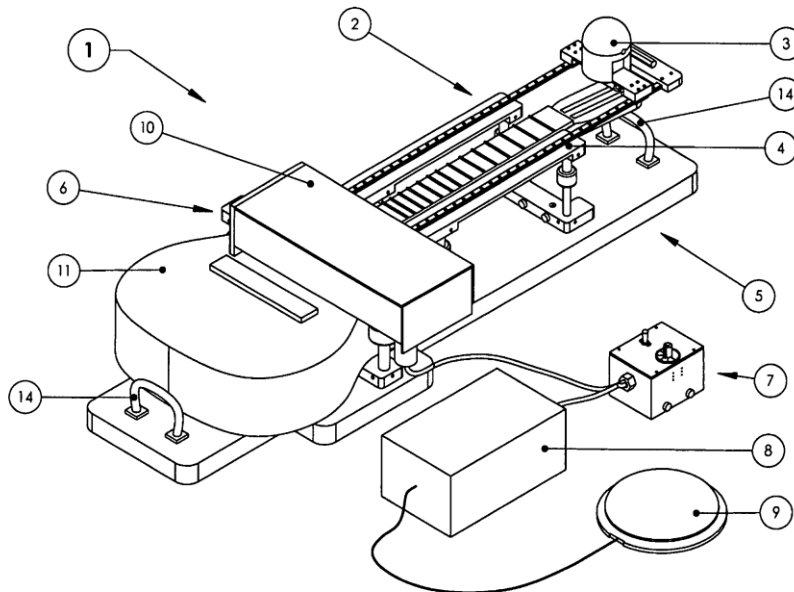


Figure 8: Modular Automated Assistive Guitar (White et. al, 2005).

A slider-crank linkage (Figure 9) is the basis of the strumming device, and is generally covered by a protective lid (10 in Figure 9). A rotary crank (29) is driven by a motor (13), and in turn drives a coupler (26) which drives a slider (24) along linear rails (25) perpendicular to the strings of the guitar. A plectrum (12) is attached to the slider block (24), such that when the slider is driven back and forth along its rails, the plectrum strums the strings of the guitar. The control box (35) can be used to start and stop the strum, as well as adjusting the speed at which the strummer moves by controlling the motor speed. The device is relatively simple, and only requires a single motor. However, the fixed linkage means that the device will strum all six strings in alternating directions, with no option to repeatedly strum in the same direction or strum a subset of the strings.

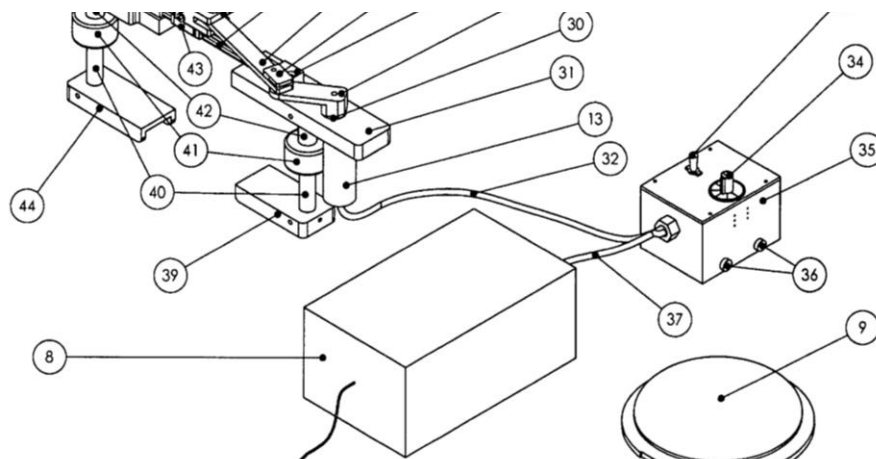


Figure 9: Slider-Crank for Guitar Strumming (White et al., 2005)

Plucking Devices

Another component of guitar playing is plucking individual strings, for which a number of devices have been invented. One such device was created by Raymond Kidwell (1966), shown in Figure 10. It plucks strings through the use of a set of ratchet wheels (124) with several

plectrums mounted to it, one wheel for each string to be played. Rotation of the wheel plucks the string each time the plectrum engages with the strings. The ratchet pins (130) are engaged by a pawl (206) attached to a sliding link (198), Figure 11. When the link (198) is driven to the left, ratchet 206 engages with the pins (130) on wheel 126, plucking string E. When the link (198) returns to the right, the pawl (206) slides underneath the pins, while pawl 208 presses the pins on wheel 128 to pluck string G. The link (198) is driven by a series of intermediate links (184, 176) that are ultimately driven by a foot pedal (166), such that the user can pluck the strings by rocking his or her foot back and forth. Additionally, the individual plectrum wheels (126, 128), are mounted on long shafts (146) which can be raised or lowered by a lever (114) which runs beneath the body of the device and can be toggled by a foot pedal (108). By this method, individual plectrums can be lowered to engage with the driving link, or raised to disengage them, allowing the user to control which notes are played at any time. In a motorized version of the mechanism, the driving link could be moving continuously, with a speed control to set tempo, while the user chooses which plectrums to engage. However, this could result in notes being delayed, if the plectrum wheel was engaged at the wrong time during the cycle, and causing variable delays in response times that could reduce the user's engagement with the music.

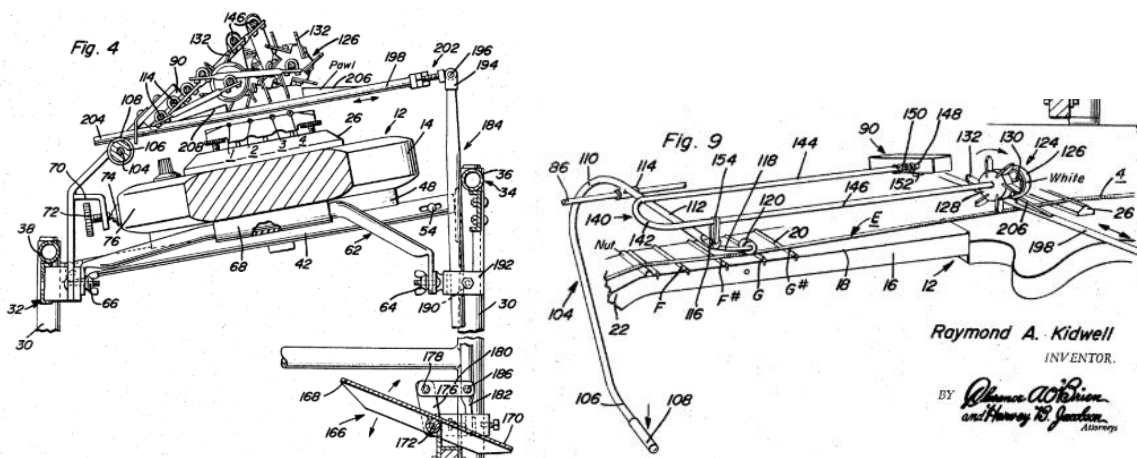


Figure 10: Mechanical Device for String Plucking (Kidwell, 1966)

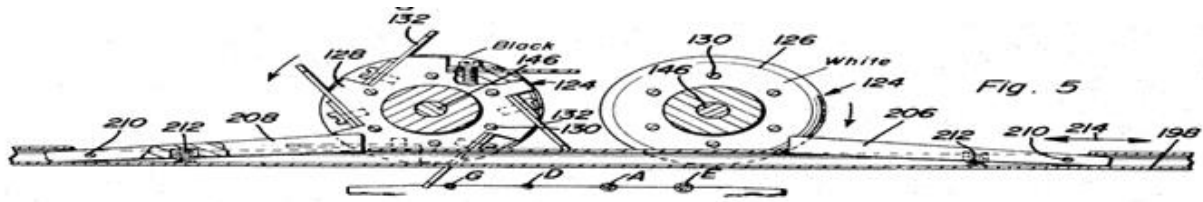


Figure 11: Ratchet System for actuation of wheel-based plectrums (Kidwell, 1966)

Another ratchet-pawl plucker wheel system was designed by Andre DuPra (2013) and is shown in Figure 12, using a simple linear solenoid to advance a ratchet wheel once for each pulse of the solenoid. The striker (25), is brought into contact with the wheel (15) when the solenoid extends, driving the wheel to rotate counterclockwise and pluck the string (10). The spring on the striker (102) returns the striker to a downward position as the solenoid retracts, allowing the wheel to rotate freely; however, the detent mechanism (30) prevents the wheel from rotating past a single index, ensuring that each activation of the solenoid plucks exactly once. This system allows for quick plucking. However, it is a highly complex system, with many complex parts needed for each individual plucker, so implementation of the design could be relatively expensive and difficult to repair.

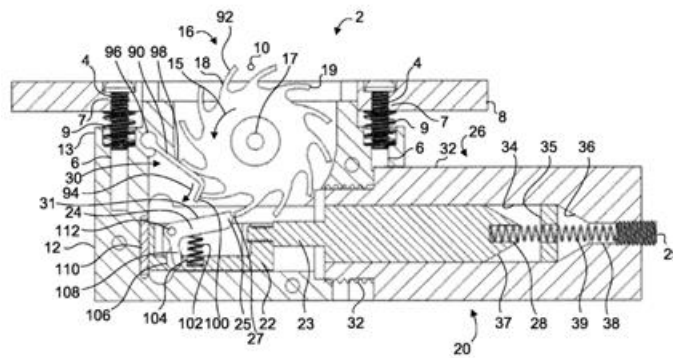


Figure 12: Ratchet system driven by linear solenoid (DuPra, 2013)

A similar plucking system was designed by Kenneth and Jeffrey Caulkins (1998), using wheels with plectrums attached; this system is shown in Figure 13. These wheels are driven by a reversed crank-slider mechanism, with a linear motor driving a piston (124), which is pin-

connected to a coupler (128), which then causes the wheel (140) to rotate about a fixed shaft. In order to ensure the wheel turns in the appropriate direction and stops after each pluck, a pair of flat magnets (149) are located on opposite sides of an octagonal plate (130) attached to the wheel; the magnets force the plate into positions where the magnets are closest together, stopping the wheel in fixed positions when the mechanism is not being driven by the motor. The primary disadvantage of this system is that the action of the motor is different for each pluck in a single rotation of the wheel; at a certain point, slow forward motion will drive the wheel forward, while in a different position, the same rotary speed will require a faster reverse motion, so precise control of a bi-directional actuator is needed to control single plucks.

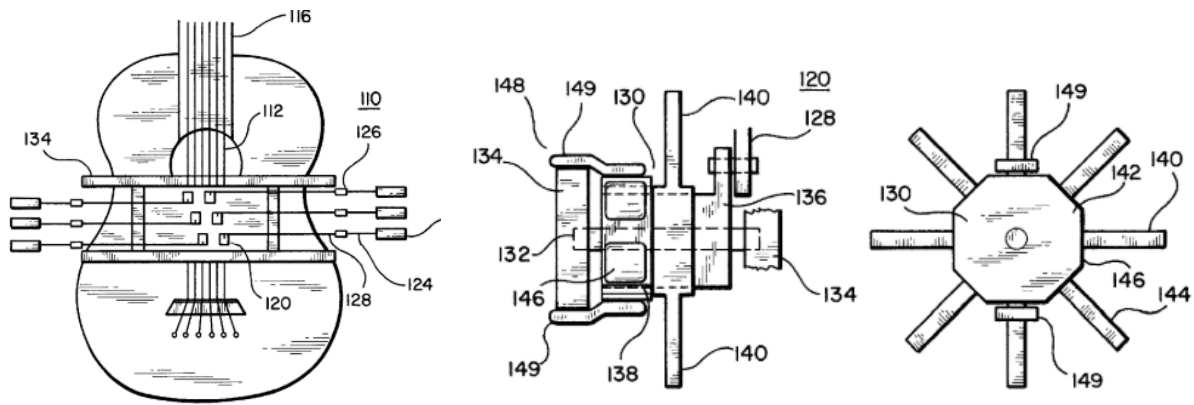


Figure 13: Apparatus for Strumming a Stringed Instrument (Caulkins & Caulkins, 1998)

Another possible design was developed by Ben Reardon (Hobson, 2015), and uses a rotary motor to actuate a plectrum for each string. The device can be seen in Figure 14. As the motors are reversible, a small motion is all that is needed to pluck each string, and a second pluck can be performed with an identical, reversed motion. This allows for fast, repeated plucking. However, it does still require precise motor control, and the motors are mounted over the soundhole of the guitar, which can muffle the sound.

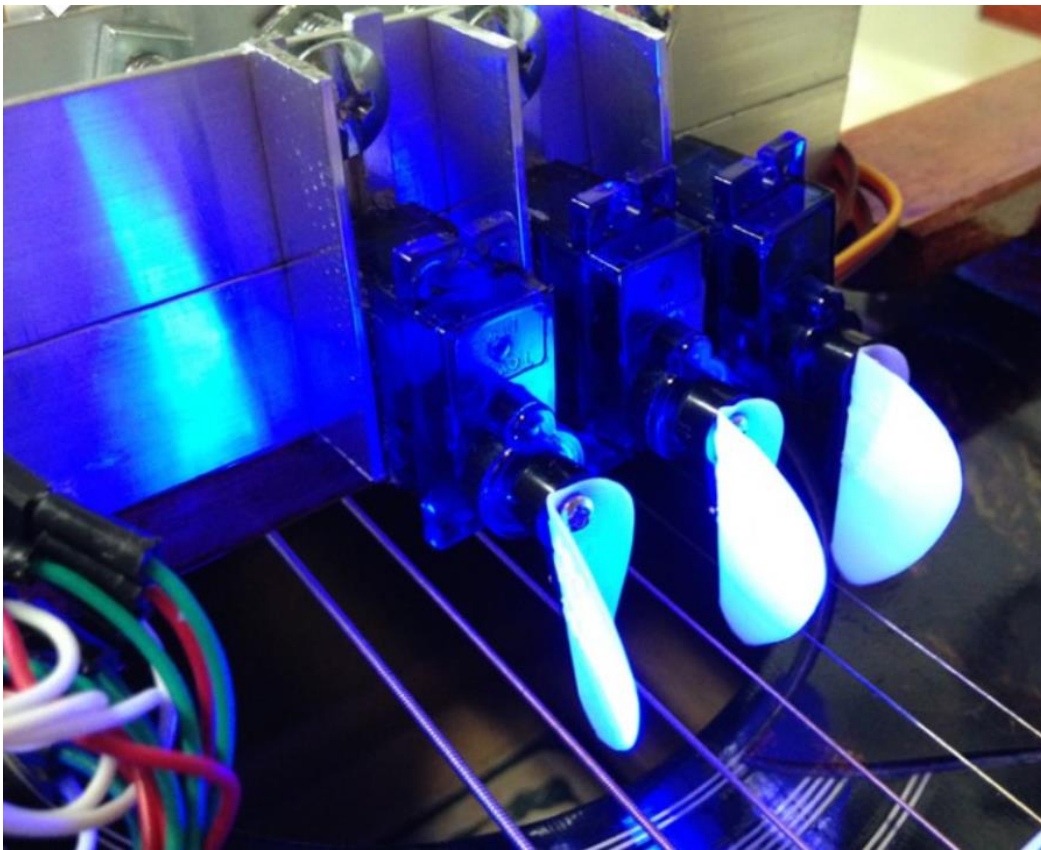
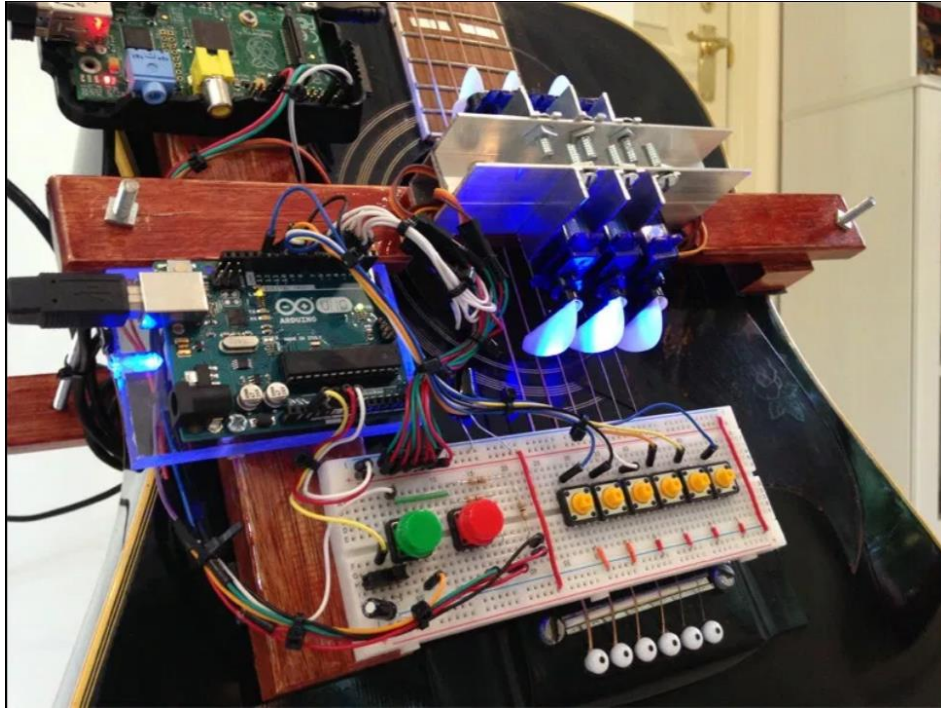


Figure 14: Robotic Guitar (Reardon, n.d.)

As an alternative to machines designed to strum and pluck, several groups have developed adaptive guitar picks. These picks are mounted on large, comfortable handles, or on a glove or wrist brace, allowing a user with little control of their fingers to comfortably hold a guitar pick (Day, 2018). The use of such a device would not help individuals with significant spasticity in their arms, but for users who primarily have difficulty gripping the pick, such a device could make playing the guitar significantly easier, especially when combined with a device to assist the fretting.

Project Approach

Goal Statement

We will make an assistive playing device that helps people without the physical ability to play a guitar. This will include both strumming and plucking so that the user would be able to play a variety of songs that range in structure and notes. This device has the potential to enable users who have never played music before to do so. As previously discussed, engagement with music changes when people make music rather than listen to it. This deeper engagement with music stimulates more of the brain and may lead to increased memory function.

User Requirements

Our designated user for this project is any person who does not have the physical capabilities to play the guitar, specifically one who has limited manual dexterity and fine motor skills. There are several assumptions made about potential users for this device. The first assumption is that the user will have two control points on their body and will have the ability to simultaneously move those points. Based on the needs of the user, the control sites will need a range of motion between 12 cm along any axis, with precision of 2 cm in motion, or 240 cm along any axis with precision of 40 cm. The second assumption is that the user will have the ability to make repeatable gestures that will serve as the activation gestures for the sensor inputs.

Needs Assessment and Functional Specifications

Needs Assessment

For this assistive device to be an effective solution, there are many elements of the problem that must be understood.

There are several requirements for the end device for it to be a successful solution: (1) it must be affordable and repairable, (2) it must have a modular user interface, (3) the user must feel like they are actively playing music, not watching a machine do so.

Affordability and minimal maintenance are essential to the continued use of assistive devices. The sponsor of this project has a limited budget for the device, and should other organizations reproduce the device for their clients, it must be made from commercially available, inexpensive parts. Assistive technology users and their caretakers often do not have deep technical backgrounds, so it is common that when an assistive device breaks, it is abandoned (Hoffman & Ault, 1996). To reduce the likelihood of abandonment, the device must be easy to fix and reassemble.

The modular user interface is a must for the device so that a variety of users can use the device. Disabilities are highly specific to the individual, and therefore, some user interfaces may work for certain individuals but not others. To give the device the widest possible user base, a variety of user interfaces with different kinds of sensors must be interchangeable and still work with the device. Inputs for control of fretting, note to pluck, and speed of plucking will be required to play the guitar. A user would need to simultaneously trigger inputs when plucking multiple strings at a time or changing the fretting while plucking. The team assumes that the user will be able to have the ability to control at least two inputs at a time.

Finally, for the device to be truly successful, the user must have the feeling that they are playing the music. The device loses its purpose of helping individuals play the guitar if it is overly automated, sounds artificial, or visually hides the plucking and fretting of the strings. When the user feels as if they are watching a machine instead of playing the guitar, they lose the benefits that come with the deeper engagement with music.

Functional Specifications

Device

Operation

The device must be able to pluck two guitar strings simultaneously, so that a wide variety of songs can be played. The device must also be able to pluck a new combination of notes every eighth of a second, so that it can play 32nd notes at 60 beats per minute; this allows the user to play at a relatively high tempo without the device falling behind. The device should be able to produce a strum effect across the full set of six strings, as well as across a subset of the strings, such as the lower three strings. This effect should be able to strum in either direction, so that strums both up and down a scale can be played.

When plucking a string, the device should not displace a string more than 3.175 mm parallel to the guitar body, and no more than 2 mm perpendicular to the guitar body, so that strings do not interfere with each other or the body of the guitar during operation. Notes played by the device should have at least 80% of the volume of notes played without the device present, assuming otherwise identical actions.

Frame

The frame of this device must not prevent resonance in the body of the guitar. This would dampen the sound produced. Aspects of maintaining resonance include not covering the soundhole of the guitar, not altering the actual structure of the guitar, and not interfering with the vibration of the guitar's soundboard. Additionally, the frame of the guitar should be able to stand upright without assistance while the guitar is being used. This allows the guitar to be stored vertically with the device attached and allows the user to choose whether to have the guitar laid horizontally or standing vertically while playing. The frame and device should have a mass of less than 2 kilograms so that the guitar remains easily transportable. The device should make no permanent alterations to the guitar, so that the guitar can be played manually with the device removed. Attaching or removing the device from a guitar should require less than 10 minutes and be achievable by hand, to allow easy setup on a new guitar. Additionally, the frame should be able to fit on guitars ranging in width from 12 inches to 17 inches, with box heights ranging from 17 inches to 21 inches, and depths between 3.5 and 5 inches. This ensures the device can be fitted to a wide range of guitars, allowing users to adapt the device to existing instruments.

Forces on Guitar String

In previous iterations of this project the maximum distance the strings could be plucked without creating interference was measured. This project team also measured the force necessary to displace the low-E string, 3.383 N, and the high-E string, 2.396 N, to this distance (Dube et al., 2018).

User Interface

Control Requirements

The user interface should never require using more than two control sites simultaneously, meaning the device can be operated using only two limbs or other suitable control sites. The control sites used should be analog, based on the user's movements. These specifications allow individuals without precise control of their fingers to use the device, allowing users with a wide variety of impairments to use the device.

Response Time

There is a slight delay after a signal is input and when the corresponding response is produced. This time between input and output is known as latency and should be no longer than 10ms. Having a short latency is important to give a feeling of full control. The time limit of 10ms is based on research that shows the latency is noticeable at different speeds for different sounds, with the maximum to be normally noticeable for a guitar being 12ms. Walker (2005) explains, "the speed of sound in air is roughly a thousand feet per second, each millisecond of delay is equivalent to listening to the sound from a point one foot further away," meaning that a 10ms latency is roughly equivalent to listening to a guitar from 10 feet away.

Setup and Calibration

The user interface should not require a technical background to be set up and prepared for use. Setup should not take someone longer than 10 minutes, and the sensors must be in an operable state no longer than 2 minutes after being turned on.

Manufacturing of Devices

The plucking device should use at least 90% commercially available parts, by count; this makes it easier to replace damaged parts and reduces overall costs, as well as allowing faster delivery of replacement parts. Custom components should be manufactured using methods and materials that are available to the general public at low cost, such as 3-D printed plastic or laser-cut acrylic.

The user interface should implement easily obtainable and affordable sensors that can be easily replaced should they be damaged or broken. Additional parts, such as baseplates, stands, frames, housing, etc., should come from readily available materials that can also be easily replaced.

Both the plucking device and user interface should be easily assembled and repaired by a user with basic tools, specifically basic screwdrivers, hammers, and wrenches. Documentation should be provided in plain English so that users understand how the device works to aid assembly, troubleshooting, and repair. These requirements ensure that the users of the device can build and repair the device affordably, allowing wider use over longer periods of time.

Electronics

The device should be powered by batteries that can either be easily obtained by the user for replacement or are rechargeable. To not cause damage on the microcontroller, the current drawn at any time should not exceed the maximum of the board's pins. Components should be easily traceable throughout the circuitry so that they may be replaced without an in-depth understanding of the whole circuit. The circuit should be packaged such that there is no risk of accidental unplugging.

Cost

The final cost of the plucking device and user interface should not exceed \$250. The parts should be easy to replace if broken; however, the devices should not require consumable components that would produce a continuing cost.

Plucker Designs

Preliminary Designs

Eight preliminary plucking mechanisms were considered for the device: a revolving platform with guitar picks on levers, rotating plectrum wheels, four-bar crank-rocker linkages, four-bar double-rocker linkages, four-bar crank-slider linkages, linearly actuated plectrums, robotic arms, and a harpsichord plectrum assembly. Each of these designs are discussed further in Appendix B.

Initial Decision Matrix

Each design was rated on each of the criteria, which were weighted from 1 to 5; the scores were totaled for comparison and are shown in Table 1. The rating scales and full descriptions of each criteria can be found in Appendix C.

Table 1: Decision Matrix for Plucking Devices

Device/Criteria	1	2	3	4	5	6	7	8	9	10	11	Total
Four-bar run both directions	3	5	5	3	5	1	2	3	5	4	4	121
Four-bar one direction	3	5	3	3	5	1	2	3	5	4	4	113
Crank-Slider	3	5	4	3	5	2	2	5	1	5	4	119
Lego-Inspired	2	3	5	4	5	4	3	3	4	4	5	121
Plectrum Wheels	3	5	4	4	5	4	2	5	4	5	4	134
Two Robotic Arms	3	1	4	3	5	3	2	1	4	1	4	78
Devices on Tracks	5	1	3	4	5	5	3	3	5	3	4	109
Linear Harpsichord Plucker	3	4	5	4	5	3	3	3	5	4	4	128
Criteria	Criteria weighting (0-5)											
DOF	1	2										
Response Time	2	5										
Plucking Speed	3	4										
Complexity (Part Acquisition)	4	2										
Complexity (Assembling of device)	5	3										
Complexity (Number of Parts)	6	2										
Complexity (Precision Needed)	7	1										
Voltage Required	8	2										
Estimated Cost	9	3										
Motor Force/Torque	10	4										
Device Mass	11	1										

The two highest-scoring designs were the plectrum wheel design and the harpsichord design; each of these designs was refined for a more detailed final comparison, focused on the practical considerations of assembling the device.

Refined Designs

Plectrum Wheels

In this design concept, a rotating wheel, with a set of plectrums arranged around it radially, is placed above the guitar string. As the wheel rotates, the plectrums are brought into

contact with the string, displacing it and performing a pluck. The rotation angle is controlled to ensure the string is plucked exactly once each time a particular plucker is activated; one plucker is located above each string of the guitar, for a total of six pluckers. The most critical constraint on the design of the plucking device is the space between the strings; the strings are approximately 10 mm apart, so by staggering the plucking devices in two rows, each plucker can have a maximum width of 20 mm. This limits the size of the plectrum wheel, as well as the size of motor available. The other constraint on the motor selection is the vertical distance above the string, to ensure the motor does not collide with the string at any point during the motion of the plectrum. To ensure adequate space between the motor and the guitar strings, a 2:1 gear ratio was used, increasing the speed of the wheel and offsetting the motor from the strings. This increases the effective speed of the pluck, allowing a faster response to the trigger. However, it also reduces the torque available at the wheel. The wheel has three plectrums arranged radially. Based on the maximum required plucking force of 3.4 N (Dube, et. al., 2018), and the available torque from the motor, the greatest wheel radius allowable is 22 mm. However, due to the space requirement, the radius is limited to 10 mm; this allows the plucking devices to be placed in two staggered rows, minimizing the distance between plectrums in the direction of the strings. Minimizing this spacing produces a more consistent sound, replicating the plucking pattern of a typical player. A 3D model of the plectrum assembly is shown as Figure 15. The motor (1) drives a 12 mm gear (2); this gear meshes with a 6 mm gear (3), which drives the plectrum (5). A small frame (4) holds the shafts in place, and rests on a horizontal surface along with the motor.

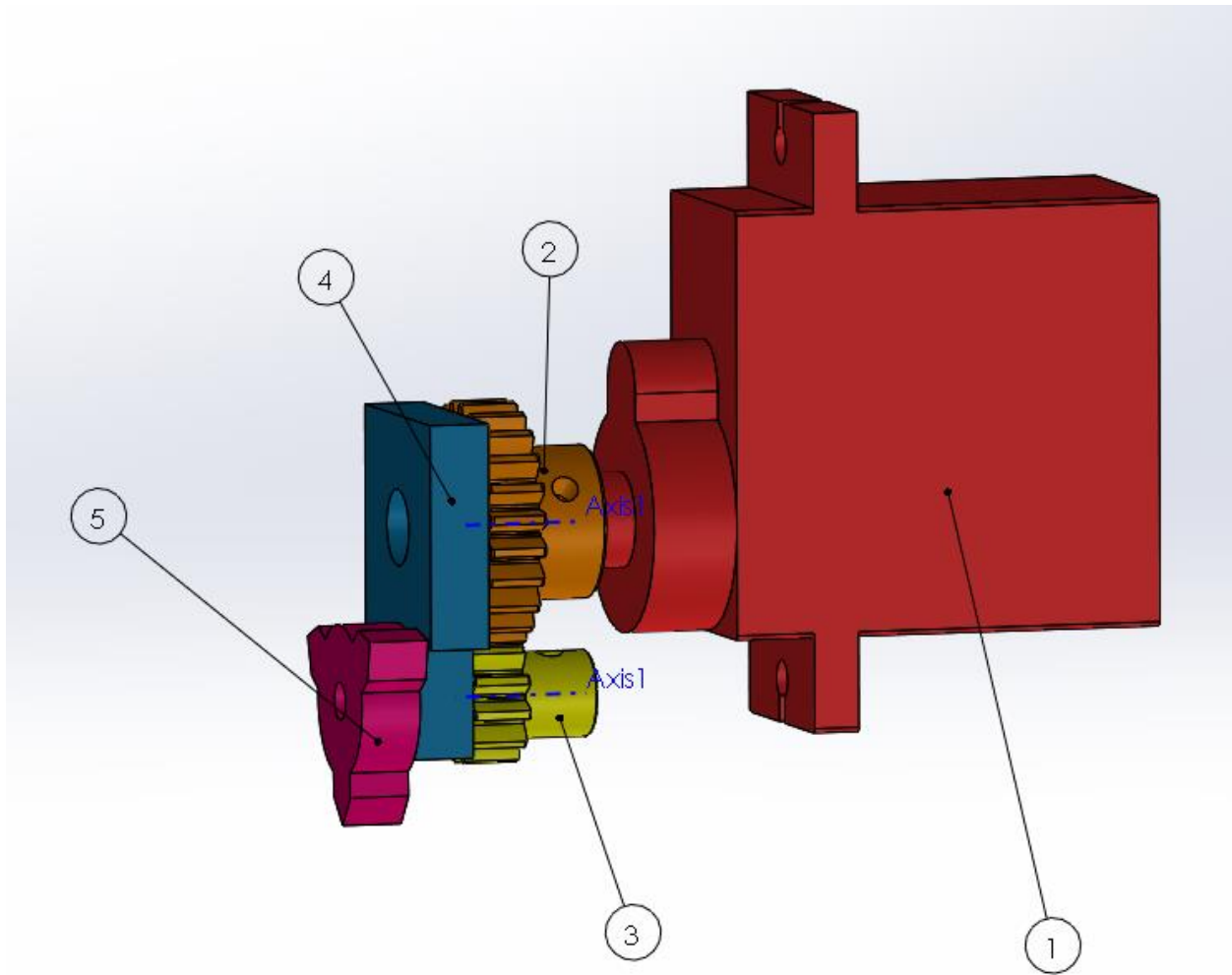


Figure 15: Wheel Plectrum Design, Plucking Assembly

This model was used primarily to analyze the feasibility and motion of the design; it lacks fasteners and other means of connecting parts, problems which were addressed in later versions of the design.

Harpichord Plectrum

In this design, six plectrum devices from harpichords are used; when triggered, a solenoid pushes a plectrum across the string. After the pluck is complete, a spring returns the plectrum to its initial position. The plectrum is mounted on a low-friction lever, or ‘tongue,’

which allows the plectrum to slip around the string on the return stroke, rather than plucking a second time. Additionally, a damping pad is brought into contact with the string at the end of the stroke to quiet the vibrations still introduced by the plectrum. In this design, the plectrum jacks would be perpendicular to the strings, and parallel to the body of the guitar.

Based on the distance between strings and the force requirements a Small Push-Pull Solenoid (Adafruit, n.d.) was chosen for actuation. This solenoid has a width of 22 mm allowing a single row to actuate all the harpsichord jacks. It also provides a throw distance of 5.5 mm and a 5 N starting force, which is enough force and distance to pluck a single string without over traveling and hitting the next string. As the solenoid is spring-loaded, a single activation plucks the string once and returns the plectrum to its starting position.

In this design the face of the harpsichord jacks needed to be lying parallel to the face of the guitar, no more than $\frac{1}{8}$ " away from the strings. The jack must also be able to travel smoothly in a linear direction. This smooth linear travel was achieved by designing slots in the supporting frame that would have two square posts through them, attached to the ends of the jack. These posts each have two sets of ball bearing rollers, one on each side of the frame, which keep the jack from moving up and down but allow for horizontal motion across the strings as shown in Figures 16 and 17.

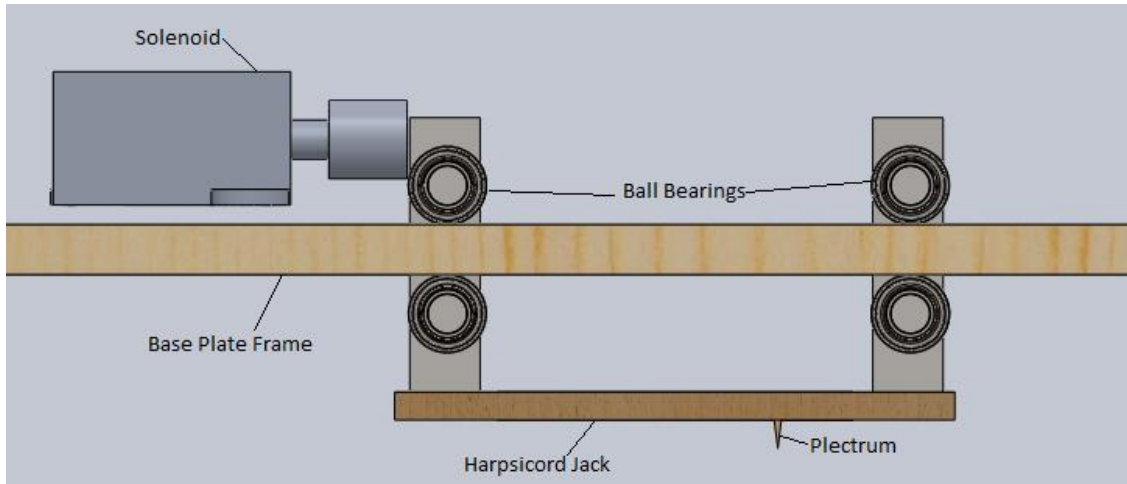


Figure 16: Harpsichord jack attached to the frame with its solenoid actuator

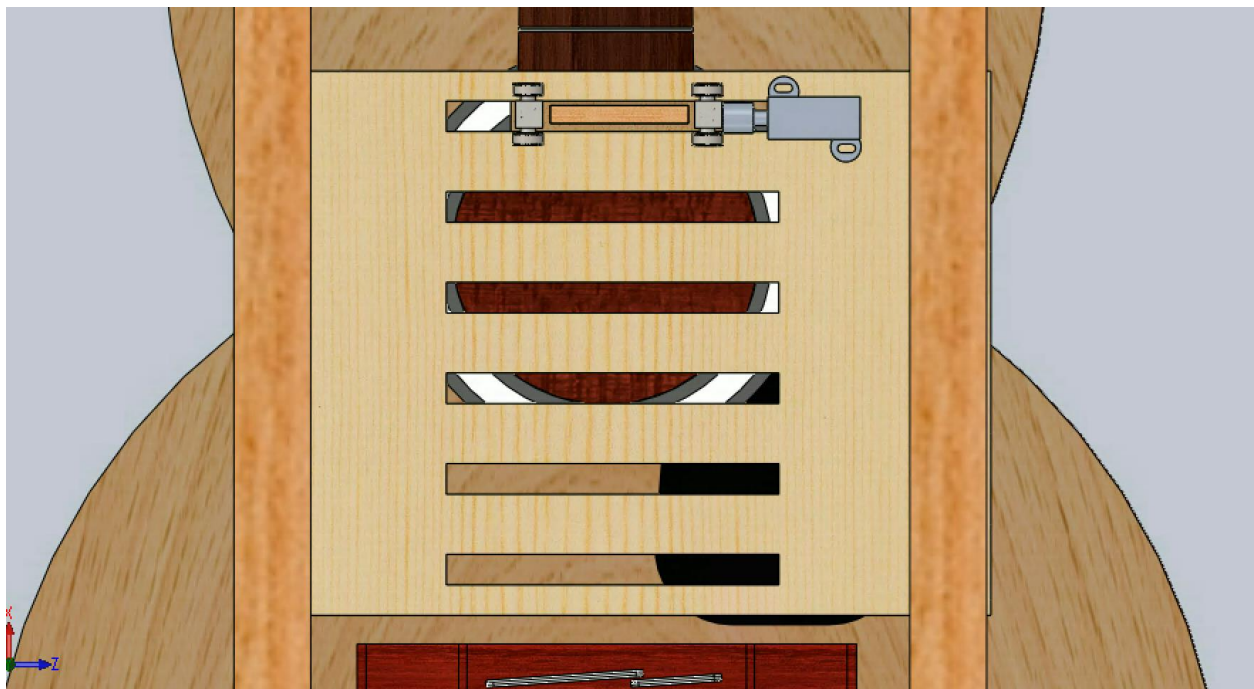


Figure 17: Top view of the pluck over the guitar

One part not designed at this stage is a piece to connect the end effector of the solenoid to its corresponding post. The piece would likely be 3D printed so it could be custom made to fit over the top of the post and encapsulate the end of the solenoid. The baseplate faces the same material selection challenges as the previous design. The goal would be to choose a material and

design which would hold up against user induced forces and still allow enough sound to pass through to minimize the effect on the sound quality of the guitar.

Final Decision Matrix

After considering both designs in depth a second decision matrix was created with new criteria. The updated criteria are shown in bold below and are fully described in Appendix D. The results are summarized below in Table 2; as shown, the plectrum wheel design scores significantly higher than the harpsichord design.

Table 2: Final Decision Matrix (bolded criteria have been re-evaluated)

Device/Criteria	1	2	3	4	5	6	7	8	9	10	11	Weighted Totals
Plectrum Wheels	3	5	4	3	4	5	2	5	2	5	3	121
Linear Harpsichord Plucker	3	4	5	1	4	1	3	3	3	4	1	98
Criteria	Criteria number	weighting (0-5)										
DOF	1	2										
Response Time	2	5										
Plucking Speed	3	4										
Complexity (Part Acquisition)	4	2										
Complexity (Assembling of device)	5	3										
Complexity (Number of Parts)	6	3										
Complexity (Precision Needed)	7	1										
Voltage Required	8	2										
Estimated Cost	9	3										
Motor Force/Torque	10	4										
Device Mass	11	1										

Based on the updated decision matrix and the further evaluation of the two final designs the plectrum wheel design was chosen for this project. This design scored very highly on response time, number of parts, required voltage and the motor torque. It also performed much better in the categories in which the harpsichord plucker was weak, such as the difficulty of part acquisition, the number of parts and the mass of the device. With the plucker design chosen the

next steps required were completing the design of the frame, finalizing the details of the plucker mechanism, and developing a working prototype.

Developed Design

Plucking Device

Further refinements of the rotating plectrum design were made to account for the limitations of the geometry, include necessary fasteners, and allow the user to adjust the device to fit multiple guitars with different dimensions. Rather than positioning the baseplate under the motor, the baseplate is above the plectrum device, and 3d-printed frames hold the motor and shafts in position, as shown in Figure 18.

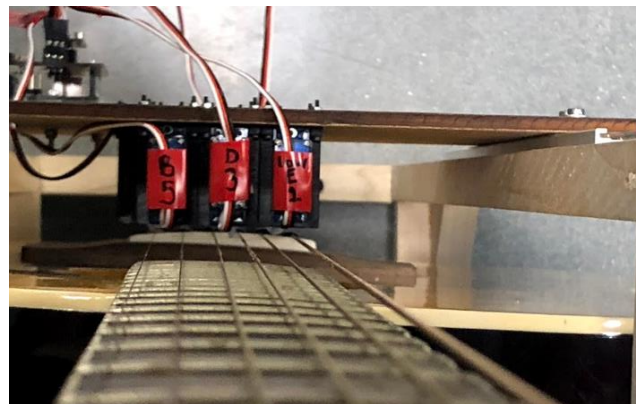


Figure 18: Baseplate Above the Plectra

M1.6 mm screws hold the motor to its frame as well as connecting the frame elements to the baseplate. The screws fit into slots on the baseplate rather than holes, allowing the plucking device to be moved horizontally by loosening the screws and sliding the device into position above the relevant string.

The plectrum itself was also redesigned; a larger angle at the tip was used, as well as a rounded blade to allow the plectrum to have a shorter period of contact with the string, allowing

a faster response time. Additionally, the plectrum was redesigned for unidirectional rotation, reducing the excess material and preventing the string from colliding with the plectrum after it releases. A dynamic model of the plectrum was designed to determine the optimal geometry using Creo Parametric software. Based on those tests, a tip angle of 30 degrees results in the string failing to release from the plectrum; overall, as plectrum angle increases, the plectrum strikes the string earlier in its rotation, but also releases it earlier; an angle that is too small prevents proper plucking, while an angle too large results in an oversized plectrum and a poor response time. An angle of 50 degrees was used for the prototype.

The lower shaft was incorporated into the plectrum part, which was 3D printed, reducing the need for fasteners. The upper shaft slides over the servo armature included with the motor and is glued in place; that armature is driven by a spline connection and secured to the motor shaft with a coaxial set screw. The gears are held to the shafts by radial set screws, and washers are used to provide spacing between the gears and the shaft housing. The full plucker assembly is shown in Figure 19.

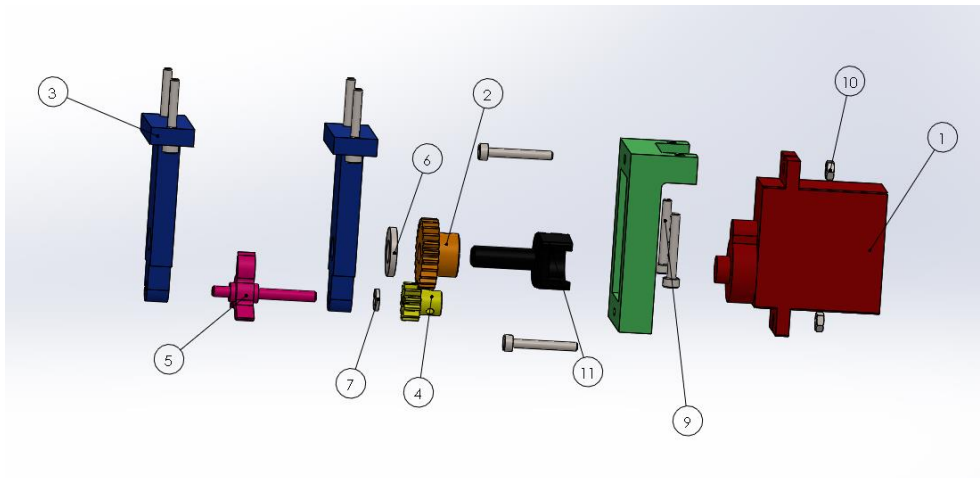
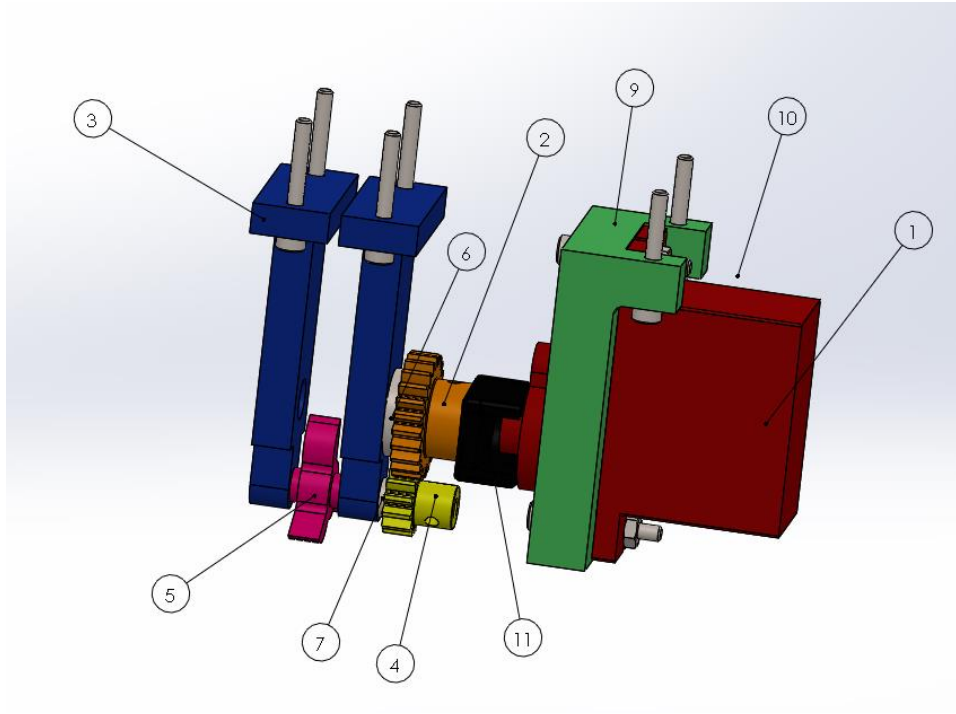


Figure 19: Prototype Design of Plucker Assembly

Table 3: Plucker Assembly Components

Component Number	Component Name
1	Servo Motor
2	12mm Gear
3	Gearshaft Mounting
4	6mm gear
5	Rotating Plectrum
6	M4 washer
7	M2 washer
8	Motor Frame
9	M1.6 socket head screw
10	M1.6 hex nut
11	Upper Gearshaft

Frame

In order to support the plucker on top of the guitar a frame was designed. This frame was a modified version of the frame used by a previous project team (Dube, et. al., 2018). It was designed to allow for a guitar to be held underneath the plucker without affecting the quality of the sound; to do this, the guitar is held in place without the frame contacting the front or back of the body. The completed frame is pictured in Figure 20.



Figure 20: Top View of Device Frame

The weight of the guitar was supported using wood supports under the neck and the strap button located on the bottom of the guitar. These two points are used to help locate the guitar at the correct distance from the plucker. The hole that the strap button sits in remains fixed, but as the guitar slides up and down the frame along the neck. The curvature of the neck allows for slight height adjustments to be made relative to the plucker. The closer to the top of the body the neck support is, the closer the strings will be to the plectrum. Once the correct distance is achieved, four padded posts can be tightened onto the top and bottom of the guitar body, two on each side. These four posts hold the guitar at the correct distance from the top of the frame and stop additional movement, such as a rotation around the neck and strap button.

This frame also contains two linear slides to align the baseplate. Once the guitar is in the frame, the baseplate can be slide onto the rails and adjusted over the soundhole. Once oriented the 8 screws in the corners of the baseplate can then be tightened, which will hold the slides in place on the rails and lock the plate in place. With the guitar and baseplate securely in the frame, the guitar can be played while standing vertically or lying flat on a table.

User Interface Designs

Preliminary Designs

Several preliminary designs were discussed, with sensors such as a camera, inertial measurement unit, IR range sensor, PIR motion detector, ZX gesture sensor, button, switch, and a spectral sensor. For the camera system, vision tracking would be used to see where the user moved within the frame. For the inertial measurement unit design, the sensor would be mounted to the user, and their position tracked. For the spectral sensor design, colored cards would be used to indicate which string to pluck. For the remaining sensors, six sensors, each representing a string, would be mounted such that the user could trigger the input either by motion or tactilely. All of these designs are discussed further in Appendix E.

Initial Decision Matrix

The aforementioned preliminary designs were compared using a decision matrix. In our decision matrix, Table 4 below, manufacturability and user accessibility were highly prioritized. Weights from 1 to 5 were given to each criterion, where 5 is the most important and 1 is the least important. Cost and estimated computational complexity were weighted 5. High costs deter anyone who is trying to replicate or repair the interface. Computational complexity influences how much delay between the interface triggering and the guitar plucking and gives insight to the complexity of the required code. Complex algorithms should be avoided if possible, such that anyone who is working with the interface is able to understand how it functions without extensive study. The criteria that were given weights of 4 were: control sites supported, viability for different ranges of motion, input detail, and user difficulty. Control sites, viability, and

difficulty all directly correlate to how many potential users would be able to interact with the interface. Input detail is important because higher resolution from the input signal can indicate more information about the triggering action and can be used to more precisely control the guitar. All criteria are further documented in Appendix F.

Table 4: Initial UI Decision Matrix

Device/Criteria	1	2	3	4	5	6	7	8	9	10	11	12	DECISION VALUE
Camera	3	5	5	5	5	1	1	3	2	4	5	5	154
IMU	5	5	5	5	5	4	5	5	5	4	5	5	192
IR Range	3	4	5	3	3	4	5	5	4	2	4	4	146
PIR Motion	3	4	5	3	3	4	5	5	4	3	1	4	139
ZX Gesture Sensor	3	4	5	3	3	5	5	5	4	1	4	4	144
Arcade Button	5	4	5	3	3	5	5	5	5	5	1	3	157
Spectral Sensor	5	3	5	1	3	5	5	5	5	4	5	2	153
Criteria	Crit weighting (1-5)												
Power Requirements	1	2											
Direction of Motion requirement	2	3											
Range of motion requirement	3	2											
Control sites supported	4	4											
Viable for different ranges of motion?	5	4											
Time for calibration	6	3											
Steps needed to calibrate	7	1											
Setup time	8	3											
Estimated Computational complexity	9	5											
Cost	10	5											
Input detail	11	4											
User Difficulty	12	4											

From this initial matrix, the team determined to move forward with the two top-scoring designs, IMU and arcade buttons.

Refined Designs

Buttons

For the button design, two button options were reviewed: the 60mm Buddy Button and 100mm arcade button. The Buddy Button is a commercial product sold by Ablenet. It is a low force push button that requires only 142 gf to activate. It is attached to a 5ft cord with a 3.5mm mono plug to interface to other electronics (Ablenet, n.d.). Shown in Figure 21, the Buddy Buttons are wired to an Arduino and can arranged in any shape for the user's ease.

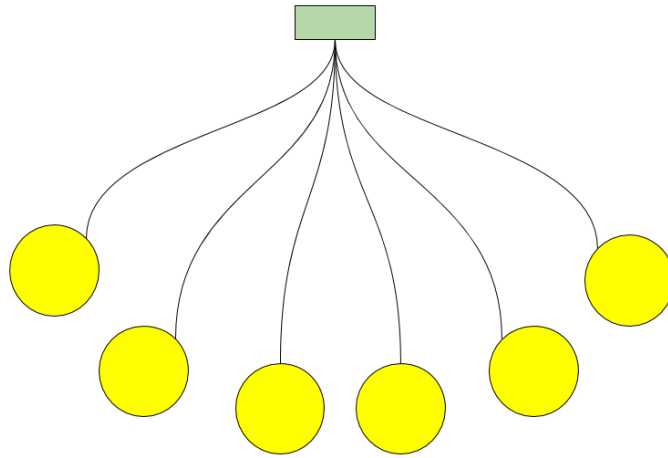


Figure 21: Buddy Button Arrangement (Higham, 2018)

The one limitation the Buddy Button presents is the cost. Six buttons are needed, and at a cost of \$65 each, the total cost of the interface would be around \$400. The benefit of the Buddy Button's low force does not outweigh the high cost because the focus of the project is on users who would be able to exert a typical amount of force to push a button.

One hundred mm arcade buttons are sold from various vendors at much lower cost. The arcade button is composed of two parts, a 100 mm dome, and underneath a microswitch. The microswitch protrudes 50 mm below the base of the button, due to this construction, the buttons

must be placed in frame or box such that it is elevated from the surface. An initial option for this is presented in Figure 22.

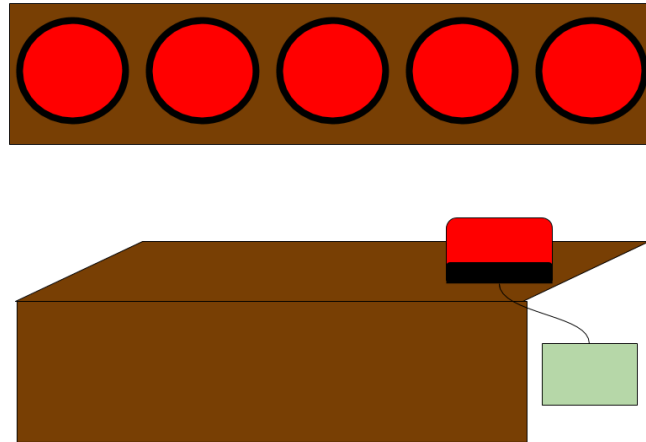


Figure 22: Arcade Button Arrangement

Upon further review, having all six buttons spaced linearly apart would separate the furthest buttons by almost 1m. An updated design that houses each button separately is presented in Figure 23. Six boxes would be laser cut out of 0.25” material. The boxes then could be arranged in whatever shape benefits the user’s range of motion.

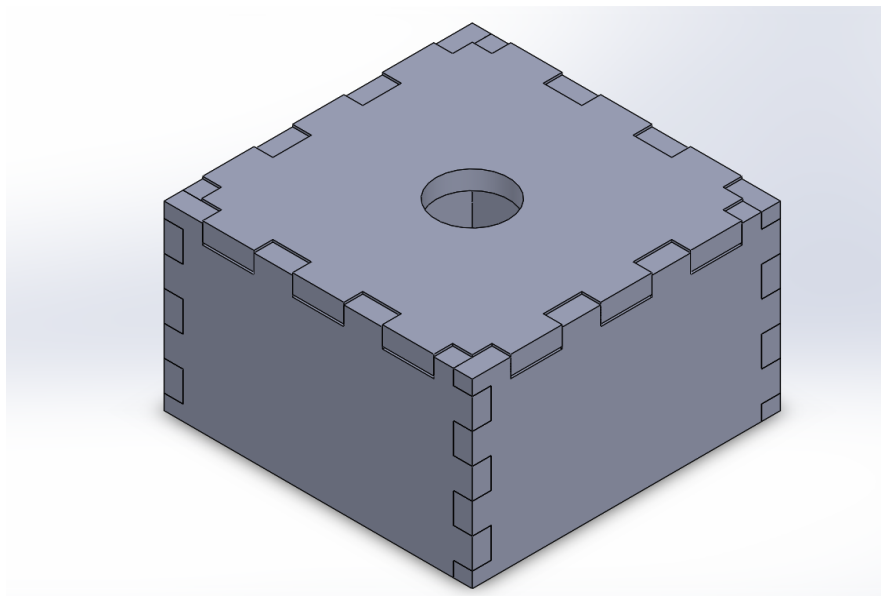


Figure 23: Arcade Button Box

There are several ways that the buttons can be wired to the Arduino UNO. This microcontroller was chosen both because it was used in the previous iteration of this project and because the project sponsor uses it for his other assistive technologies. The Arduino UNO has a total of thirteen digital input/output pins, six of which can be used for Pulse Width Modulation (PWM) and should be reserved for running actuators for the plucker mechanism. To read all six button values with the fewest pins, resistors can be put in parallel with the buttons and the voltage can be read through one of the five analog pins. By comparing the input to what is the known value of analog voltages per resistor, the pressed button or buttons can be calculated. The following figure is a circuit from the Arduino Forums on how buttons can be wired in parallel.

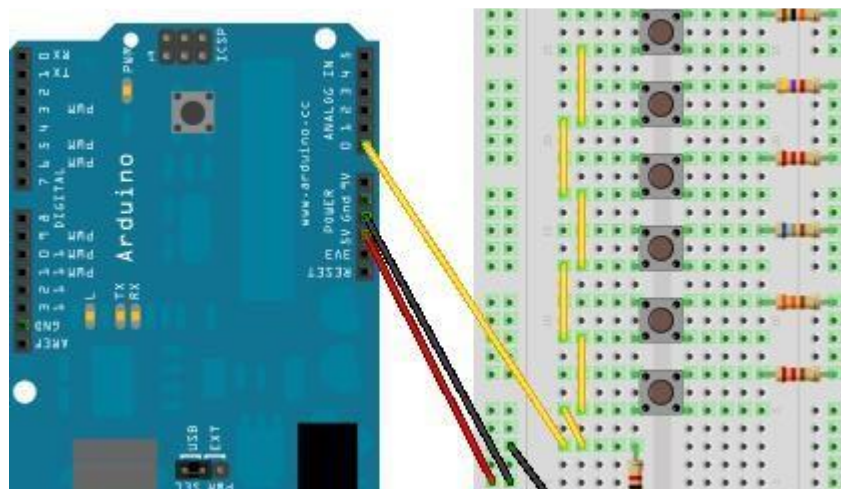


Figure 24: Parallel Button Circuit (digimike, 2010)

To test, one 100 mm arcade button and one momentary push button were used, as shown in Figure 25.

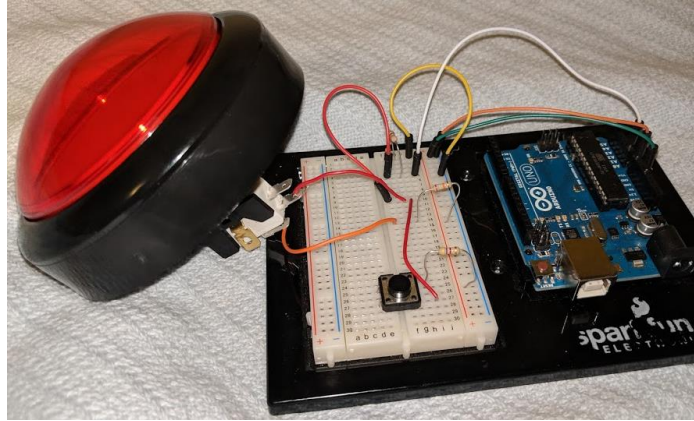


Figure 25: Button Testbench

Five percent precision resistor values (measured in ohms) that worked are presented in the following chart that shows the analog value for each pair of resistor values.

Table 5: Analog Values for Resistor Combination Chart

Resistor	0	2.2k	4.7k	8.2k	10k	12k	18k
0	0	836-837	692-694	558-560	509-511	460-461	362-363
2.2k	836-837	X	885-894	869-871	865-867	860-862	849-857
4.7k	692-694	885-894	X	785-787	773-774	762-764	741-743
8.2k	558-560	869-871	785-787	X	702-704	684-686	648-653
10k	509-511	865-867	773-774	702-704	X	659-660	619-622
12k	460-461	860-862	762-764	684-686	659-660	X	591-594
18k	362-363	849-857	741-743	648-653	619-622	591-594	X

Although 5% precision resistors were used for testing, they should not be used for the final user interface as the possible resistor variance leads to total resistances that could be

mistaken as two different combinations. There are also only twenty-four values of 5% resistors while 1% resistors offer a greater selection of ninety-six.

Inertial Measurement Unit

While the primary concern with the Inertial Measurement Unit (IMU) implementation is the computational complexity and accumulating errors, there are also design decisions to be made about how the system would be structured. The team compared two designs, the primary difference between these being the microcontroller board used.

Both designs will use the Sparkfun MPU-9250 IMU breakout board. The InvenSense MPU-9250 is a well-regarded standard for 9 degree of freedom motion tracking. Compared to competitors this device is more accurate, smaller, and cheaper. Additionally, the Sparkfun breakout board is well documented and has been thoroughly tested in conjunction with Arduino boards. In both designs the IMU will be communicating using an Inter-integrated Circuit (I2C) serial computer bus. This communication requires only two pins and can be used to communicate with many devices at once. The Sparkfun breakout board only allows for two device addresses but this can be extended using additional hardware if necessary. In both designs the Arduino microcontroller board will serve as the Master node, providing clock signal and initiating communication, and the IMU will serve as the Slave node, receiving the clock signal and responding to the master. In addition to a 3.3V power and ground this requires the SCL (clock) and SDA (data) pins on the Arduino. These pins are determined by the hardware.

The first design would be to use a stationary Arduino UNO with tethered connections to a logic level converter and then the Sparkfun MPU-9250. The IMU is a 3.3V device and the Arduino UNO has an operating voltage of 5V so the logic level converter is necessary to allow the I2C to be properly interpreted. Alternatively, this can be accomplished using external 4.7K

pull up resistors on the SCL and SDA pin. Since I2C communication already utilizes built in pull up resistors, these would be acting to reduce the voltage so that the IMU could interpret the clock and data sent from the Master node. This method is problematic primarily due to instability and should only be considered as a temporary solution. The logic level converter provides a permanent solution but introduces more complexity in the electronics.

The second design would involve using two Arduino Pro Mini 328 - 3.3V/8MHz boards with attached IMUs and wireless communication modules. The Arduino Pro Mini is a 3.3V board so no intermediate hardware is necessary to communicate with the IMU. The Pro Mini is also a much smaller board than the UNO so the whole device could be mounted directly on the control site. This gives the option to use wireless communication via nRF24L01+ transceiver module. Wireless communication provides the clear advantage of not risking cords becoming unplugged, tangled, or impacting the motion of the control site. The communication speed would need to be determined experimentally but similar projects have shown the response time to be sufficient. The Arduino Pro Mini does not come with USB for programming so this would have to be done via an additional component.

From a cost perspective the designs are nearly equivalent. The Arduino UNO costs around \$20 and the Arduino Pro Mini costs \$9, but two are needed so the costs are equivalent. The WiFi transceiver modules can be purchased at the rate of 10 for \$12. The logic converter can be purchased for only \$3 and only two would be needed.

Ultimately the decision was made to pursue the use of Arduino Pro Mini. The advantages of this design are that it can communicate with the IMU without intermediate hardware, is small enough to be mounted on the control site, and still provides comparable computational power.

Final Decision Matrix

After considering the IMU and button-based UI approaches in detail an updated decision matrix was constructed. The criteria listed from the previous matrix have been used to reevaluate the IMU and Button user interfaces for the final decision matrix in Table 6. The new scores were given based on both testing with the components and personal conversations with an occupational therapist. Criteria shown in bold have been re-evaluated and are fully described in Appendix G.

Table 6: Final Decision Matrix (bolded criteria have been re-evaluated)

Device/Criteria	1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	DECISION VALUE
IMU	5	5	5	5	5	4	5	5	5	2	5	5	3	4	1	0	3	231
Buttons	5	4	5	3	3	5	5	5	5	1	1	1	3	4	5	5	3	215
Criteria	Criteria number	Weighting (1-5)																
Power Requirements	1	2																
Direction of Motion requirement	2	3																
Range of motion requirement	3	2																
Control sites supported	4	4																
Viable for different ranges of motion?	5	4																
Time for calibration	6	3																
Steps needed to calibrate	7	1																
Setup time	8	3																
Estimated Computational complexity	9	5																
Final Cost	10	5																
Input detail	11	4																
User Difficulty	12	4																
Effect on user body	13	5																
Manufacturing of custom parts	14	4																
Repairability	15	3																
Error accumulation rate	16	5																
Code Editing Requirement	17	5																

Developed Design

Electronic Component Selection

To implement the IMU-based user interface, the following components are needed: three Arduinos, three wireless transceivers, two IMUs, one RGB LED, one momentary push button, and batteries. The components are used for three separate devices: two identical wearables and one device mounted to the guitar.

The wearable devices used the 3.3V Arduino Pro Mini 328, for its small size of 18 by 33 mm and same 3.3V logic level as the MPU-9250 IMU. The guitar device used the Arduino UNO, which was saved from the previous project iteration. The UNO provides a sufficient number of digital I/O pins and has a small-enough footprint that it can be easily mounted to the same base plate as the plucking device. The wireless transceivers that have been selected for the project are the nRF24L01+ Single Chip Transceiver. The nRF24L01+ communicates to the Arduinos via Serial Peripheral Interface (SPI) and features bidirectional communication up to 2 Megabits per second (Nordic Semiconductor, 2008). Furthermore, this device can be used to develop a network of up to 3125 devices communicating over a single channel, each module actively listening to six other modules at a time (How to Mechatronics, n.d.) so this application is well within the communication limits of the chip.

The goal for powering the devices was to use batteries that enable all the devices to be portable as well as provide several hours of use between charges. For the wearable devices, the total current draw was estimated to be about 50mA; the Arduino Pro Mini draws 30mA, the IMU draws 5mA, and the nRF24L01+ draws 15mA. The selected battery is a 3.7V 400mAh Lithium Ion battery that will supply about 8 hours of continuous use between charges. For the guitar

device, the overall current draw was estimated to be 400mA. The Arduino UNO draws 45mA, and the RGB LED draws 20mA.

The largest source of current use is the plucking mechanism. The servo motors draw 120 mA no load and up to 800mA when stalled. Given the usage, the assumption is that only two motors will be running at the same time. Using Equation 1 and Equation 2, the speed, torque, and current relationships were calculated in Table 7 and plotted in Figure 26.

Equation 1: Torque of a Motor

$$torque = torque_{stall} - \frac{torque_{stall} * speed}{speed_{noload}}$$

Equation 2: Current Draw of a Motor

$$current = torque * \frac{current_{stall} - current_{noload}}{torque_{stall}} + current_{noload}$$

Table 7: Speed Torque and Current Draw of FS90R Motors

Speed (RPM)	Torque (in-oz)	Torque (in-lbf)	Current (A)	Current (mA)
0	21.0	1.3	0.8	800.0
8.66	19.6	1.2	0.8	754.7
17.32	18.2	1.1	0.7	709.4
25.98	16.8	1.1	0.7	664.1
34.64	15.4	1.0	0.6	618.8
43.3	14.0	0.9	0.6	573.5
51.96	12.6	0.8	0.5	528.2
60.62	11.2	0.7	0.5	482.9
69.28	9.8	0.6	0.4	437.6
77.94	8.4	0.5	0.4	392.3
86.6	7.0	0.4	0.3	347.0
95.26	5.6	0.4	0.3	301.7
103.92	4.2	0.3	0.3	256.4
112.58	2.8	0.2	0.2	211.1
121.24	1.4	0.1	0.2	165.8
129.9	0.0	0.0	0.1	120.5

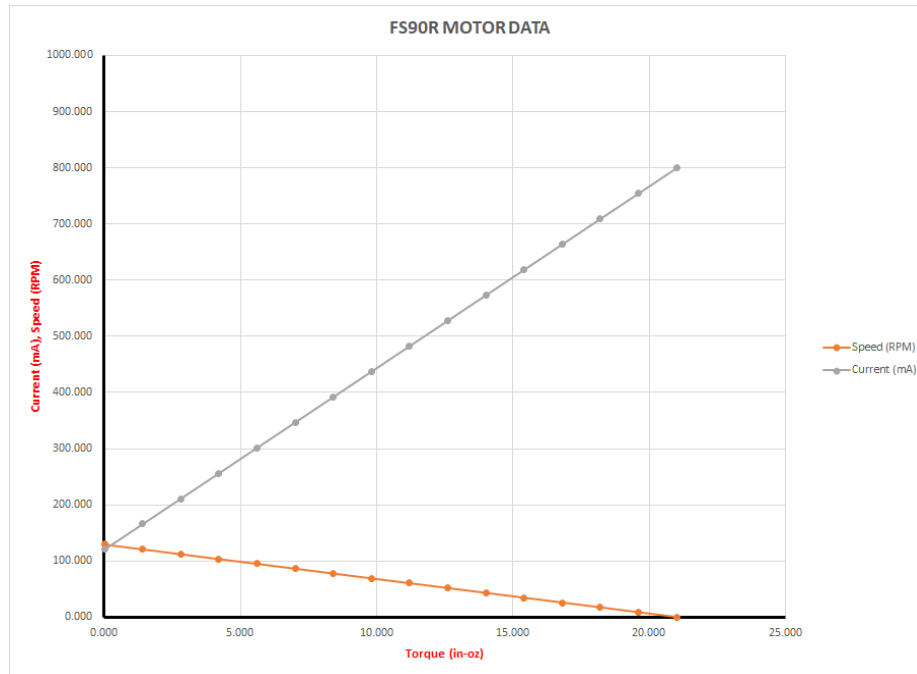


Figure 26: Speed and Current vs. Torque of FS90R Motors

Based on SolidWorks test results, the estimated torque to the motor during a pluck is 1.4 in-oz and would result in 165mA current draw. Given the total estimation of 400mA, two 3.7V 1Ah batteries were selected. Two batteries were needed to get 7.4V in series to be within the Arduino UNO’s voltage requirement.

Circuit Design

To eliminate the end user having to solder any electrical components, printed circuit boards (PCBs) were designed for both the wearable devices and the guitar device. The schematic for the wearable device board is presented in Figure 27. Table 8 presents the pinout of the design.

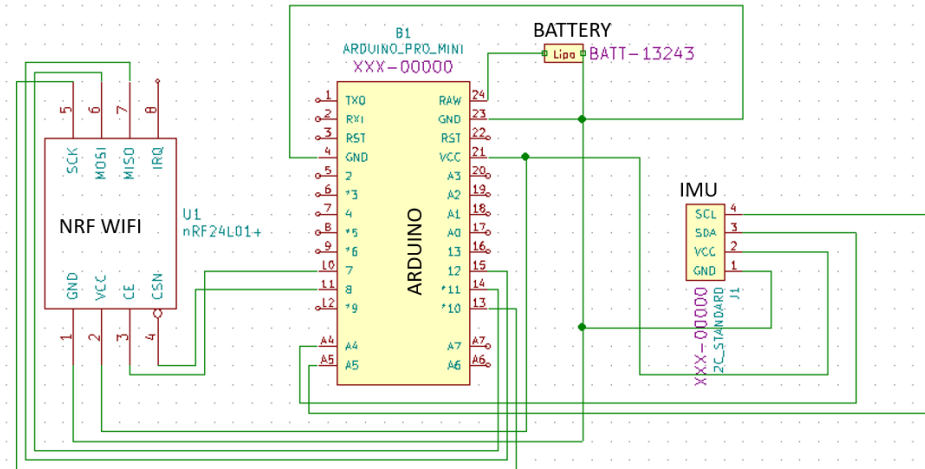


Figure 27: Wearable Device Writing Schematic

Table 8: Wearable Device Pinout

Pin Number	Pin Name	Connection
4, 23	GND	Battery ground, nRF Ground, IMU Ground
10	D7	nRF CE
11	D8	nRF CSN
14	D11	nRF MOSI
15	D12	nRF MISO
16	D13	nRF SCK
21	VCC	nRF VCC, IMU VDD
24	RAW	Battery Power
A4	SDA	IMU SDA
A5	SCL	IMU SCL

An additional goal of the PCB for the wearable devices was to make the footprint of the device as small as possible so that the device could be mounted to any control site comfortably. The resulting PCB design is presented in Figures 28 and 29. The board is 40 by 40mm square and the Arduino Pro Mini, nRF24L01+ and IMU fit all fit within this footprint. To make all

components fit, the nRF and IMU are mounted on the top of the PCB, and the Arduino and battery connector are mounted to the bottom of the PCB. To accommodate all of the required connections, it is a multilayer design; the red traces are the top copper layer, and the green traces are the bottom copper layer.

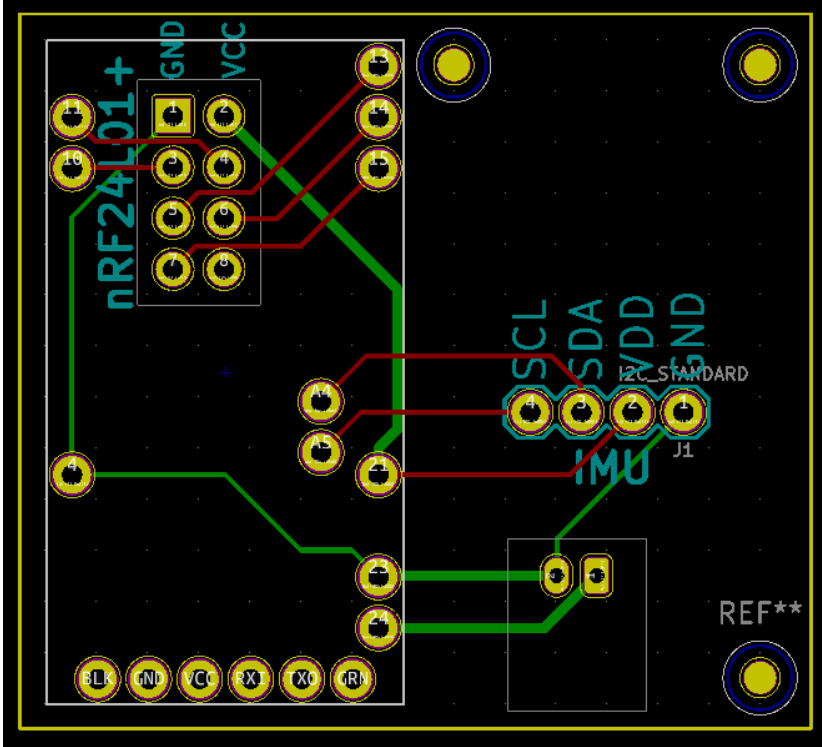


Figure 28: Top View Wearable PCB Design

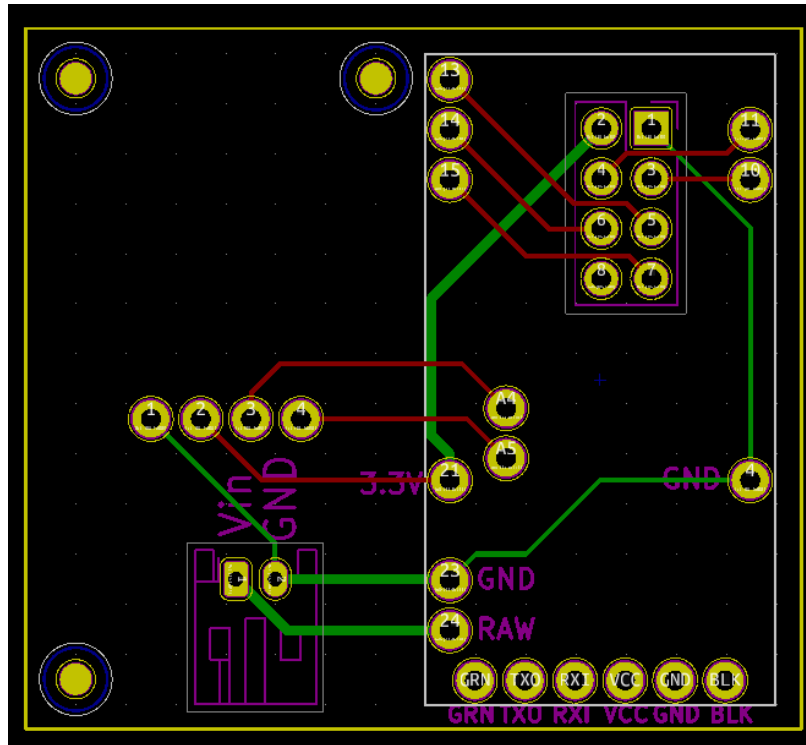


Figure 29: Bottom View Wearable PCB Design

The guitar device wiring schematic is presented in Figure 30. Table 9 presents the pinout of the design.

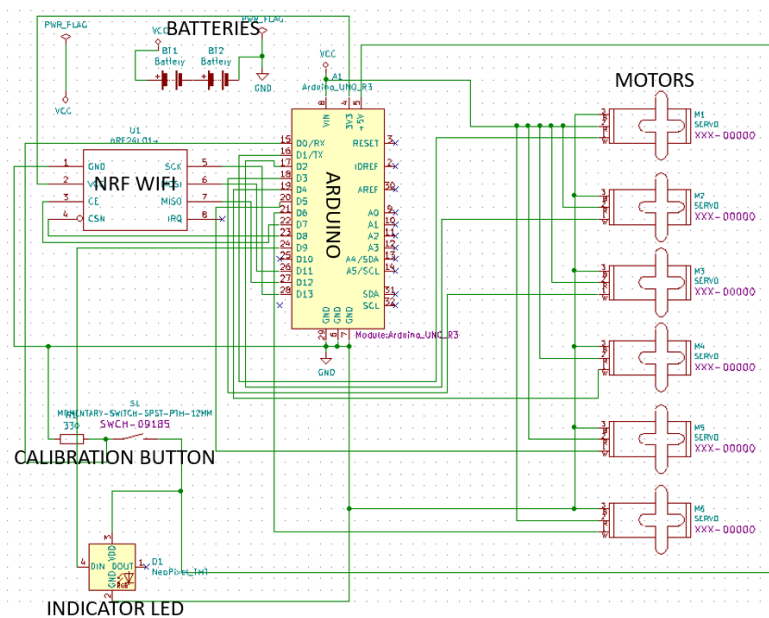


Figure 30: Guitar Device Wiring Schematic

Table 9: Guitar Device Pinout

Pin Number	Pin Name	Connection
15	D0/RX	Button
16	D1/TX	Servo 1 Input
17	D2	Servo 2 Input
18	D3	Servo 3 Input
19	D4	Servo 4 Input
20	D5	Servo 5 Input
21	D6	Servo 6 Input
22	D7	nRF CE
23	D8	nRF CSN
24	D9	LED DIN
26	D11	nRF MOSI
27	D12	nRF MISO
28	D13	nRF SCK
8	VIN	Battery Power, Servo VCC
4	3V3	nRF VCC
5	+5V	Button, RGB LED
6, 7, 29	GND	Battery Ground, Ground of all components

The guitar device PCB was designed to fit over the top of the Arduino UNO with all of the components mounted to the top. Just like the other PCB, the red traces are the top copper layer, and the green traces are the bottom copper layer. The PCB layout is shown in Figure 31.

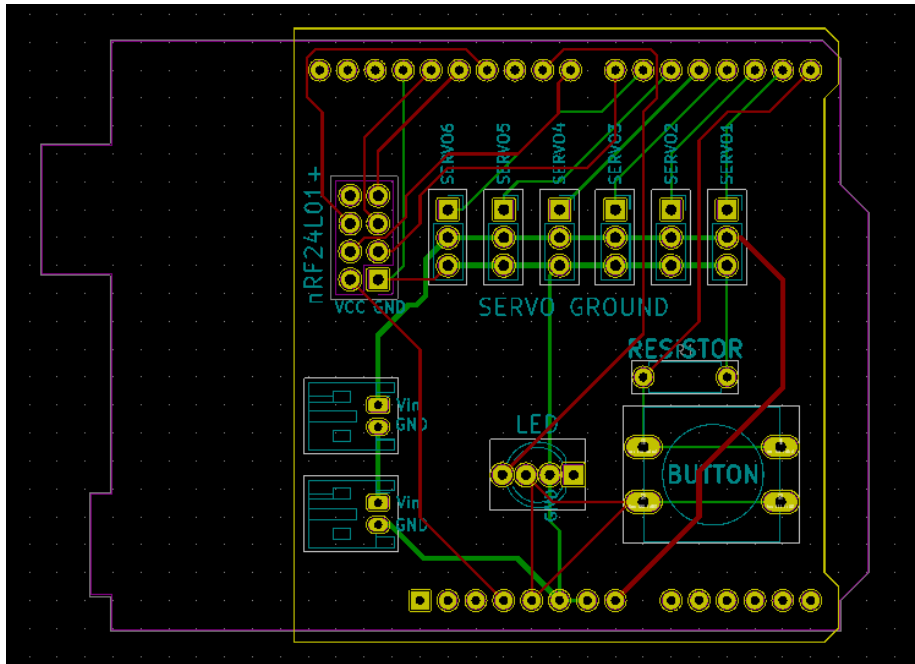


Figure 31: Top View Guitar PCB Design

Device Casing

All the electrical components for the IMU UI are contained within a two-part 3D printed casing that can be strapped to a person on various locations, this includes but is not limited to the hand, wrist, arm, leg, or even head. The bottom half of the case is printed in PLA plastic with a density fill of 25%. This part of the case is where the boards and battery sit, with the three extruded pins going through the screw holes in the PCB board. On the bottom, located under the main cavern is a large rectangular cut away that a strap can go through and be used to secure the device. There are also two small rectangular cut outs located on opposite sides on the top walls, these two holes are where the top snaps into place. The top is made out of TPU plastic printed at a density of 15% which provides enough flexibility for the snap fit to work without breaking off latches on the top. In the device created the strap was made from Velcro and cloth sewn together

to provide a secure and easily adjustable fit, but it can be interchanged with anything that would fit through the strap hole on the casing.



Figure 32: Pictures of Device Casing

Overall Code Design

The diagram below gives an outline of the electronic components of this system and shows how these communicate. The components in the blue box are mounted on the user's control site and communicate via a wireless transceiver with the components in the red box, which is mounted on the guitar. This diagram also labels communication protocols and the information being communicated. The software development has been split into three components:

1. Reading IMU sensor values with Arduino Pro Mini and generating string plucked messages
2. Sending messages regarding string plucks via wireless transceiver
3. Use Arduino UNO on guitar body to control servo motion

Figure 33 describes the function of each major component and the communication protocols used to send messages between them. The signals used are Serial Peripheral Interface (SPI), Inter-Integrated Circuit (I2C) and Pulse Width Modulation (PWM).

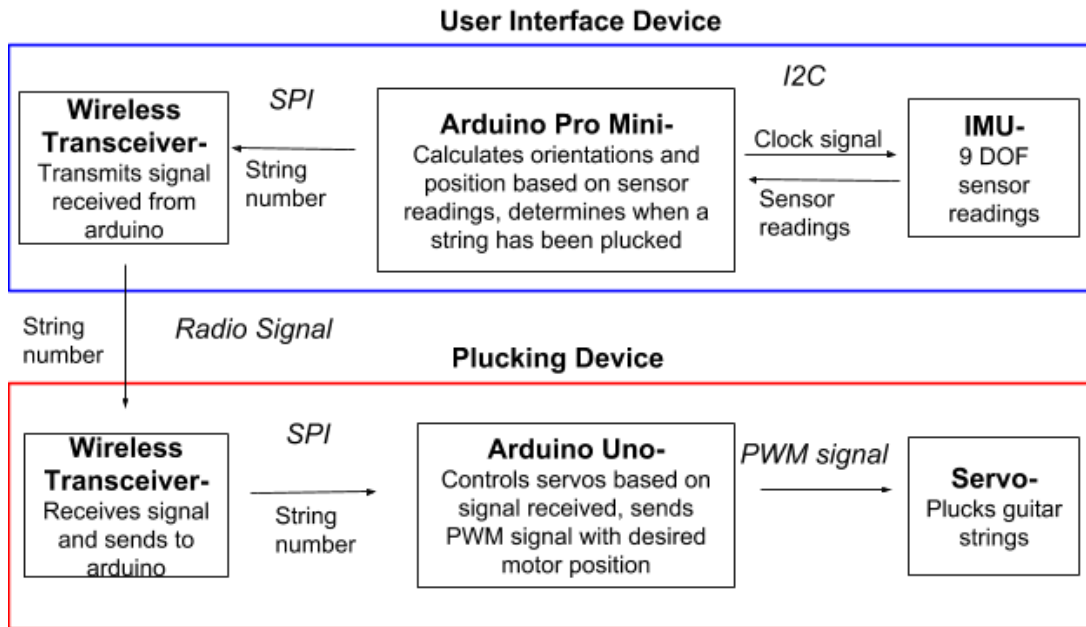


Figure 33: Top Level Code Control

The wearable devices are responsible for reading the IMU sensor output and for the necessary computations to turn these readings into which string to pluck. The guitar device is responsible for plucking a string when messaged to do so, and to initiate calibration of the wearable devices when the onboard button is pushed. Since there are two IMU devices there will be two sets of messages to pluck strings sent to the guitar. A simplified flowchart of the whole system is shown below in Figure 34. The code for the wearable devices is in Appendix XYZ and for the guitar device is in Appendix ZYX.

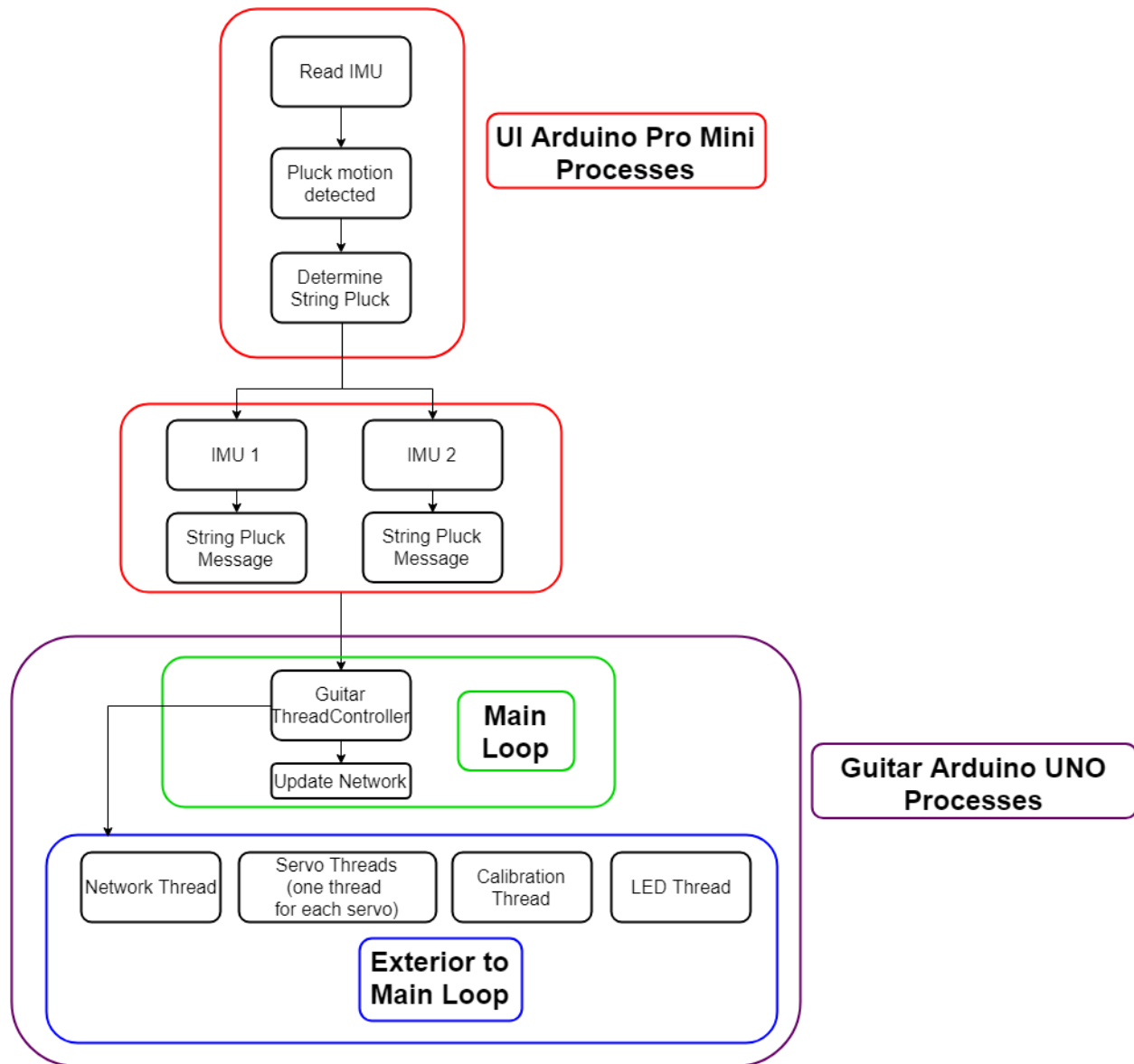


Figure 34: Flow Chart of Whole Device Code

A calibration process is included in the system to allow for a wide range of users with various ranges of motion to be able to use the device. The calibration process works through communication between the IMU device and guitar device. The process is initiated by pressing a button on the guitar device and then again for each subsequent phase of the calibration. A flow chart of this process on both boards is shown below in Figure 35. The calibration sets parameters to be used in determining when a pluck is registered.

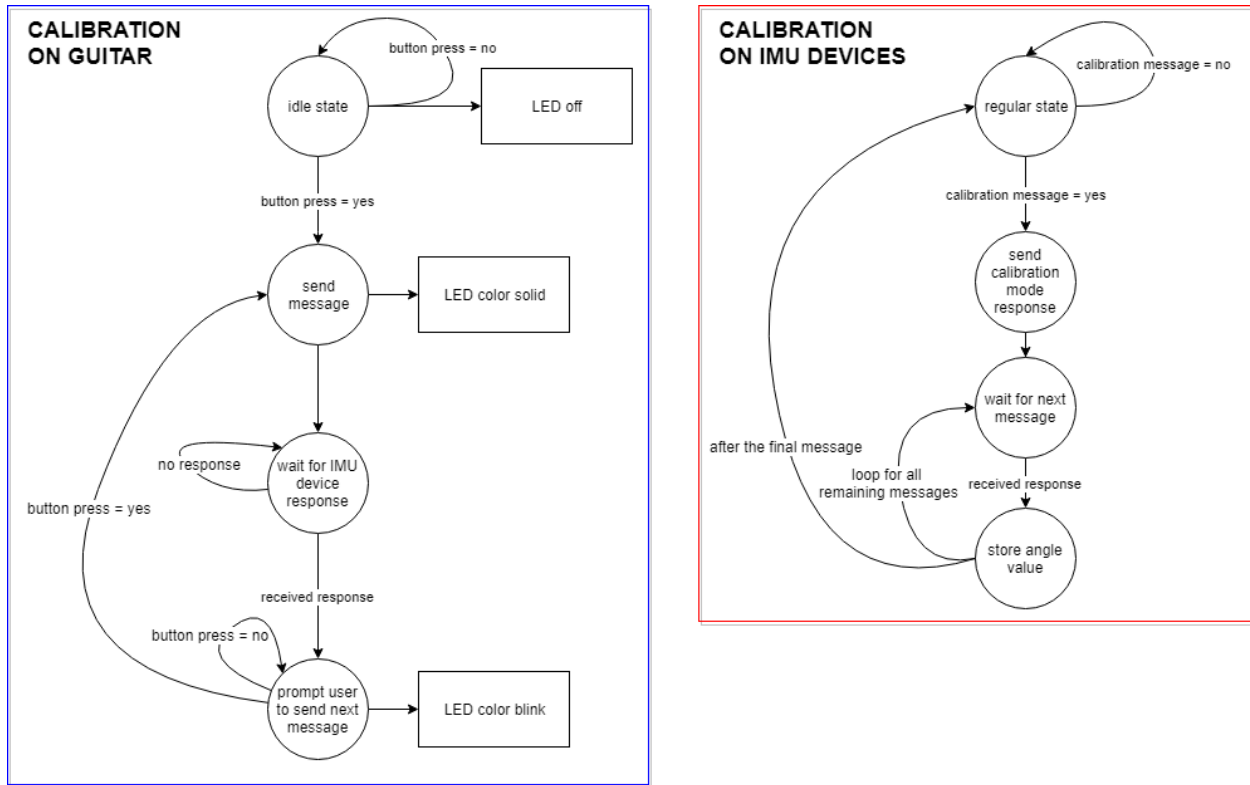


Figure 35: Calibration Process in IMU and Guitar Devices

Wearable Device Code Design

The readings from the IMU give the measurements from the accelerometer, gyroscope, and magnetometer along three axis each for a total of nine degrees of freedom. Using sensor fusion, these readings are combined and filtered to give useable orientation values in the form of Euler angles. This orientation data is used to determine when pluck messages should be transmitted to the guitar. There are two wearable devices simultaneously transmitting to the guitar to allow for the user to pluck multiple strings at once, a necessity for imitating normal guitar play. A diagram of the wearable device process is shown below in Figure 36.

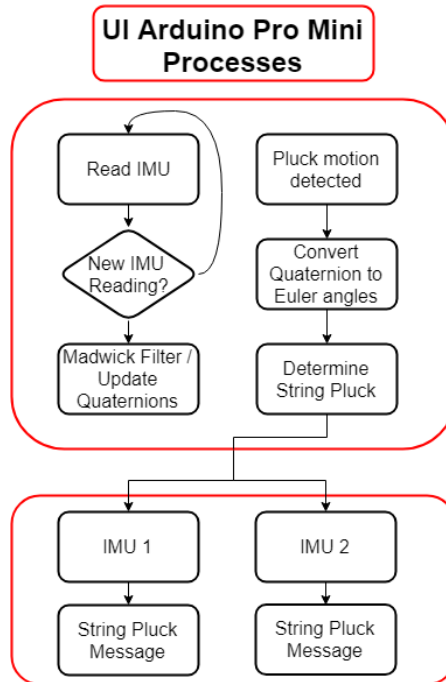


Figure 36: UI Arduino Flowchart

Tracking Orientation of Wearable Device

Instantaneous readings of each of the nine axis are taken roughly 147 times a second. The raw readings provide information on the instantaneous motion of the IMU but needs to be processed to be useful for orientation tracking. These are filtered using a Mahoney-Madgwick filter which uses the acceleration due to gravity and the earth’s magnetic field to find the device’s orientation in absolute space. Incrementally the sensor readings are applied based on the previous readings and expected variance giving a robust estimate for the device’s orientation expressed in quaternions. The Mahony-Madgwick filter implemented for this goal is a sophisticated, lightweight algorithm that gives sensor fusion typical of a Kalman filter but in a much more efficient manner. Importantly these calculations will be able to keep up with the approximately 147 Hz sampling frequency of the IMU. This ensures the orientation will be recent and there will not be error resulting from missing readings during computation.

There are two main components to the wearable device code structure, an interrupt that takes readings from the IMU and a loop for processing the readings and calculating string pluck signals. Before either of these components are used there are necessary setup functions that will only be used once to initialize communication between the Arduino and IMU, and to calibrate the IMU tolerances. Whenever all nine variables of the IMU have a new value a signal is sent to the Arduino; when this is received an interrupt is triggered and code that reads the IMU and stores the values is called. The rest of the code runs in a loop that processes the IMU readings using the Mahoney-Madgwick filter to update the quaternions.

Euler angles and quaternions are two methods of representing the orientation of a body. Each has their own advantages and disadvantages and work in significantly different ways. Quaternions use complex numbers to represent a rotation *theta* around a fixed axis known as the Euler axis. Euler angles use pitch, roll and yaw to represent a rotation. Euler angles have some inherent disadvantages for tracking orientation but are better for intuitive understanding of orientation information. In this application the orientation is tracked in quaternions and converted to Euler angles only for the purpose of detecting plucks intuitively. Figure 37 summarizes the concerns for each method.

Quaternion	Euler Angle
Less computational overhead (single rotation)	Easier to understand
Easier to convert to matrix form	Prone to Gimbal lock singularity
Difficult physical interpretation	Requires three rotations to be applied

Figure 37: Angle Representations

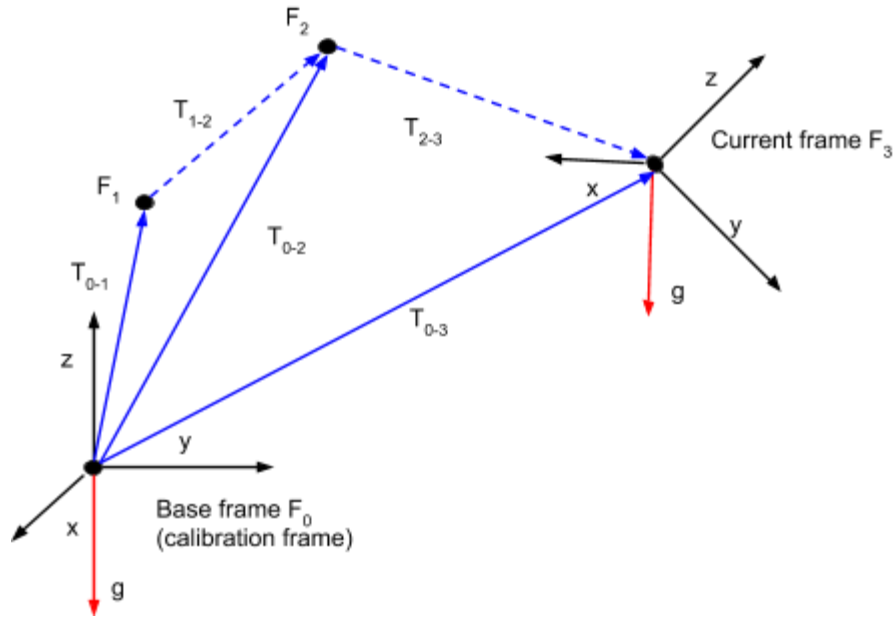


Figure 38: Diagram to Show transformations of IMU coordinate frames

Figure 38 shows how the transformation from the base frame to the current frame would be tracked and updated. The orientation information in the quaternions can be easily represented as a rotation matrix T . The double integration of the x , y , and z axes of the accelerometer form the displacement components giving us the form of the matrix shown below:

Equation 3: Homogeneous Frame Transformation Matrix

$$\begin{bmatrix} & & & x \\ & T & & y \\ & & & z \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

T is the 3x3 rotation matrix and x , y , and z are the displacements along each of those axis.

A matrix tracks the current position of the IMU (with respect to the base frame), and each time the sensors are read, an intermediate transformation matrix between the current position and

the past current position (T_{1-2} or T_{2-3} in Figure 38) is also created. The intermediate transform and the base frame transform are combined into an updated base frame transform matrix.

Concerns with Position Tracking

The accelerometer readings have some noise and a great amount of drift. Since the acceleration data accumulates in the velocities which again accumulate in the position that is being tracked, small errors in acceleration data can have a significant impact on the results. Each axis of the sensor has different (and inconsistent) error so they must be calibrated separately. After calibration significant variance persists in the readings that must be accounted for using tolerancing. Applying tolerances to these readings is difficult because small changes in acceleration readings could be all that represents a significant change in IMU position, so this must be done in a way where insignificant changes are ignored, and significant changes are considered. Another difficulty of the calibration is that the accelerometers measure the force of gravity acting on them. As the IMU is rotated this force will not be applied along the same axis as it was when the IMU was calibrated, therefore the rotation matrix generated from the gyroscope and magnetometer readings is needed to determine the transformation between the gravity force when calibrated in the base frame and gravity in the frame of the IMU after rotation.

Based on these considerations the team developed two different approaches to implementing the IMU for the control guitar string plucks:

1. Using the orientation data exclusively, plucking the strings based on rotations.
2. Using the acceleration readings coupled with the orientation to determine position and incorporate an external sensor to adjust for drift.

The acceleration readings from the IMU alone have too much error to accurately track position. Although further filtering could be applied to the sensor readings ultimately the drift is difficult to combat without some other input. Due to the overhead of having to set up both the IMU and an external sensor for the second proposed control schema, orientation-based control was used in the final prototype.

Determining Pluck signals and Controlling Device

The final aspect of the wearable device code is detecting when a pluck signal should be sent. The final control algorithm accomplishes this using only orientation information and limited motion characteristics. The pitch value from the Euler angles of the IMU is compared to certain thresholds determined during calibration. The pitch is controlled by the user through changing the angle of the device. A 'pluck' is registered when the motion starts and then stops. The string signal to be sent when a pluck is registered is based on the angle of the device as shown in Figure 39. The pluck motion ensures that the wearable device only sends a pluck message for the last string crossed as opposed to each string. In order to pluck each string crossed the user must move the device over the entire range in one motion, thus registering a strum and sending a pluck signal for each of the strings.

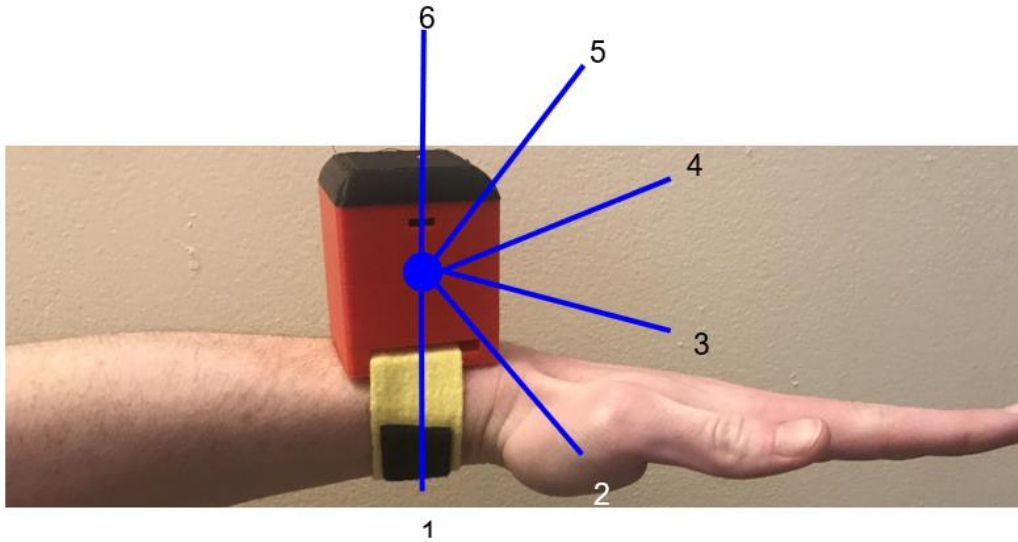


Figure 39: Plucking Angles

Guitar Device Code Design

The guitar device had to be able to respond to many simultaneous events, such as plucking one string while receiving a message to pluck to another. The Arduino UNO has a single core processor and does not have the ability to run multiple loops at once inherently. To overcome this limitation, “protothreading” was implemented to handle several events. Protothreads act to replace multithreading on devices that do not have multiple cores by rapidly calling small functions of non-blocking code. Whereas multithreaded programs run on multiple stacks in memory, protothreads all run from the same stack and rewind the stack to call on various threads (Dunkels et al., 2005). Figure 40 represents the main loop and protothread tasks.

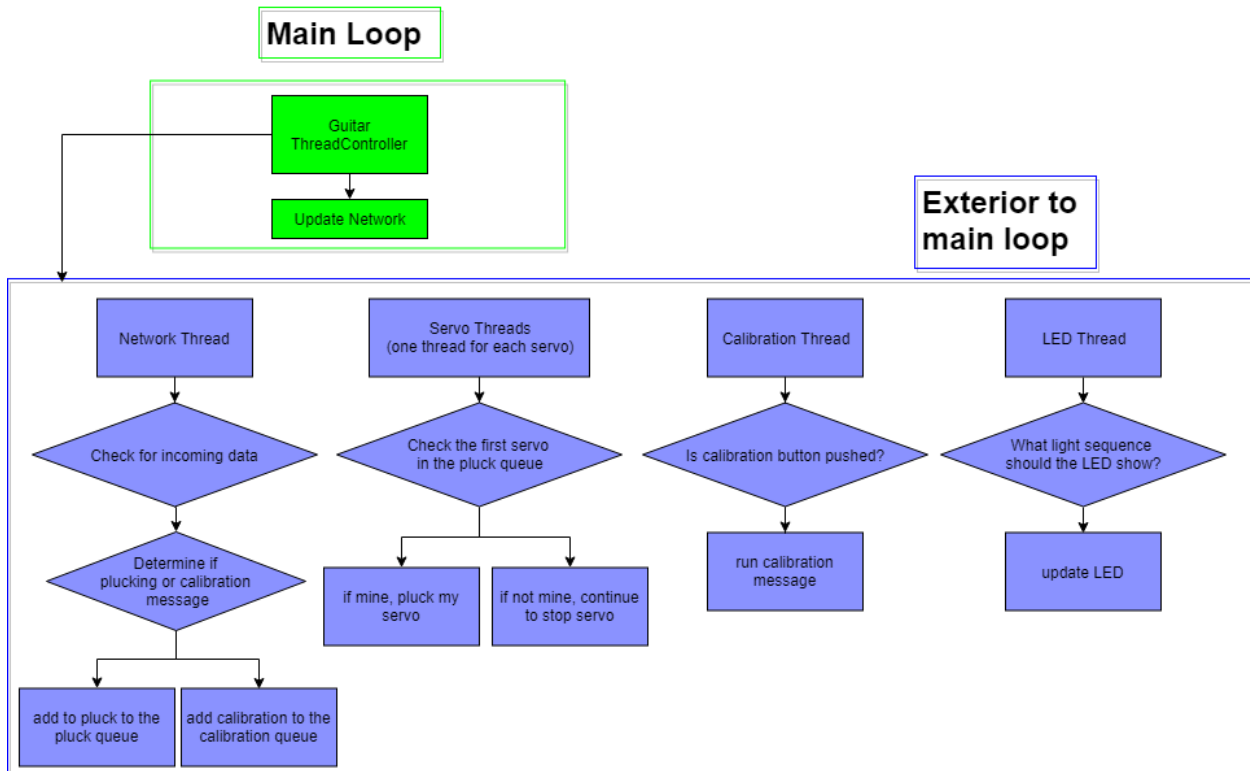


Figure 40: Guitar Code Architecture

Prototyping and Testing

Assembly of Plucker and Frame

For initial testing, a single plucking device was assembled. The initial functional test resulted in failure; when the motor was activated, the 3D-printed shaft broke under the applied load, and the shafts bent, causing the gears to slip. The plucking device was redesigned to account for these problems, while maintaining the same basic mechanism and reusing parts wherever possible.

Redesigned Plucking Device

To rectify the problems found during prototype testing, the 3D-printed shaft was replaced by a threaded metal shaft glued to the plectrum. A new frame element was created to support the shafts on both sides of the gears, preventing the gears from slipping during operation by significantly reducing the ability of the shafts to bend. Washers were used to provide spacing between components, reducing friction in the mechanism.

In this design (Figure 41), the motor (1) is held to its frame (2) by a pair of M1.6 screws and nuts (3,4). The servo armature (14) is held to the motor by a coaxial set screw (not pictured), and a spline connection transmits torque. The servo armature is cut short to prevent collisions with the string, and the upper shaft (5) is glued to the armature; the wide connection allows transmission of torque through contact as well as through the adhesive, increasing the strength of the connection. The 12mm gear (6) is mounted on the upper shaft and held in place by a radial 0-80 setscrew (not pictured), with additional adhesive strengthening the connection. The upper shaft is supported on either side by the gear frame (8). The 6mm gear (7) meshes with the 12mm

gear and is held to the lower shaft (13) by another radial set screw. Again, the shaft is supported on either side of the gear by the gear frame (8). The plectrum (11) is mounted on the lower shaft outside the gear frame; it is glued to the shaft and held in place with a pair of M1.6 nuts and a small piece of wire through the side of the plectrum. The lower shaft is supported on the far side of the plectrum by the shaft mounting (12). Spacing between components on shafts is provided by M2 and M4 washers (10, 9), for the lower and upper shafts, respectively. Initial testing of this design found that the glue was not sufficient to hold the plectrum to the shaft; after multiple tests of different plectrum, shaft, and glue options, the final design used two-part epoxy as an adhesive, mounting a 6mm wide plectrum. The gear frame kept the shafts aligned properly, and the gears functioned well in multiple tests.

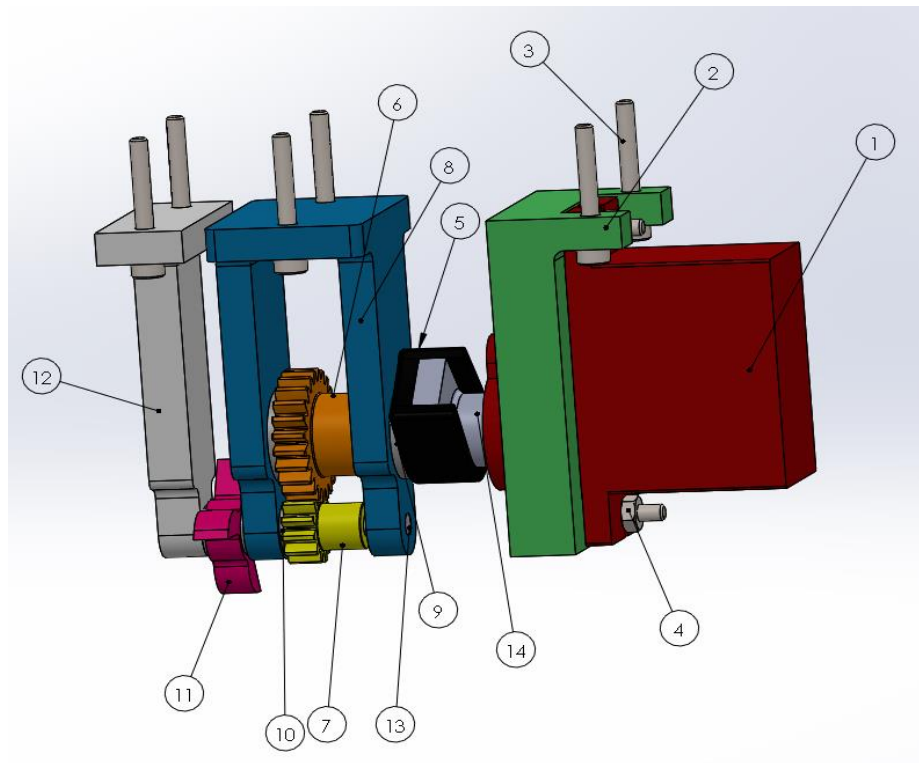


Figure 41: Redesigned Plucking Assembly

Table 10: Components of Design

Component Number	Component Name
1	Servo Motor
2	Motor Frame
3	M1.6 screw
4	M1.6 nut
5	Upper Shaft
6	12 mm Gear
7	6 mm Gear
8	Gear Frame
9	M4 washer
10	M2 washer
11	Rotating Plectrum
12	Shaft mounting
13	Lower shaft
14	Servo armature

User Interface Devices

Manufacturing and Assembly

The first iteration of both printed circuit boards was printed on copper-clad FR4 with a LPKF ProtoLaser S4 machine on the WPI campus. These boards have the advantage of being produced very quickly.

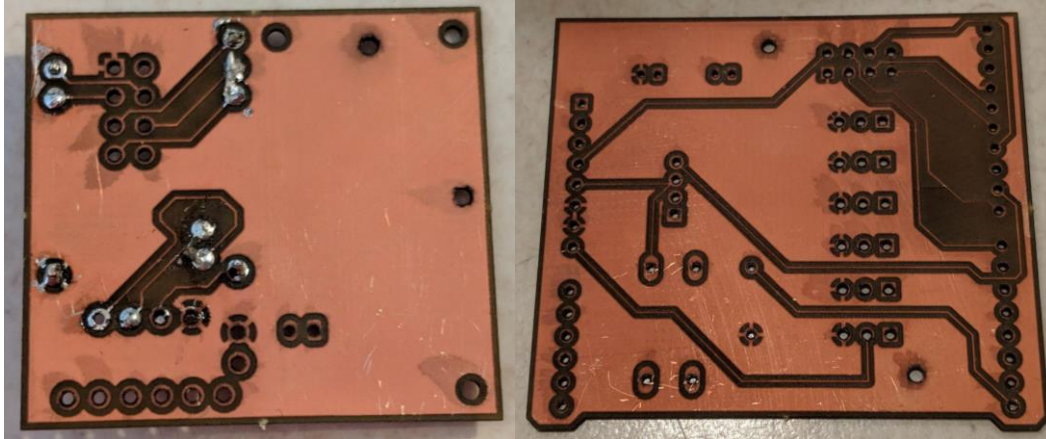


Figure 42: PCBs Manufactured on WPI Campus (Wearable Device left, Guitar Device right)

These boards are convenient; however, we determined that for a better end product, we chose to use an external manufacturer. The boards printed at OSH Park were also printed in copper-clad FR4, have a purple mask printed over to protect the traces, and have silk-screening capabilities so that we could label where components are to be plugged in to make it easier for the end user to assemble. The following pictures are the final boards produced by OSH Park.

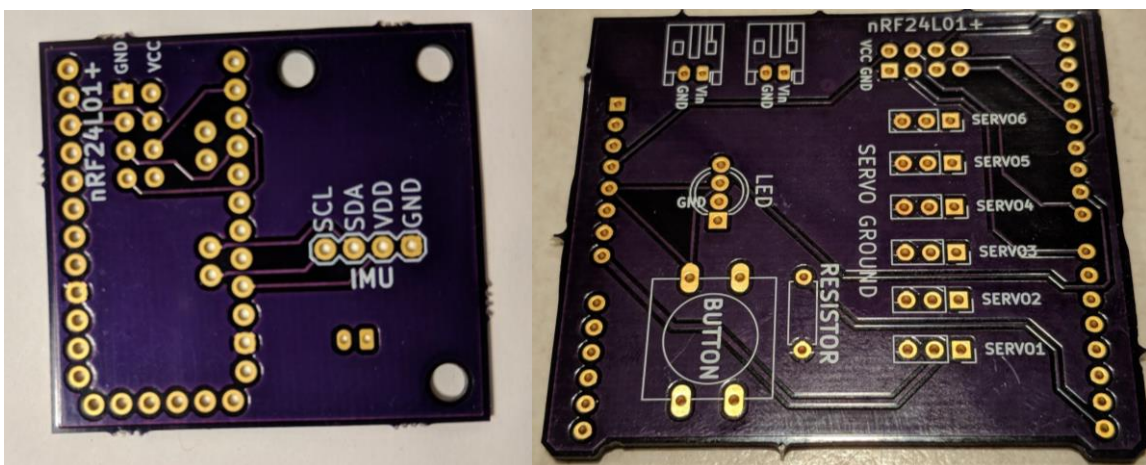


Figure 43: PCBs Manufactured Externally (Wearable Device left, Guitar Device right)

The PCBs for both the wearable device and guitar device were assembled such that components could be switched out if one component was damaged, all the end user would need to do is to plug in a new one. This was done by mounting male and female headers to the

components and PCBs, instead of directly soldering to each other. Figure 44 shows the assembly of one wearable device unit, and Figure 45 shows the assembly of the guitar device.

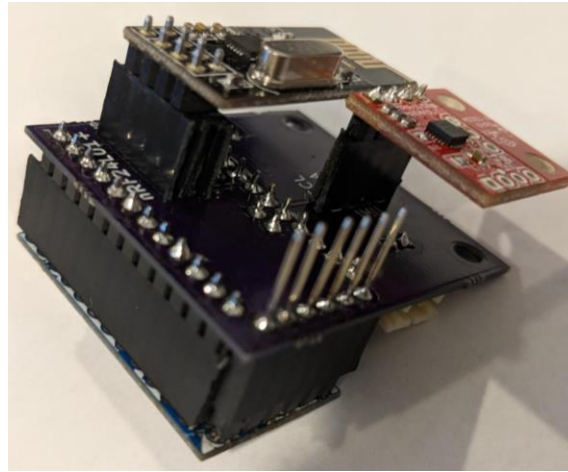


Figure 44: Wearable Device Circuit Assembly

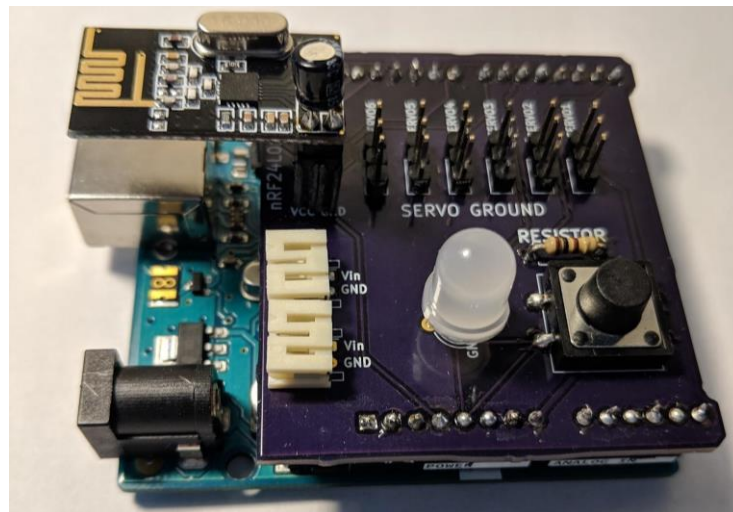


Figure 45: Guitar Device Circuit Assembly

User Testing

In order to determine if the user interface device would be capable of giving accurate readings at the speeds and ranges needed, user testing was required. This also gave the opportunity to gather subjective feedback about user preference in playing settings. The metric for judging success at each different setting was the percentage accuracy of notes played which

would be automatically recorded. The user interface was tested with 9 people who had no disability. Three tests were run modifying the calibrated different angles needed to activate a pluck in each. One test was run at a faster playing speed. The user would control the device by tilting their hand vertically around the wrist while holding the IMU. The angle of the IMU's reading would be used to track the orientation which would be used to determine plucks. A pluck is registered if the IMU crosses a threshold, defined at regular intervals by the 'string angle'.

Table 11 shows the details of the tests.

Table 11: Test Details

	Range between string selections (in degrees)	Speed in BPM
Trial 1	15	20
Trial 2	25	20
Trial 3	5	20
Trial 4	15	30

Each user practiced using the device by giving them some time where the 'plucks' they produced were displayed on the screen. Any questions about control of the device were answered and then the first trial began. During a trial, the user was prompted with different numbers and had to play them within the allotted time (2-3 seconds depending on trial). At the end of a trial the accuracy was automatically calculated and printed on the screen to be recorded. The program would adjust the variables for the next trial (string angle or speed) and prompt the user to practice with this new control. This process of practicing and playing notes was repeated for each of the trials. Table 12 shows the results recorded. An image of the test is shown in Figure 46.


```

COM5
/
4
5
Play the notes that appear on the screen in...
3...
2...
1...
begin!
/
|-----3-----| ///24/
|---2-----| /3/2//
|-1-----| //1///
|---2-----| /2////
|-----3-----| /3////
|-----5-----| /5////
|-----3-----| /3////
|---2-----| /2////
|-1-----| /1////
|---2-----| /2////
|-----3-----| /3////
|-----4-----| /4////
|-----3-----| //3///
|---2-----| /2////
|-1-----| //1///
|---2-----| /23///
|-----3-----| /23///
|-----4-----| /4//

```

Figure 46: Sample results from one of the testing trials

Table 12: Test Results

User #	Trial 1 accuracy	Trial 2 accuracy	Trial 3 accuracy	Trial 4 accuracy
1	0.69	0.78	0.33	0.81
2	0.89	0.89	0.53	0.75
3	0.81	0.97	0.94	0.92
4	0.94	0.92	0.89	0.69
5	0.78	0.81	0.58	0.67
6	0.92	0.97	0.56	0.86
7	0.89	0.97	0.75	0.61
8	0.89	0.67	0.86	0.61
9	0.56	0.47	0.25	0.33
Average	0.819	0.828	0.632	0.694

The team also asked for feedback from the users about their ability to control the device and the most comfortable range. The team asked each user the preferred range based on ease of control. The preferred ranges are shown below in Table 13.

Table 13: Preferred Ranges

	Percent preferred by (user could prefer more than one range) n=9
Small range (5 degrees between notes)	11%
Medium Range (15 degrees between notes)	55%
Large Range (25 degrees between notes)	55%

Overall these tests gave some important insight to the limits of the device and the user's ability to operate it. Although the accuracy was lower at faster speeds the device was capable of handling playing speeds much faster than the users were playing. Based on the sample rate of the IMU, the fastest possible playing speed for the device is 0.0071 seconds per note or 8400 beats per minute meaning that communication with the IMU will not be a limiting factor in the response time of the device.

Results

Final Device

The final device consists of six plucking devices, each with a rotating plectrum driven by a servo motor, controlled by a single Arduino UNO and mounted on a frame which holds the plectrums in position over the guitar strings. Two user interface devices are worn by the user and send signals to the Arduino on the guitar device, triggering plucks based on the angular movement of the user's control site. The position of the guitar in the frame can be adjusted to account for different distances between the pluckers and guitar strings, while the plucker devices can be adjusted both along the guitar strings and perpendicular to them to ensure the pluckers are in an optimal position on any guitar. The plucking devices use a pair of gears to offset the plectrum from the motor, providing adequate space for the strings, and increasing the rotation speed of the plectrum relative to the motor. The plucking device drawings are in Appendix J, and frame drawings are in Appendix K. Assembly instructions for the plucking device are in Appendix L, for the frame are in Appendix M, and for the user interface are in Appendices N and O. The following figures are of the device in its final state.



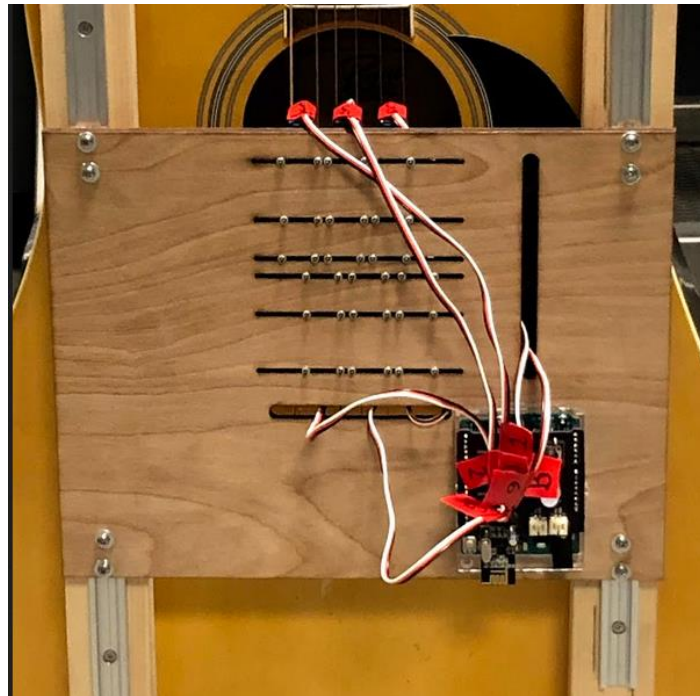


Figure 47: Final Plucking Device (Top), Close-up View of the Plucking Device (Bottom)

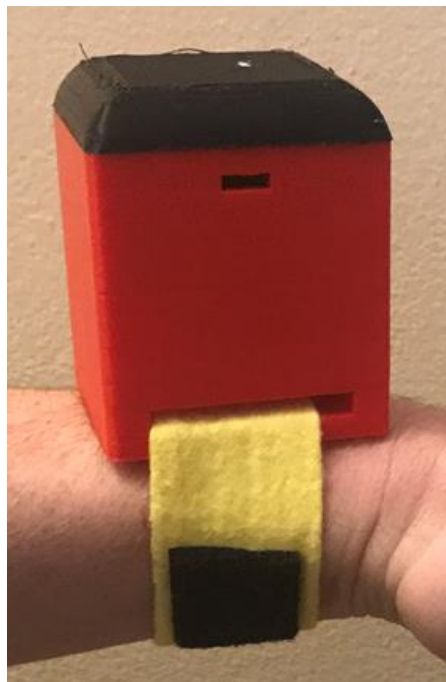


Figure 48: Final Wearable Device

Functional Specification Review

The device that was constructed is a functioning guitar plucker. It met the broad project goals and most of the functional specifications.

Operation

The specification for plucking mechanism operation was that the device must be able to pluck two guitar strings simultaneously. The device must also support strumming across the full set of strings and a subset of strings. Finally, the device must not displace a string more than 3.175mm parallel to the guitar body.

The final device can pluck as many strings as the number of wearable devices in use. The user can trigger a strum effect by quickly crossing each of the six plucking thresholds consecutively in one movement; this simulates a strum by plucking each string in quick succession. The final device can strum the full set of strings in either direction. During operation, strings do not interfere with each other or collide with the body of the guitar, and notes are played at a reasonable volume.

Frame

The specification for the device requires the frame to not interfere with the resonance of the guitar and to weigh less than 2 kilograms. The frame should also support guitars ranging in width from 12 inches to 17 inches, with box heights ranging from 17 inches to 21 inches, and depths between 3.5 and 5 inches. Finally, the frame should be able to be assembled by hand in under 10 minutes.

The frame allows the guitar to rest vertically or horizontally and weighs 2.04 kg; with the plucking device attached, the full device weighs 2.34 kg. It can be attached to a new guitar in

under 10 minutes and can be easily adjusted to a wide range of guitar geometries. When the guitar is played, it can be done so at a reasonable volume, meaning that the resonance of the instrument is not detrimentally affected.

Forces on Guitar String

The plucking mechanism was required to provide the maximum force to pluck the strings, which is 3.383 N for the low-E string. The motors used are powerful enough to supply this force to the string, resulting in successful plucking.

User Control Requirements

The user interface was designed to never need more than the use of two control sites simultaneously to operate the device, so that the device is not cognitively difficult to use. The notes are triggered solely by moving the interface devices mounted on the user's body.

Response Time

The specification for response time was that the latency between the signal trigger and the corresponding response was no longer than 10ms, which is the equivalent to listening to a guitar from 10 feet away. This is required so that the user feels in full control while playing the guitar. Furthermore, the device must be able to play at a rate of 32nd notes at 60 beats per minute, or 8 notes per second, which is a standard tempo of many songs.

The device experiences an average latency of 17.4ms, which is slightly above the target of 10 ms. This is still barely within the range of latency perceptible to most humans so it will not ultimately affect the playing experience. The device can pluck 6 notes per second if the motors

are rotating continuously based on both the communication latency and time needed to execute a plucking motion.

Setup and Calibration

The user interface was required to not require a technical background to use, and that the device should be setup within 10 minutes, and operable within 2 minutes of being turned on. The device can easily be attached to a guitar in less than ten minutes, and the microcontroller startup time once attached is less than a minute.

Manufacturability

The plucking mechanism was required to consist of at least 90% commercially available parts so that the device could be easily reproducible. The user interface was required to implement easily affordable and replaceable sensors. The whole device was required to be assembled using basic tools hand and power tools. The final plucking mechanism uses 86% commercially available parts (by part count). The custom components need to be 3D printed or laser cut. The assembly instructions (Appendix J) provide suggestions of sources for the custom parts, and the files necessary can be found on the public drive linked within that document.

Electronics

The electronics for the device were required to use batteries that were either easily obtainable or rechargeable. The circuitry had to support replacing components without knowledge of the total circuit and had to be packaged in a way to prevent accidental unplugging.

The device implements low cost rechargeable lithium ion batteries. The PCBs have labelled male and female headers so board components can be plugged in and held captive,

which prevents the accidental unplugging of board components and does not require the user to be familiar with the circuit.

Total Cost

The total device cost, including the plucking mechanism, frame, and user interface, must not exceed \$250. The estimated total cost for the final device is \$428, with a cost breakdown and Bill of Materials in Appendix P. The device is more expensive than desired, but some of the components could potentially be purchased at a lower price. The electronic components were the most expensive part of the device, with most of the mechanical components relatively cheap to acquire.

Conclusions and Recommendations

Conclusions

The final device has six plucking mechanisms, each positioned over one string of the guitar, and two user interface devices, which can be strapped to the user's hand, wrist, or any other control site. The user interface devices communicate wirelessly with the device on the guitar, allowing the user to pluck two strings simultaneously. The plucking devices can be adjusted to ensure that the plectrums are positioned directly above their respective strings, as well as over the soundhole of the guitar, which ensures the plucks sound natural.

However, the device has some limitations. The motors are programmed to run for a set time, rather than a set rotation distance, so calibrating the length of a pluck is difficult and subject to drift. Additionally, moving the plucking devices perpendicular to the strings is difficult, as each plucker is held in place by six screws, all of which must be loosened to adjust the mechanism; additionally, it is easy to misalign the components while adjusting them, resulting in additional strain on the frame elements and increased friction on the shafts.

Recommendations for Future Work

Fretting Device

This project did not develop a means of fretting the guitar; future project could develop an automatic fretting device and an adaptable user interface, which would greatly increase the number of songs the user can play, albeit with increased complexity for the user.

Actuation Method

One limitation of the current device is the use of continuous rotation servo motors. As these motors are activated with a rotation speed and duration, they must be calibrated for accurate rotation distances. Replacing the motors with position-control stepper motors would allow more precise, reliable control of motor position, allowing easier replacement of components and adaptation of the design.

Circuit Design

A limitation of the circuit is that the Arduino UNO cannot have code uploaded to it when the PCB is plugged in. This is because digital pins 0 and 1 are in use and are shared with the USB serial connection. In a future iteration, the servo motors could be connected to an I2C motor driver board which would free up 6 digital pins. An added benefit of a motor driver is that the power for the motors could be supplied independently from the power for the rest of the microcontroller. A separate solution would be using a microcontroller with more digital pins.

User Interface Modularity

One consideration the project sponsor wanted taken into account was modularity of the user interface such that the plucker mechanism could be controlled by a variety of methods for a variety of users. This resulting device does support some modularity; however, with some caveats. Any sensing system could replace the IMU as long as the device communicates over the nRF24L01+ radio to the guitar device. It is not possible to plug other sensors into the Arduino UNO on the guitar device without unsoldering pins from the PCB, and any sensors would have to be analog devices, as there are no remaining digital pins available.

Wearable Device Memory

The low memory available on the Arduino Pro Mini proved to be problematic as it limited the complexity of the code on the device. The Arduino Pro Mini comes with a ATmega328P microcontroller running at 8MHz. This board has 32 kB of programmable flash memory and 2,048 bytes of SRAM (static random-access memory). Flash memory stores the Arduino sketch and the SRAM stores dynamic variables used in the sketch. The program necessary to communicate read from the IMU, interpret the sensor readings into device orientation, determine if a pluck is detected, and communicate the pluck message to the guitar take up 27,260 bytes (88%) of the program space. The variables used to track the IMU's orientation and calibration information take up 1,706 bytes (83%) of the SRAM leaving only 342 bytes for local variables used throughout the program. As a result of these memory constraints the final version of the program on the wearable device had to be kept very lean, meaning all debug and testing methods have been placed in separate files. For future iterations of this project a recommendation would be to use a board with more memory than the ATmega328P to allow for more complicated processes.

IMU Accuracy

Another area for improvement would be upgrading to a higher precision IMU. Although a more expensive model would not necessarily be sufficient to facilitate position-based control, it would allow for better combination of motion and orientation based control. It is hard to confirm the accuracy of the IMU do to the difficulty of experimenting with acceleration, but the tolerancing for each of the axis was plus or minus 10% which is very significant.

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Appendices

Appendix A: Fretting Devices

A number of the mechanical guitar-playing devices also included a method for fretting the individual strings, although many of the methods used would be impractical to operate with motors. One such method was developed by the aforementioned Kidwell (1966), whose device (Figure 49) uses a series of oversized levers (104), attached to foot pedals (108), to engage the frets on specified strings and positions. Each lever is positioned such that when its pedal is depressed, a fretting pad is brought into contact with a single string on the neck of the guitar, holding it down and changing the effective length, which in turn changes the frequency the string vibrates at when plucked or strummed, producing a different note. In a motorized model, the levers could be operated by linear motors, and would be much smaller; however, the nature of the design limits the number of strings that could be fretted in a given position, making this design fairly limited in use.

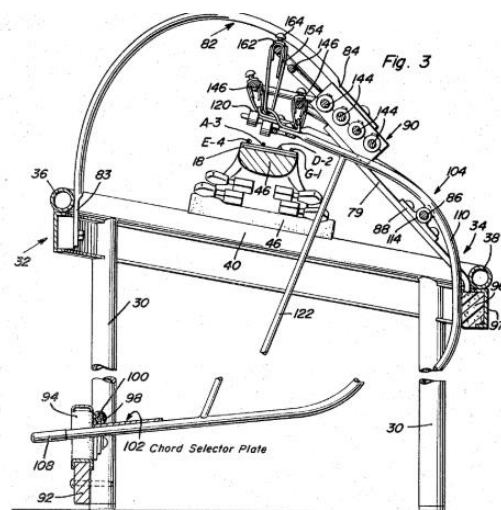


Figure 49: Lever-actuated system to fret guitar strings (Kidwell, 1966)

Another potential fretting device was designed by David Rand (1986), shown in Figure 50. While the previous device fretted single strings, this device is designed to fret specific key combinations of strings, each combination with a single input. While this reduces the number of possible combinations, it also reduces the number of inputs required, so the device is much simpler. This is achieved through a set of specially-designed bars (90-97), each of which fits around the others and has a single button (90.1), such that the user can finger a full chord with a single press, rather than needed to hold down each individual string. The bars are held in place on springs (30), such that releasing the bar is sufficient to release the fretting. In a motorized device, the bars could be engaged by a linear motor.

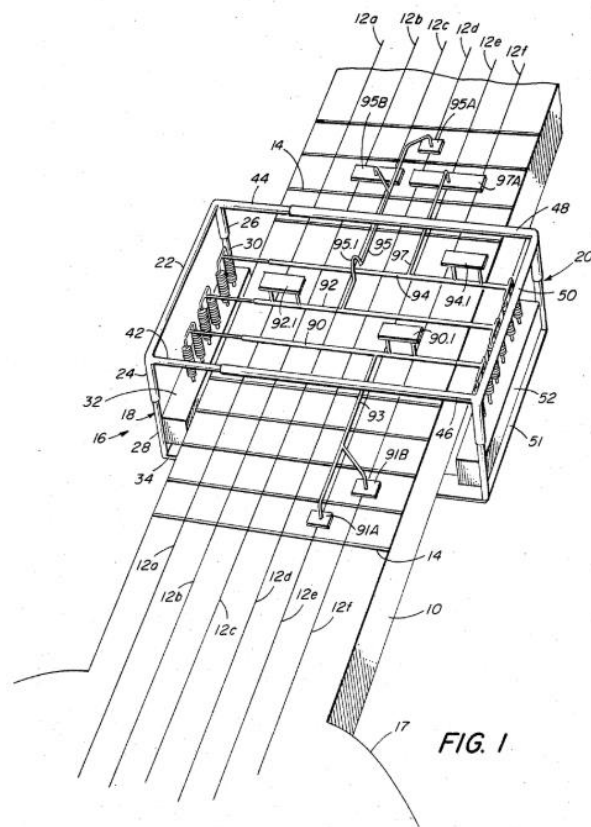


Figure 50: Chord-based guitar fretter (Rand, 1986)

A similar fretting device was commercialized as the ChordBuddy (ChordBuddy Guitar Learning System, 2018). The device, shown in Figure 51, has four color-coded buttons corresponding to the C, D, G, and E minor chords, some of the most common guitar chords. Each button is mounted to an irregularly-shaped plastic lever, such that when a button is pressed, the lever engages the appropriate strings of the assigned chord. This allows the user to fret chords with a single finger, and with a larger target area. It is marketed to the elderly, particularly those with arthritis, to prevent the pain that traditional fretting can cause; another target market is young children and others learning to play the guitar, as it simplifies the process of fretting, making it easier to learn other elements of the music. However, the ChordBuddy costs \$45 dollars, so a lower-cost alternative would be desired for use with a full assistive guitar.

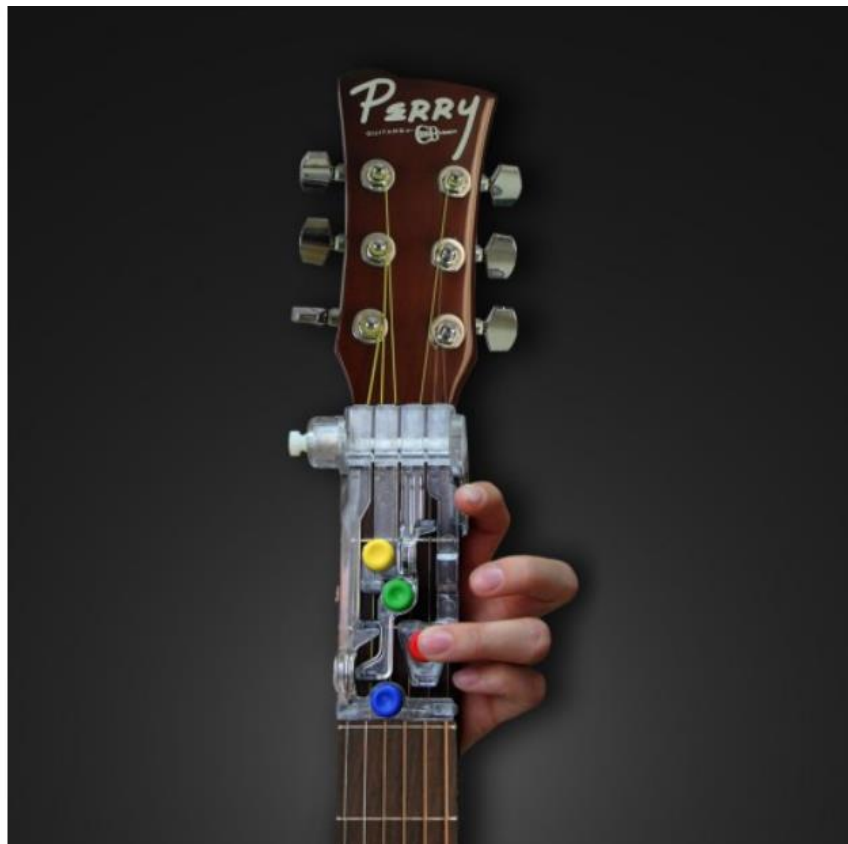


Figure 51: ChordBuddy Fretting System (Chordbuddy 2018)

Appendix B: Preliminary Plectrum Designs

LEGO Inspired System

Our design was inspired by Youtube user TECHNICALy Possible's Lego Guitar Robot (TECHNICally Possible, 2016). The device is designed to specifically strum the song "Little Talks" by Of Monsters And Men. The device is composed of both a plucker and fretter made out of the LEGO Mindstorms EV3 robotics kit shown in the following picture.



Figure 52: Lego Guitar Robot (TECHNICally Possible, 2016). Screenshot by author.

The plucking device features a revolving platform with a singular pick on a lever. As the platform rotates forward and back, a pedal (circled in red in the following image) can depress the lever to raise the pick away from the guitar strings. Depending on the placement of this pedal, the pick can be controlled to only play both up and down strokes, only the downstrokes, or to miss the strings completely for a pause in the song (TECHNICally Possible, 2016).

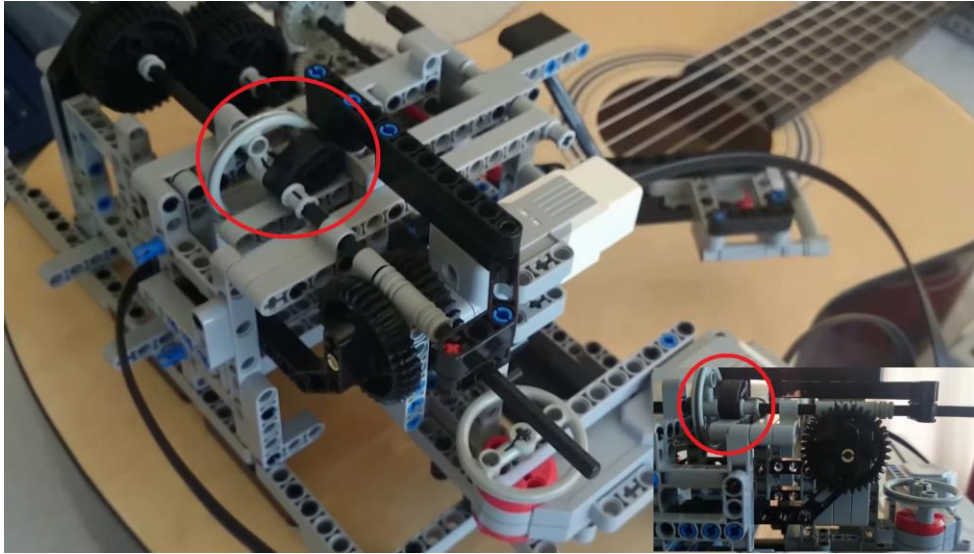


Figure 53: Lego Plucking Device (TECHNICally Possible, 2016). Screenshot by author.

This design inspired the following mechanism in Figure 54, which would have six plectrums on levers driven back and forth by one rotary motor. This rotary motor operates continuously with variable speed to rock the plectrums back and forth across their assigned strings.

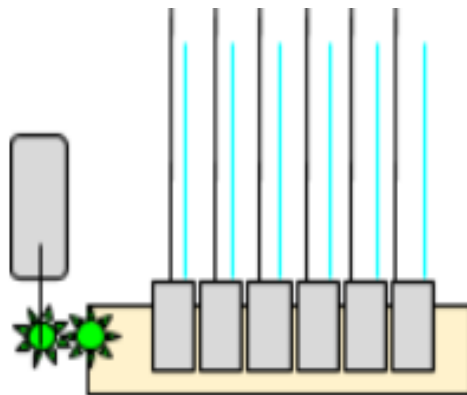


Figure 54: Rotating Base

For each plectrum, there is a servo motor with a pedal to depress the lever as shown in Figure 55.

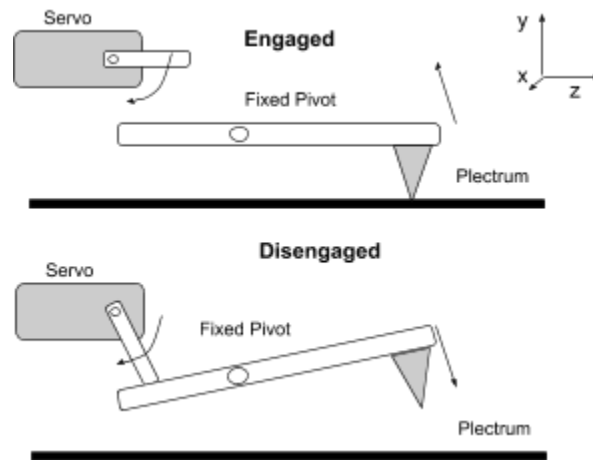


Figure 55: Lever Depression

This design requires seven actuators (one rotary, six linear) with bidirectional control. The necessary motor speed is dependent on the length of the levers; a longer lever results in less rotation needed to pluck the string, as well as a plucking motion that is straighter. With a 3mm pluck distance, a 1 cm lever would require 17 degrees per pluck; this gives a necessary motor speed of 136 deg/sec or 22.7 RPM. However, the actual speed requirement is significantly higher, as the device must reverse direction repeatedly. Longer levers result in lower speed requirement, but torque increases, increasing the load on the motor. For this design, most parts can be directly purchased; however, levers may need to be custom manufactured. An estimated cost of all parts is \$109.

Plectrum Wheels

In this design, each string is plucked a series of plectrums mounted radially to a rotating wheel. As the wheel turns, each plectrum strikes the string it turns, plucking it. This would allow for very fast plucking relative to motor speed. Allowable size of wheel depends on length of

pluck and extension of plectrum beyond the string; the initial assumption was a wheel with a total diameter of approximately 9mm. Two plectrums per wheel allows relatively high plucking speed without a need for incredible precision. Small plastic gears with 7mm total diameter (pitch diameter 6mm), could be fit to the wheel, with a 6mm or 12mm gear fit to the motor to drive. This would allow the motor to be vertically displaced from the strings, as the motor is likely to be wider than the plucking wheel.

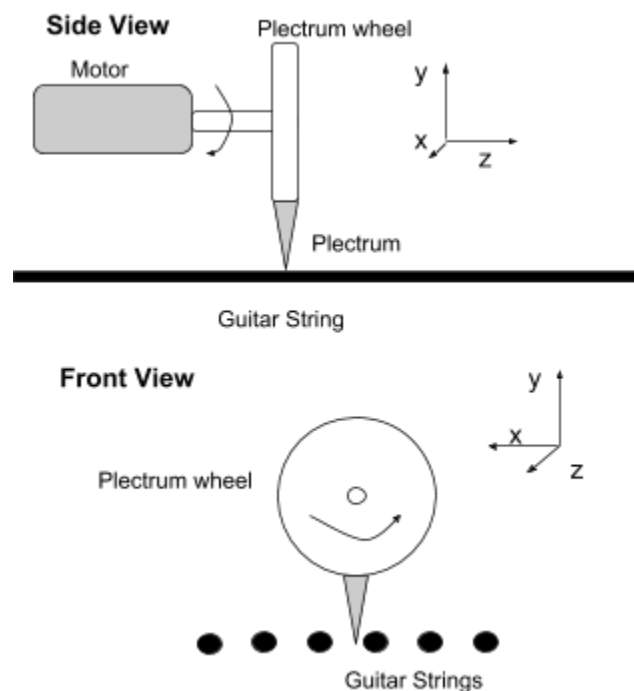


Figure 56: Plectrum Wheels

This design requires six actuators, one per wheel for each string. Other parts required include commercially-produced gears, and custom-made wheels. This design can be built by hand; however, the placement of the wheels needs to be within millimeter precision for both the horizontal and vertical placement to properly pluck a string. The estimated cost for this design is about \$100 for motors, gears, and raw materials.

Four-bar Crank-Rocker Linkage

In this design, a four-bar crank-rocker linkage is situated over each of the six strings of the guitar; the plectrum is attached to the coupler link. The plane of the linkage is perpendicular to the body of the guitar, as well as to the direction of the strings. Each rotation of the crank link results in a single pluck of the strings. The linkage system allows a more complex plucking motion than other designs, producing a more natural sound. However, the design has significant problems with its physical layout; the device must be positioned so that the links never collide with the body of the guitar; in particular, the crank pin must be elevated enough to allow the crank to rotate fully without striking the guitar; this means that the linkage requires a larger support structure. This design requires six actuators, one for each linkage; The links and frame could be laser-cut, with commercial motors. This device would cost roughly \$99 for motors and materials.

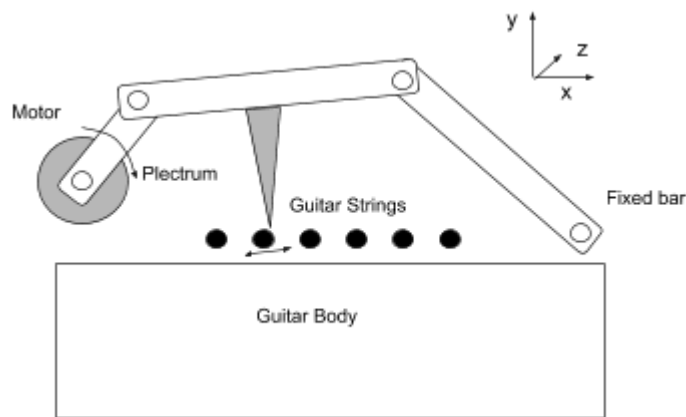


Figure 57: Four-bar Linkage

Four-bar Double-Rocker Linkage

In this design, a four-bar double-rocker mechanism would be used to pluck the strings of the guitar, with one linkage positioned over each string. The plectrum would be mounted on the coupler link of the linkage, as in the previous design. As the coupler follows a complex curve, its

motion path can be optimized to produce a natural plucking motion. The advantage of the double-rocker system is that only a portion of the coupler curve is swept through by the motion; this allows a more optimal coupler curve, as the linkage can be limited to only move through the portion of the cycle that includes the pluck. The device's primary limitation is the physical layout of the device; the links must be designed to have the desired coupler curve without colliding with the body of the guitar. With the limited rotation of the driving link, this is easier to resolve than in the crank-rocker design, but still a significant challenge. The design again would use planar, laser-cut parts, with an approximate total cost of \$99.

Four-bar Crank-Rocker Linkage

This design consists of a set of four-bar crank-rocker linkages, one for each string. The plane of the linkage is positioned parallel to the body of the guitar. Similarly to the other linkage designs, this device would have one linkage for each string to be plucked. Each slider block is positioned over its string with an attached plectrum, with the central point of the slider's range centered on the string's location. Therefore, the device will pluck the string once for every 180 degrees of rotation in the crank; while the plucking is bi-directional, the motor rotates in the same direction for every pluck. This design is limited by the necessary size of the components; assuming the crank pin is in line with the slider, the length of the crank must be half the desired plucking distance; while offsetting the crank allows for a longer link, the fundamental problem of link sizing remains. Additionally, the device requires sliding bearings or a similar mechanism to prevent friction in the slider joint, which results in a significant increase in costs. The design could use planar links, with commercially available slider bearings and motors, for an estimated cost of \$177.

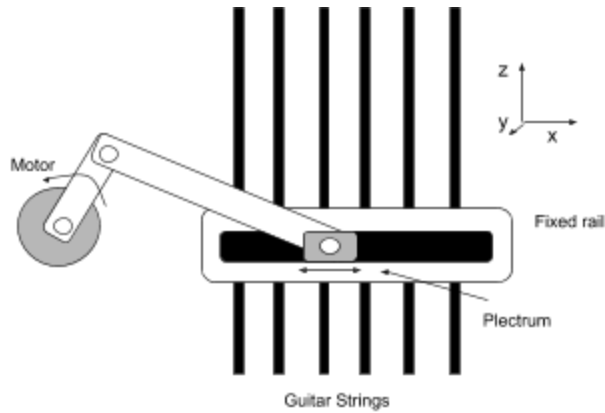


Figure 58: Four-bar Crank-Slider

Moving Plectrum

Each plectrum is on a small frame that travels perpendicular to the strings of the guitar; this device is driven by a rack-and-pinion gear set. This gearset is used to move the device to any string on the guitar, as well as driving the plectrum across strings to perform plucks and strums. A second rotary motor is on the moving frame and mounted to the plectrum; this motor rotates the plectrum out of engagement with the strings, allowing it to travel to the necessary position without plucking unwanted strings. Two such devices would allow any two strings to be simultaneously plucked. The primary disadvantage of this device is its speed; rather than simply initiating a pluck as the single-string plucking designs do, this device must disengage the plectrum, move to the appropriate string, return the plectrum to the plucking position, and only then move across the string to pluck. This means that the motors driving the device will need significantly greater speeds to achieve the same response time as single-string mechanisms. Additionally, the device needs slider rails to keep the plectrum mount moving in a straight line; this produces significant friction and requires additional slider bearings to reduce this friction and ensure the device operates at the necessary speeds. The device has an estimated cost of \$97.

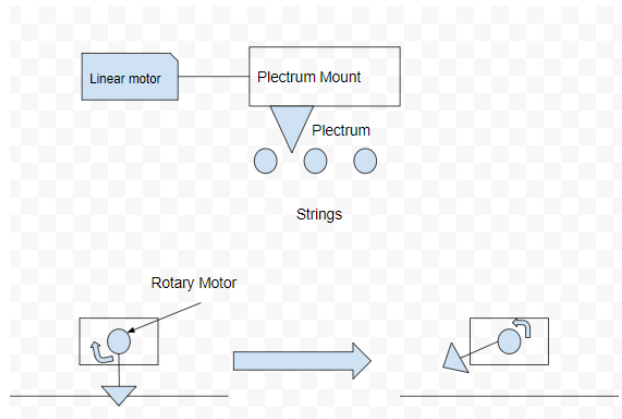


Figure 59: Moving Plectrum Plucker

Two Robotic Arms

A pair of three degree of freedom robot arms would be responsible for plucking the six strings. One arm would be located on each side of the strings and each arm would have a plectrum as an end effector. A strum would be performed by one arm travelling across all six strings or simultaneous plucking done by having each arm pluck single strings. The device would be able to pluck all six strings with two devices; however, the mechanism would still have six degrees of freedom and require six actuators. This design's main disadvantage is the speed required; the arm would need to be capable quickly moving to each of the individual strings as the notes change, requiring significant motion speed to achieve a reasonable response time. The cost of this device was estimated to be \$112.

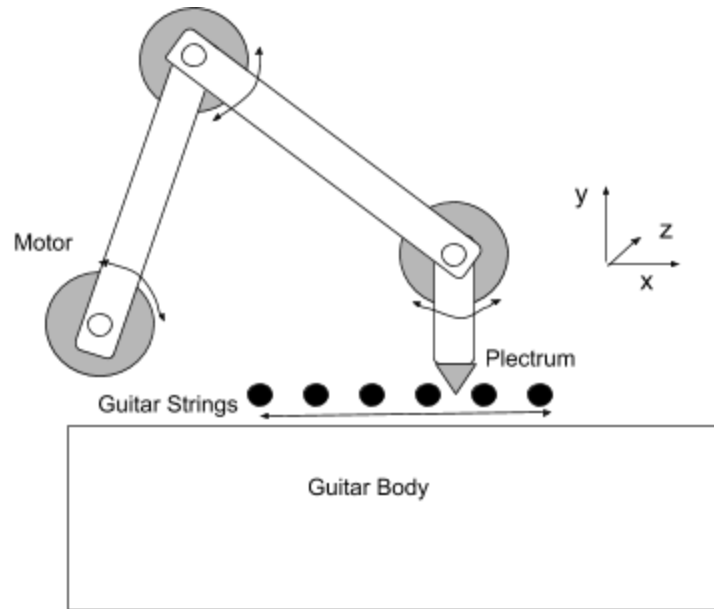


Figure 60: Single Robotic Arm Plucker

Harpichord Plectrum

Six plectrum devices from harpsichords are used; when triggered, a solenoid pushes a plectrum across the string. After the pluck is complete, a spring returns the plectrum to its initial position; The plectrum is mounted on a low-friction lever, or “tongue,” which allows the plectrum to slip around the string on the return stroke, rather than plucking a second time. Additionally, a damping pad is brought into contact with the string at the end of the stroke to quiet the vibrations still introduced by the plectrum. In this design, the plectrum jacks would be perpendicular to the strings, and parallel to the body of the guitar. The return mechanism of the jacks allows the design to be used with springed one-way solenoids, which are very low cost; the initial estimate for this device’s cost is \$80.

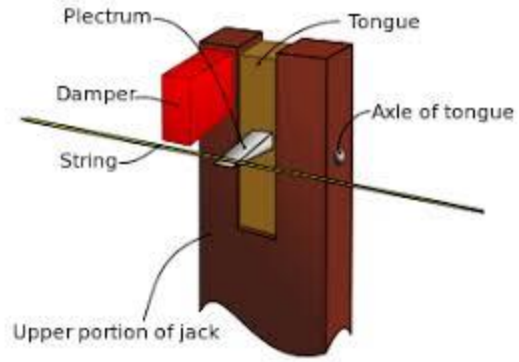


Figure 61: Harpsichord Jack with the plectra up against a string (Vladsinger, 2008)

Appendix C: Initial Criteria for Plucker Decision

In order to objectively evaluate the designs, a set of measurable criteria were developed, with the methodology for each criteria and the rating scale used summarized below.

1. **Degrees of Freedom:** Evaluating the number of degrees of freedom. With six strings, it should be possible to play the guitar with a mechanism having a maximum of six degrees of freedom; a system with fewer degrees of freedom will use fewer actuators and will have greater efficiency.
2. **Response Time:** The system must have a response time of less than 0.01 s (10 ms) in order for the sounds to seem instantaneous. The closer the plucker is to the string at rest, the shorter the delay between activation and pluck; this will be measured as the fraction of total pluck cycle distance the device must travel before starting its pluck. Assuming a constant motor speed and 8 plucks per second, 0.01 s response time is achieved if the device is at rest no more than 8% of a cycle from the string. Estimate 2 degree angle of free space/equivalent for linear motion
3. **Plucking Speed:** Related to response time, plucking speed is the average motor speed needed to repeatedly pluck the string, at a rate of 8 plucks/second (32nd notes at 60 bpm). This is a very rough estimate, as the device will probably not be running continuously, and it does not account for acceleration; however, it functions as a simple approximation of the motor characteristics required. A lower motor speed will reduce the noise from the mechanism and be easier to precisely control.
4. **Manufacturing Complexity (Acquiring parts):** This focuses on how difficult it will be for the client to acquire all the parts he or she needs in order to make the device; ideally, the device should be assembled entirely of off-the-shelf parts, but some parts

manufactured simply in a makerspace, such as 3d printed plastic parts, laser cut wood or acrylic, or other similar manufacturing methods, is preferable to custom-manufactured parts (such as milled metal or hand-carved wood).

5. **Manufacturing Complexity (Assembly of Device):** Primarily a measure of how difficult it will be for the client to assemble the device, measured by what tools would be needed for assembly.
6. **Manufacturing Complexity (Number of Parts):** How many individual parts are needed to assemble the device.
7. **Manufacturing Complexity (Precision of Assembly):** How precisely parts must be fitted together for the device to function. A device requiring great precision is more difficult to assemble, and also more vulnerable to parts becoming misaligned over time.
8. **Power Required:** Estimated total electric power needed to operate the device; this considers the power needed to run each motor as well as the maximum number of motors that could be running at one time. A device that uses less power will be easier to adapt to battery power, which makes the device more portable.
9. **Estimated Cost:** An estimated cost of the components of the device. The most expensive component for each device is the motors; other noticeable costs will be any laser-cut parts and any bearings needed. Small plastic gears are relatively inexpensive, as are link pins and guitar picks; the cost of an Arduino or similar chip is a factor, but should not affect the comparison of the designs, as each design should be able to run off the same chip.
10. **Motor Force/Torque Required:** The amount of torque or force, for rotary or linear motors respectively, that is needed to drive the device with the necessary acceleration for an appropriate response time. The assumption made here is that the device must reach

the needed plucking speed within the 0.01s time between trigger and pluck; from this acceleration, the resulting inertia forces can be calculated. Additionally, the device must be able to deliver at least 3.4 N in order to pluck the strings themselves.

11. **Device Mass:** The total mass of the plucking device; lower mass allows the device to be transported more easily.

Table 14: Plucker Decision Criteria

Criteria	Score: 1	Score: 2	Score: 3	Score: 4	Score: 5
Degrees of Freedom	8 DOF or more required	7 DOF required	6 DOF required	5 DOF required	4 DOF or less required
Response Time	Initial motion distance greater than 30% of total plucking distance	Initial motion distance between 30% and 20% of total plucking distance	Initial motion distance between 20% and 10% of total plucking distance	Initial motion distance between 10% and 5% of total plucking distance	Initial Motion less than 5% of total plucking distance.
Plucking Speed	Greater than 800 RPM or greater than 0.48 m/s	Speed between 600-800 RPM or between 0.36-0.48 m/s	Speed between 400-600 RPM or between 0.24-0.36 m/s	Speed between 200-400 RPM or between 0.12-0.24 m/s	Required Motor Speed of 200 RPM/0.12 m/s or less
Manufacturing Complexity (Acquiring parts)	More than 5 parts must be custom made by an outside vendor	At least 1 part must be custom made by an outside vendor	Some of the parts are available off-the-shelf (nuts, bolts, motors) but most of the device must be custom made in a makerspace	Most items are commercially available off-the-shelf and the remaining parts can be custom made by the client in a makerspace	All parts of the device are commercially available off-the-shelf
Manufacturing Complexity (Assembly of Device) (1/3 weighting)	Specialized tools needed		Power tools needed		Basic hand tools only
Complexity (Number of	More than 50 components	40-50 components	30-40 components	20-30 components	Fewer than 20 components

Parts) ($\frac{1}{3}$ weighting)					
Complexity of Assembly (Precision Required) ($\frac{1}{3}$ weighting)	more precise than 0.1 mm	0.1-1 mm precision needed	1-10 mm precision needed	10mm-1cm precision needed	less precise than 1 cm
Voltage Required	More than 12 volts		9-12 volts		0-9 volts or less needed
Estimated Cost of Final Design	More than \$175	\$150-175	\$125-150	\$100-125	Less than \$100
Motor Force/Torque Required	Greater than 0.1 Nm Torque, or Greater than 6.5 N linear Force	0.075-0.1 Nm Torque, or 5.5-6.5 N linear Force	0.05-0.075 Nm Torque, or 4.5-5.5 N linear force	0.025-0.05 Nm Torque, or 3.5-4.5 N linear Force	Less than 0.025 Nm of torque required or less than 3.5 N of linear force required
Device Mass	Greater than 4 kilograms	3-4 kilograms grams	2-3 kilograms grams	1-2 kilograms	Less than 1 kg

Appendix D: Refined Plucker Criteria

To decide on a final design, further evaluation was performed on the two designs. The evaluation criteria were considered, and the rating scales were revised to effectively compare the two designs. For some of the criteria, the values have not changed from the initial decision matrix, so the scale was not adjusted. The key criteria evaluated were the difficulty of acquiring components, the tools needed for assembly, the number of components, the total cost, and the mass of the device. The updated rating scales for these criteria are summarized in Table 15.

Table 15: Final Plucking Device Criteria

Criteria	Score: 1	Score: 2	Score: 3	Score: 4	Score: 5
Complexity (Part Acquisition)	Significant number of parts must be custom-made	Requires a small number of custom-made parts	Most components require a makerspace	Most parts are available 'off the shelf', some require manufacturing in a makerspace	All parts are available 'off the shelf'
Complexity (Tools Needed)	Multiple specialized tools are needed and/or multiple components must be modified by the person assembling the device	One specialized tool is needed or one component must be modified by the person assembling the device	Three or more hand tools are needed	Two different hand tools are needed	One or no tools are needed
Complexity (Number of Parts)	Greater than 200 components	150-200 components	100-150 components	50-100 components	50 or fewer components
Estimated Cost	Above \$150	\$125-150	\$100-125	\$75-100	Below \$75
Device Mass	Above 400 g	300-400 g	200-300 g	100-200 g	Below 100 g

Appendix E: Preliminary User Interface Designs

Camera

This design uses a camera to track brightly colored patches placed on the user on two similar control sites, most likely both hands or both feet. As the location of colored squares move across the camera's field of view the guitar strings would be plucked. To create a strumming effect the user would need to quickly move one of the control sites over all six of the "strings" (indicated by lines of the white backdrop). This would involve setting up a white backdrop with indicators to reduce visual noise in the camera's input. Due to the limitations of the camera there could be issues in some lighting situations and the camera would need to be calibrated each time the device is set up to correctly identify the colored squares. This would also require the user to wear colored patches which although unlikely could be an issue for some users. Each of the strings are 12 cm apart, multiplied by the six strings give 72 cm wide required range of motion in the X axis (as labeled in the figure). The speed at which the guitar could be played would be dependent on the user's speed moving across this 72 cm space. The user would also need to be able to keep the colored squares relatively level in the camera's field of view which could be tiring over several minutes of playing. The cost for the camera is \$31.50. The computation necessary to process the input from the camera is complicated which could slow down response time slightly.

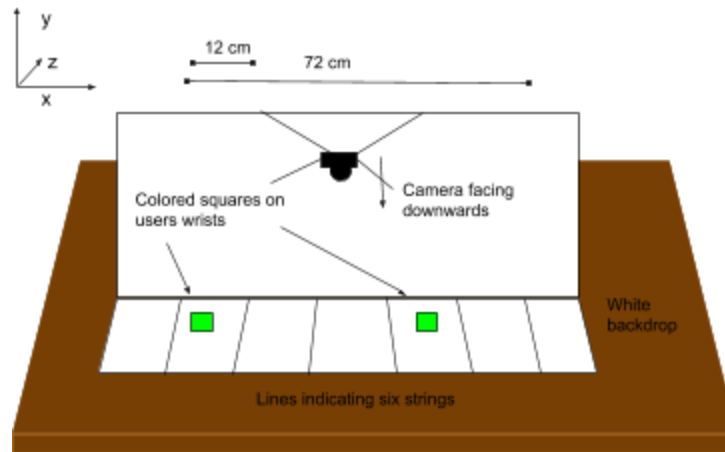


Figure 62: Camera UI Setup

Inertial Measurement Unit

This design would utilize a pair of Inertial Measurement Units (IMUs) to track the position of two control sites on the user; notably these control sites can be dissimilar and calibrated separately. The calibration would involve moving the IMU to three points which would be set as the center, high E and low E string locations. The other strings would be filled in based on these measurements. As the location of IMUs move across the calibrated field of strings the guitar strings would be plucked. To create a strumming effect, the user would need to quickly move one of the control sites over all six of the “strings”. To help the user play correct notes, tape could be used to indicate how the system had been calibrated. The range of motion for this device is very flexible, since it is entirely determined through calibration. The range of possible distances is from 12 cm to 240 cm (oriented on any axis). This could have therapeutic value as well as practical value for making the device easier for individuals to play. The IMU would need to be attached to the user with Elastic or Velcro. Any control site that could provide the required range of motion and is able to have an IMU attached would be considered viable for this approach. Attaching and calibrating the device are the only steps of set up making this device

fairly low profile and flexible. The total cost for two IMUs is \$29.90. The computational complexity for this design is fairly high as it would involve taking the double integral of the acceleration value to give position and using a Kalman filter to reduce accumulated drift in the value.

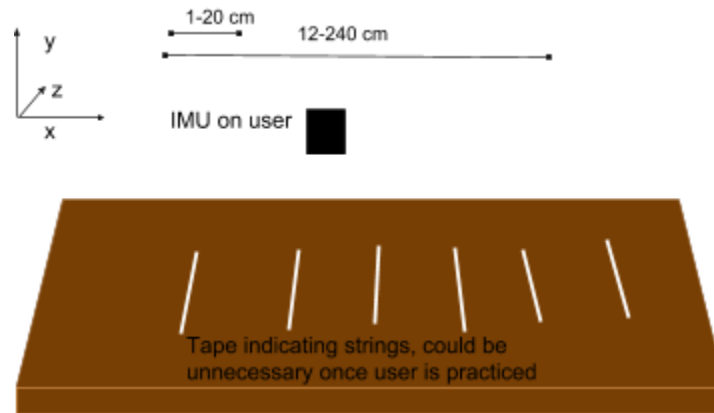


Figure 63: IMU UI Setup

Six-Sensor Approach

The “six-sensor approach” to this design would involve using one sensor for each string arrayed in fixed positions on a platform. There are several viable options for which sensors could be used in this system including; IR range sensor, a PIR motion detection sensor, and a ZX gesture sensor. These are considered separately in the decision matrix but together here since the design is similar. As the sensor is activated the corresponding string on the guitar will be plucked. The user could achieve strumming by moving the control site across the whole sensor platform (over all six sensors). The distance between each sensor is 12 cm and the total width of the device is 72 cm, meaning this would require 72 cm range of motion in the X direction. This platform could be propped up on the Y axis to switch the axis of the range of motion required from the user. This device works with any number of control sites but is ideal with two similar

locations such as both hands, both elbows, or both feet. The setup is very minimal since there is no calibration and the array of sensors is already fixed on a platform. The cost depends on the sensor used but is around \$83. Since this approach requires six sensors it can be more expensive. The simplicity of the design would make the computation fairly minimal.

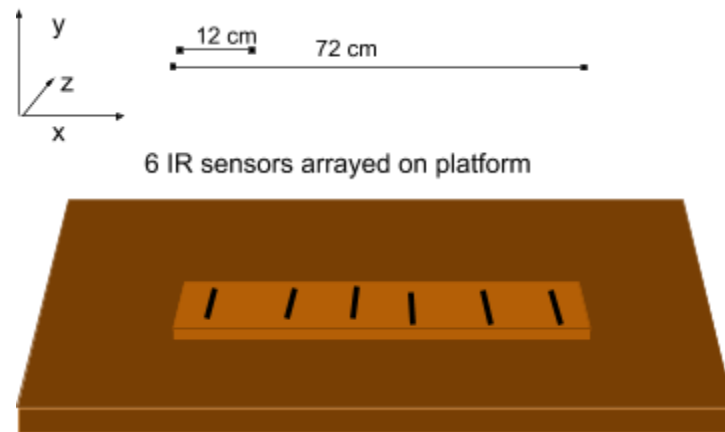


Figure 64: Six Sensor Array UI Setup

Digital Sensor Approach

This design is very similar to the six-sensor approach but opts to use digital, tactile sensors. The sensors the team is considering for this design are 100mm arcade buttons, rocker switch, and toggle switch. These are considered separately in the decision matrix but together here since input selection does not affect the overall design much. The six inputs would each correspond to one of the strings and would activate the corresponding string when activated. The range of motion required of the user is 72 cm in the X axis and +/- 5 cm in the Y axis to toggle the inputs. This design would require the user to exert small force. Due to the range of motion required to flip a switch or press a button this design is mostly conducive to being used by hands or potentially feet but would be difficult to use with any other control site. Computationally this would be the simplest of the designs.

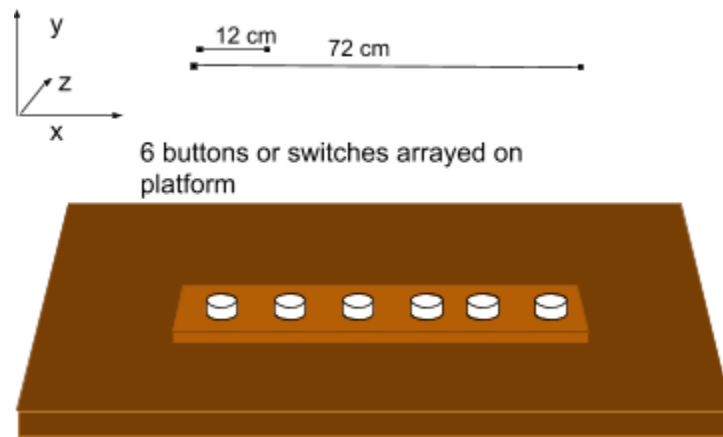


Figure 65: Digital Sensor Array Setup

Spectroscopy

This design would implement a spectral sensor capable of detecting different colors. The user would hold up cards of different colors to the two sensors and based on the colors shown a string on the guitar would be plucked. This design would require the user to be able to identify and pick up the correct card and then move the card in front of the sensor. This would require varying amounts of motion on the X-axis and 15 cm of motion on the Y axis since the sensors would be supported on stilts. Since this sensor uses light the lighting conditions in the room this is used in could affect the results. This design has an issue regarding the speed at which the notes could be played. Since our requirement is 8 notes per second it would be very difficult to pick up and display that many cards even for a person without limitations.

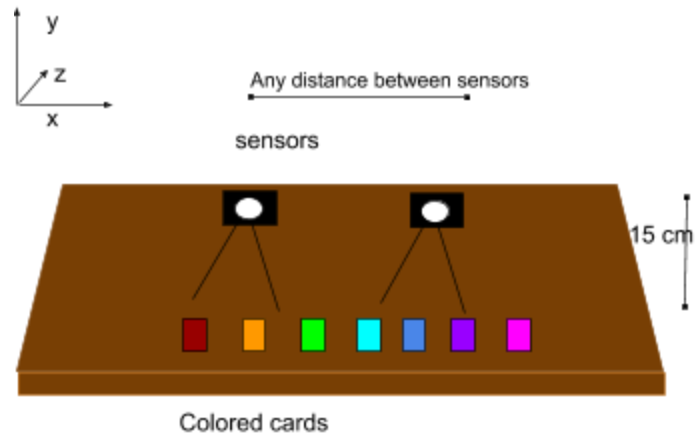


Figure 65: Spectropic Sensor UI Setup

Appendix F: Initial Criteria for User Interface Decision

The criteria used to evaluate these initial designs were:

1. **Power Requirements:** power requirements needed for user interface, as compared to Arduino’s power supply
2. **Direction of motion requirement:** types of motions on different axis required to operate device
3. **Range of motion requirement:** range of motion required from user measured in cm in x, y, and z axis
4. **Control sites supported:** number of control sites the design would viably work on
5. **Viability for different ranges of motion:** can the design be adapted to different motion ranges
6. **Time for calibration:** how long does it take for a sensor to become operable
7. **Steps needed to calibrate:** what tasks must be done for a sensor to become operable
8. **Setup time:** estimated time to physically set up user interface
9. **Estimated Computational complexity:** what is the delay between sensor reading and calculated output for the guitar
10. **Cost:** total cost of sensors and additional hardware
11. **Input detail:** input resolution from binary to 10 bit
12. **User Difficulty:** measurement of how long it takes a user from triggering one note to triggering another note

These criteria were then made into a rubric and evaluated on a scale of 1 - 5, with 1 being the worst, and 5 being the best. The rubric is presented in Table 16.

Table 16: User Interface Decision Criteria

Criteria	Score: 1	Score: 2	Score: 3	Score: 4	Score: 5
Power Requirements	Draws more than 150mA on 3V or 1A on 5V pins		Requires more than Arduino 5V pin		Fits Arduino power requirements
Direction of	Rotational	Rotational	Linear	Linear	Linear

motion requirement	motion 3 axes	Motion 2 axes	Motion 3 axes / Rotational Motion 1 axis	motion 2 axes	motion 1 axis
Range of motion requirement	Motion greater than 1 meter/ less than 5 cm				Motion within 5 cm to 1 m
Control sites supported	Can only be controlled by specific part of the body		Can be controlled by several parts of the body		Can be controlled by any moving part of the body
Viable for different ranges of motion	Motion requirement cannot be adjusted		Motion requirement can be switched between settings		Motion requirement can be determined by user
Time for calibration	> 2 minutes	1 - 2 minutes	30 seconds - 1 minute	< 30 seconds	No calibration required
Steps for calibration	Requires additional tools		More than 1 step		1 step
Setup time	> 10 minutes		5 - 10 minutes		< 5 minutes
Estimated Computational Complexity	Requires additional board / Delay of 1 ms	Delay of 1- .5 ms	Delay of .1 ms	Delay of .1 ms - .1 μ s	Delay of < .1 μ s
Cost	> \$100	\$75 - \$100	\$50 - \$75	\$25 - \$50	< \$25
Input Detail	Binary	2 bit resolution	4 bit resolution	8 bit resolution	10 bit resolution
User Difficulty	> 1 second	1 - 1/2 second	1/2 - 1/4 second	1/4 - 1/8 second	< 1/8 second

Appendix G: Refined User Interface Criteria

To choose a final design, these additional criteria that were not previously evaluated will also be used. Table 10 has these additional criteria, and the criteria that were re-evaluated from the previous decision matrix.

1. **Final Cost:** A better estimate on what the design will cost
2. **Manufacturing of custom parts method:** What technologies are required to build the user interface
3. **Repairability:** What steps are needed to repair the interface should a component break
4. **How fast does error accumulate:** time in which error will have noticeable change in user experience. This metric determines how often calibration must occur.
5. **Need for code editing when parts are replaced:** what kind of changes to the code must occur when components are switched out. Certain electronic components may give a different reading between units. The end user should have to change the code as little as possible after they replace something in the physical interface.

Table 17: Additional Decision Criteria

Criteria	Score: 1	Score: 2	Score: 3	Score: 4	Score: 5
Final Cost	Above \$75	\$56-\$74	\$41-\$55	\$26 - \$40	Under \$25
User Difficulty	Majority of individuals in user group can not play song at real time		Minority of individuals in user group cannot play song at real time		All individuals in user group can play song at real time
Effect on user body	Multiple conditions in user group experience pain or deterioration of body		Single condition in user group experience pain or deterioration of body		No individuals in user group are affected
Manufacturing of custom parts method		Less accessible technologies like laser cutting, CNC		More accessible technologies like 3D printing	No manufacturing of custom parts
Repairability	Unsoldering				Unplugging
Error accumulation rate	Faster than 30 seconds	30 seconds - 1 minute	1 minute - 2 minutes	2 minutes - 3 minutes	Slower than 3 minutes or no error
Need for code editing when parts are replaced	Editing of code functionality		Editing of defined constants		No editing required

Appendix H: Wearable Device Code

```

1  /* MQP IMU interface
2  by: Benjamin Shaffer
3  date: April 17, 2019
4
5  Reads IMU and process reading to give orientation information
6  Sends pluck signals to guitar device based on orientation of device
7
8  Hardware setup:
9  MPU9250 Breakout ----- Arduino
10 VDD ----- 3.3V
11 VDDI ----- 3.3V
12 SDA ----- A4
13 SCL ----- A5
14 GND ----- GND
15 */
16
17 //----- IMU Definitions -----//
18 #include "quaternionFilters.h"
19 #include "MPU9250.h"
20
21 #define MPU9250_ADDRESS MPU9250_ADDRESS_ADO
22
23 // Set to true to get Serial output for debugging
24 #define SerialDebug true
25
26 // sets which Euler angle is used to control guitar
27 #define selectAxis myIMU.pitch
28
29 //----- Network Definitions -----//
30 #include <RF24Network.h>
31 #include <RF24.h>
32 #include <SPI.h>
33
34 //SPI pins
35 #define CE 7
36 #define CSN 8
37
38 //calibration messages to receive
39 #define CALIBRATE_MESSAGE 1
40 #define MIDDLE_MESSAGE 2
41 #define VERTICAL_MESSAGE 3
42
43 //string to pluck messages to send
44 #define STRING_E_LOW 1
45 #define STRING_A 2
46 #define STRING_D 3
47 #define STRING_G 4
48 #define STRING_B 5
49 #define STRING_E_HIGH 6
50
51 #define PLUCK_FINISHED 99
52
53 //calibration messages to send
54 #define CALIBRATE_MODE 7
55 #define MIDDLE_COMPLETE 8
56 #define VERTICAL_COMPLETE 9
57 #define ERROR_MSG 10
58
59 //radio set up
60 RF24 radio(CE, CSN);
61 RF24Network network(radio);
62 const uint16_t imu01_node = 01; //this node
63 const uint16_t guitar_node = 00; //master node
64
65 //----- Global variables -----//
66
67 // Pin Definitions
68 int intPin = 12; // These can be changed, 2 and 3 are the Arduinos ext int pins
69 int myLed = 13; // Set up pin 13 led for toggling
70
71 // Initialize IMU
72 MPU9250 myIMU;
73
74 // variables used for calibration, consts are not changes
75 float stringAngle = 15;
76 float float activatedAngle = 15;
77 float originStringAngle = 0;
78 const float originActivatedAngle = 0;
79
80 // variable that tracks the current 'string number' of the IMU
81 int stringStatus = 0;
82
83 //----- Setup Procedure -----//
84 // runs once on startup, connects to IMU.
85 void setup() {
86     Wire.begin();
87     // TWBR = 12; // 400 kbit/sec I2C speed
88     Serial.begin(38400);
89
90     // Set up the interrupt pin, its set as active high, push-pull
91     pinMode(intPin, INPUT);
92     digitalWrite(intPin, LOW);
93     pinMode(myLed, OUTPUT);
94     digitalWrite(myLed, HIGH);
95
96     initializeIMU();
97
98     setupComms();
99
100 //----- Main Loop -----//
101 // runs continuously, reads IMU,
102 // Calculated Quaternions,
103 // Sends appropriate pluck.
104
105 void loop() {
106     //check network for new message
107     network.update();
108     int message = checkForMessage();
109     // if calibration message is received proceed to calibration
110     if (message == CALIBRATE_MESSAGE) {
111         calibrationReceive(message);
112     }
113
114     // If intPin goes high, all data registers have new data
115     // On interrupt, check if data ready interrupt
116     if (myIMU.readByte(MPU9250_ADDRESS, INT_STATUS) & 0x01) {
117         readIMU(); //gets values for each 9 DOF
118     }
119
120     // update the quaternions that store the IMU orientation
121     updateQuaternion();
122
123     // update LCD once per half-second independent of read rate
124     if (myIMU.delt_t > 500)
125     {
126         //convert the stored quaternions into Euler angles
127         updateEulerAngles();
128
129         //debug functions
130         //printSensorValues();
131         //printEulerAngles();
132
133         // get the pluck value (if any)
134         int pluck = checkPluck(stringStatus);
135         // send pluck to guitar
136         sendPluck(pluck);
137
138     }

```



```

139 //print pluck for debug
140 //printpluck(pluck);
141 //Serial.println();
142
143 // update IMU variables used for math
144 myIMU.count = millis();
145 myIMU.sumCount = 0;
146 myIMU.sum = 0;
147 }
148 }
149
150 void initializeIMU() {
151 // Read the WHO_AM_I register, this is a good test of communication
152 byte c = myIMU.readByte(MPU9250_ADDRESS, WHO_AM_I_MPU9250);
153 Serial.print("MPU9250 "); Serial.print("I AM "); Serial.print(c, HEX);
154 Serial.print(" I should be "); Serial.println(0x71, HEX);
155
156 if (c == 0x71) // WHO_AM_I should always be 0x68
157 {
158   Serial.println("MPU9250 is online...");
159
160 // Start by performing self test and reporting values
161 myIMU.MPU9250SelfTest(myIMU.selfTest);
162 Serial.print("x-axis self test: acceleration trim within : ");
163 Serial.print(myIMU.selfTest[0], 1); Serial.println("% of factory value");
164 Serial.print("y-axis self test: acceleration trim within : ");
165 Serial.print(myIMU.selfTest[1], 1); Serial.println("% of factory value");
166 Serial.print("z-axis self test: acceleration trim within : ");
167 Serial.print(myIMU.selfTest[2], 1); Serial.println("% of factory value");
168 Serial.print("x-axis self test: gyration trim within : ");
169 Serial.print(myIMU.selfTest[3], 1); Serial.println("% of factory value");
170 Serial.print("y-axis self test: gyration trim within : ");
171 Serial.print(myIMU.selfTest[4], 1); Serial.println("% of factory value");
172 Serial.print("z-axis self test: gyration trim within : ");
173 Serial.print(myIMU.selfTest[5], 1); Serial.println("% of factory value");
174
175 // Calibrate gyro and accelerometers, load biases in bias registers
176 myIMU.calibrateMPU9250(myIMU.gyroBias, myIMU.accelBias);
177
178 myIMU.initMPU9250();
179 // Initialize device for active mode read of accelerometer, gyroscope, and
180 // temperature
181 Serial.println("MPU9250 initialized for active data mode....");
182
183 // Read the WHO_AM_I register of the magnetometer, this is a good test of
184 // communication
185 byte d = myIMU.readByte(AK8963_ADDRESS, WHO_AM_I_AK8963);
186 Serial.print("AK8963 "); Serial.print("I AM "); Serial.print(d, HEX);
187 Serial.print(" I should be "); Serial.println(0x48, HEX);
188
189 // Get magnetometer calibration from AK8963 ROM
190 myIMU.initAK8963(myIMU.factoryMagCalibration);
191 // Initialize device for active mode read of magnetometer
192 Serial.println("AK8963 initialized for active data mode....");
193 if (SerialDebug)
194 {
195   // Serial.println("Calibration values: ");
196   Serial.print("X-Axis sensitivity adjustment value ");
197   Serial.println(myIMU.factoryMagCalibration[0], 2);
198   Serial.print("Y-Axis sensitivity adjustment value ");
199   Serial.println(myIMU.factoryMagCalibration[1], 2);
200   Serial.print("Z-Axis sensitivity adjustment value ");
201   Serial.println(myIMU.factoryMagCalibration[2], 2);
202 }
203 // if (c == 0x71)
204 else
205 {
206   Serial.print("Could not connect to MPU9250: 0x");
207   Serial.println(c, HEX);

```

```

270 void sendMessage(int message) {
271   RF24NetworkHeader header(guitar_node);
272   network.write(header, &message, sizeof(message));
273 }
274
275 //this function is
276 int checkForMessage() {
277   int incomingData = 0;
278   while (network.available()) {
279     RF24NetworkHeader header;
280     network.read(header, &incomingData, sizeof(incomingData));
281   }
282   return incomingData;
283 }
284
285 //this should be "blocking code" i.e. not sending guitar plucks
286 void calibrationReceive(int message) {
287   //get set up for calibration
288   Serial.println("calibrate mode");
289   //delay(2000);
290   sendMessage(CALIBRATE_MODE); //send that ready to calibrate
291
292   while (message != MIDDLE_MESSAGE) {
293     network.update();
294     message = checkForMessage();
295   }
296
297   if (message == MIDDLE_MESSAGE) {
298     //save the middle position
299     Serial.println("middle");
300     long selectSum = 0, activateSum = 0;
301     float startTime = millis();
302     int readingCount = 0;
303     while (millis() - startTime < 2000) {
304       if (myIMU.readByte(MPU9250_ADDRESS, INT_STATUS) & 0x01)
305         { readIMU(); //gets values for each 9 DOF
306           }
307     }
308     updateQuaternion();
309     updateEulerAngles();
310     selectSum = selectSum + selectAxis;
311     readingCount++;
312   } //while loop
313   originStringAngle = selectSum / readingCount;
314   Serial.println("origin calibration complete: ");
315   Serial.println(originStringAngle);
316   //completed
317   sendMessage(MIDDLE_COMPLETE);
318 }
319
320 while (message != VERTICAL_MESSAGE) {
321   network.update();
322   message = checkForMessage();
323 }
324
325 if (message == VERTICAL_MESSAGE) {
326   //save the activation position
327   Serial.println("vertical");
328   float startTime = millis();
329   int readingCount = 0;
330   long selectSum = 0;
331   while (millis() - startTime < 2000) {
332     if (myIMU.readByte(MPU9250_ADDRESS, INT_STATUS) & 0x01)
333       { readIMU(); //gets values for each 9 DOF
334         }
335     updateQuaternion();
336     updateEulerAngles();
337     selectSum = selectSum + selectAxis;
338   }
339 }
340
341 // Define output variables from updated quaternion---these are Tait-Bryan
342 // angles, commonly used in aircraft orientation. In this coordinate system,
343 // the positive z-axis is down toward Earth. Yaw is the angle between sensor
344 // x-axis and Earth magnetic North (or true North if corrected for local
345 // declination, looking down on the sensor positive yaw is counterclockwise.
346 // Pitch is angle between sensor x-axis and Earth ground plane, toward the
347 // Earth is positive, up toward the sky is negative. Roll is angle between
348 // sensor y-axis and Earth ground plane, y-axis up is positive roll. These
349 // arise from the definition of the homogeneous rotation matrix constructed
350 // from quaternions. Tait-Bryan angles as well as Euler angles are
351 // non-commutative; that is, the get the correct orientation the rotations
352 // must be applied in the correct order which for this configuration is yaw,
353 // pitch, and then roll.
354 // for more see
355 // http://en.wikipedia.org/wiki/Conversion_between_quaternions_and_Euler_angles
356 // which has additional links.
357 myIMU.yaw = atan2(2.0f * (*getQ() + 1) * (*getQ() + 2) + *getQ() *
358                 * (*getQ() + 3), *getQ() * *getQ() + * (*getQ() + 1) *
359                 * (*getQ() + 3));
360
361 // Calculate the gyro value into actual degrees per second
362 // This depends on scale being set
363 myIMU.gx = (float)myIMU.gyroCount[0] * myIMU.gRes;
364 myIMU.gy = (float)myIMU.gyroCount[1] * myIMU.gRes;
365 myIMU.gz = (float)myIMU.gyroCount[2] * myIMU.gRes;
366
367 // User environmental x-axis correction in milliGauss, should be
368 // automatically calculated
369 myIMU.magBias[0] = +470.;
370 // User environmental x-axis correction in milliGauss TODO axis??
371 myIMU.magBias[1] = +120.;
372 // User environmental x-axis correction in milliGauss
373 myIMU.magBias[2] = +125.;
374
375 // Calculate the magnetometer values in milliGauss
376 // Include factory calibration per data sheet and user environmental
377 // corrections
378 // Get actual magnetometer value, this depends on scale being set
379 myIMU.mx = (float)myIMU.magCount[0] * myIMU.mRes * myIMU.factoryMagCalibration[0] -
380           myIMU.magBias[0];
381 myIMU.my = (float)myIMU.magCount[1] * myIMU.mRes * myIMU.factoryMagCalibration[1] -
382           myIMU.magBias[1];
383 myIMU.mz = (float)myIMU.magCount[2] * myIMU.mRes * myIMU.factoryMagCalibration[2] -
384           myIMU.magBias[2];
385
386 void updateEulerAngles() {
387   // Define output variables from updated quaternion---these are Tait-Bryan
388   // angles, commonly used in aircraft orientation. In this coordinate system,
389   // the positive z-axis is down toward Earth. Yaw is the angle between sensor
390   // x-axis and Earth magnetic North (or true North if corrected for local
391   // declination, looking down on the sensor positive yaw is counterclockwise.
392   // Pitch is angle between sensor x-axis and Earth ground plane, toward the
393   // Earth is positive, up toward the sky is negative. Roll is angle between
394   // sensor y-axis and Earth ground plane, y-axis up is positive roll. These
395   // arise from the definition of the homogeneous rotation matrix constructed
396   // from quaternions. Tait-Bryan angles as well as Euler angles are
397   // non-commutative; that is, the get the correct orientation the rotations
398   // must be applied in the correct order which for this configuration is yaw,
399   // pitch, and then roll.
400   // for more see
401   // http://en.wikipedia.org/wiki/Conversion_between_quaternions_and_Euler_angles
402   // which has additional links.
403   myIMU.yaw = atan2(2.0f * (*getQ() + 1) * (*getQ() + 2) + *getQ() *
404                   * (*getQ() + 3), *getQ() * *getQ() + * (*getQ() + 1) *
405                   * (*getQ() + 3));
406 }

```

```

408         *(getQ() + 1)
409         - * (getQ() + 2) * *(getQ() + 2) - * (getQ() + 3) * *(getQ() + 3) //476
410         * (getQ() + 1) * *(getQ() + 3) - *getQ() *
411         *(getQ() + 2)); //477
412         *(getQ() + 1) * *(getQ() + 1) + * (getQ() + 2) *
413         *(getQ() + 3), *getQ() * *getQ() - * (getQ() + 1) *
414         *(getQ() + 1) //478
415         - * (getQ() + 2) * *(getQ() + 2) + * (getQ() + 3) * *(getQ() + 3) //482
416         *RAD_TO_DEG; //483
417         // Declination of Worcester MA (42.2626° N, 71.8023° W) is //484
418         // 14.16° W ± 0.36° (or 8.5°) on 2019-02-16 //485
419         // - http://www.ngdc.noaa.gov/gsonmag-web/#Declination //486
420         myIMU.yaw -= 14.16; //487
421         myIMU.pitch *= RAD_TO_DEG; //488
422         myIMU.roll *= RAD_TO_DEG; //489
423
424         void updateQuaternion() { //490
425             // Must be called before updating quaternions! //491
426             myIMU.updateTime(); //492
427
428             // Sensors x (y)-axis of the accelerometer is aligned with the y (x)-axis of //493
429             // the magnetometer; the magnetometer z-axis (+ down) is opposite to z-axis //494
430             // (+ up) of accelerometer and gyro the output to the quaternion filter. For the
431             // MPU-9250, we have chosen a magnetic rotation that keeps the sensor forward
432             // along the x-axis just like! We have to make some allowance for this
433             // orientation mismatch in feeding in the LSM9DS0 sensor. This rotation can be
434             // modified to allow any convenient orientation convention. This is ok by
435             // a craft orientation standards! Pass gyro rate as rad/s
436             MadwickQuaternionUpdate(myIMU.ax, myIMU.ay, myIMU.az, myIMU.gx*PI/180.0f,
437             myIMU.gy*PI/180.0f, myIMU.gz*PI/180.0f,
438             myIMU.mx, myIMU.mz, myIMU.deltat);
439             // MahonyQuaternionUpdate(myIMU.ax, myIMU.ay, myIMU.az, myIMU.gx * DEG_TO_RAD,
440             myIMU.gy * DEG_TO_RAD, myIMU.gz * DEG_TO_RAD, myIMU.mx,
441             myIMU.mz, myIMU.deltat);
442             // Serial print and/or display at 0.5 s rate independent of data rates
443             myIMU.delt_t = millis() - myIMU.count;
444
445             void printPluck(int p luck) {
446                 if (pluck == 0) {
447                     Serial .print("/");
448                 } else {
449                     Serial.pri t(pluck);
450                 }
451             }
452
453             void printSensorValues() {
454                 if (SerialDebug)
455                 {
456                     Serial.print("ax = "); Serial.print((int)1000 * myIMU.ax);
457                     Serial.print(" ay = "); Serial.print((int)1000 * myIMU.ay);
458                     Serial.print(" az = "); Serial.print((int)1000 * myIMU.az);
459                     Serial.println(" mg");
460
461                     Serial.print("gx = "); Serial.print( myIMU.gx, 2);
462                     Serial.print(" gy = "); Serial.print( myIMU.gy, 2);
463                     Serial.print(" gz = "); Serial.print( myIMU.gz, 2);
464                     Serial.println(" deg/s");
465
466                     Serial.print("mx = "); Serial.print( (int)myIMU.mx );
467                     Serial.print(" my = "); Serial.print( (int)myIMU.my );
468                     Serial.print(" mz = "); Serial.print( (int)myIMU.mz );
469                     Serial.println(" mg");
470
471                     Serial.print("q0 = "); Serial.print(*getQ());
472                     Serial.print(" qx = "); Serial.print(* (getQ() + 1));
473                     Serial.print(" qy = "); Serial.print(* (getQ() + 2));

```

Appendix I: Guitar Device Code

```

1 //Libraries required to run project
2 #include <Adafruit_NeoPixel.h>
3 #include <CircularBuffer.h>
4 #include <RF24.h>
5 #include <RF24Network.h>
6 #include <Servo.h>
7 #include <SPI.h>
8 #include "Thread.h"
9 #include "ThreadController.h"
10
11 //NeoPixel Definitions
12 #define NEOPIXEL_PIN 9 //pin for neopixel LED
13 #define NUMPIXELS 1 //number of neopixels are attached
14 Adafruit_NeoPixel led = Adafruit_NeoPixel(NUMPIXELS, NEOPIXEL_PIN, NEO_RGB + NEO_KHZ800);
15 #define BLINK 1
16 #define SOLID 0
17
18 //Radio Definitions
19 #define CE 7 //SPI pin for NRF24L01+
20 #define CSN 8 //SPI pin for NRF24L01+
21 RF24 radio(CE, CSN); //create a radio object
22 RF24Network network(radio); //create a network object
23 const uint16_t guitar_node = 00; //network address of THIS radio device
24 const uint16_t imu01_node = 01; //network address of 1st child device
25 const uint16_t imu02_node = 02; //network address of 2nd child device
26
27 //function to send messages over radios
28 boolean broadcast(const uint16_t node, int message) {
29     RF24NetworkHeader header(node);
30     return network.write(header, &message, sizeof(message));
31 }
32
33 //Message Queues
34 CircularBuffer<int, 5> calibrationMessages; //stack of calibration results
35 CircularBuffer<int, 30> toPluck; //stack of servos to pluck
36
37 //Pins for each servo
38 #define SERVO_E_LOW 1 //pin for servo for low E string
39 #define SERVO_A_2 //pin for servo for A string
40 #define SERVO_D 3 //pin for servo for D string
41 #define SERVO_G 4 //pin for servo for G string
42 #define SERVO_B 5 //pin for servo for B string
43 #define SERVO_E_HIGH 6 //pin for servo for high E string
44
45 //messages to send to the wearable devices during calibration mode
46 #define CALIBRATE_MESSAGE 1
47 #define MIDDLE_MESSAGE 2
48 #define VERTICAL_MESSAGE 3
49
50 //Button Definitions
51 #define BUTTON 0 //pin for calibration button
52 boolean calibrationHold;
53 boolean ignoreButton;
54
55 int servoStop [] = {89, 90, 89, 90, 90, 89}; // values to stop each motor from servo 1
56 int servoGo [] = {180, 0, 180, 0, 180, 0}; //values to run each motor at full speed
57 from servo 1 - servo 6
58
59 //Thread for handling incoming messages to the radio
60 class dataThread: public Thread
61 {
62     public:
63     void run() {
64         while (network.available()) { //when the network is open and data is being
65             transmitted from another source
66                 int incomingData;
67                 RF24NetworkHeader header;
68                 network.read(header, &incomingData, sizeof(incomingData));
69
70                 if (incomingData < 7) { //values 1-6 are servo pluck messages
71                     if (!calibrationHold) { //when there is calibration hold, messages will be
72                         thrown out
73                         toPluck.push(incomingData); //add message to the plucking queue
74                     }
75                 }
76                 else {
77                     calibrationMessages.push(incomingData); //messages that are not 1-6 are
78                     calibration messages
79                 }
80             }
81         }
82     }
83     public:
84     ServoThread(int n) {
85         name = n;
86         startPluck = 0;
87         lastPluck = 0;
88         pluckTime = 89; //how many milliseconds the servo plucks for, can be adjusted
89         doPluck = false;
90     }
91     Servo servo;
92     int name;
93     unsigned long startPluck;
94     unsigned long lastPluck;
95     int pluckTime;
96     boolean doPluck;
97
98     void run() {
99         if (!toPluck.isEmpty()) { //toPluck.first() == name) {
100             toPluck.shift(); //remove this current pluck off of the circular buffer
101             doPluck = true;
102             startPluck = millis();
103         }
104         else {
105             servo.write(servoStop[name - 1]); //if not me, continue to stop
106         }
107         if (doPluck) {
108             servo.write(servoGo[name - 1]);
109             if (millis() > startPluck + pluckTime) { //when duration of the pluck has been
110                 achieved
111                 servo.write(servoStop[name - 1]); //stop servo
112                 lastPluck = millis(); //record the time
113                 doPluck = false;
114             }
115             }
116         }
117     }
118 };
119
120 //Thread to control onboard LED
121 class LEDThread: public Thread
122 {
123     public:
124     int red;
125     int green;
126     int blue;
127     int duration;
128     int offDuration;
129     unsigned long lastTime;
130     boolean isLit;
131     int mode; //mode 1 is blinking, anything else is solid color
132
133

```

```

133 void run() {
134     if (mode == BLINK) {
135         ledBlink();
136     }
137     else {
138         ledSolid();
139     }
140     runned();
141 }
142 void setColor(int r, int g, int b) {
143     r d = r;
144     green = g;
145     blue = b;
146 }
147 void setDuration(int on, int off) {
148     ONduration = on;
149     OFFduration = off;
150 }
151 void setMode(int m) { //set if blinking or solid
152     mode = m;
153 }
154 private:
155 void ledBlink() {
156     if ((millis() - lastTime) > ONduration) {
157         lastTime = millis();
158         itsLit = false;
159         led.setPixelColor(0, 0, 0, 0); //turn off
160         led.show();
161     }
162     else {
163         if ((millis() - lastTime) > OFFduration) {
164             lastTime = millis();
165             itsLit = true;
166             led.setPixelColor(0, red, green, blue); //change to color
167             led.show();
168         }
169     }
170     void ledSolid() {
171         led.setPixelColor(0, red, green, blue); //change to color
172         led.show();
173     }
174 }
175 }
176 }
177 void ledSolid() {
178     led.setPixelColor(0, red, green, blue); //change to color
179     led.show();
180 }
181 }
182 }
183 //Thread to control calibration button and sending messages back and forth
184 class CalibrationThread: public Thread
185 {
186     public:
187     LEDThread *LED thread;
188     boolean middle = false;
189     boolean right = false;
190     boolean vertical = true;
191     boolean success = true;
192     int response = 0;
193     enum calibrationStates {
194     IDLE_STATE, SET_RESPONSE_STATE, BUTTON_WAIT_STATE, SEND_STATE, ERROR_STATE;
195     };
196     uint16_t node;
197     int message;
198     int state;
199     void run() {
200
201
202     stateMachine();
203     runned();
204     }
205     private:
206     void stateMachine() {
207         switch (state) {
208             case IDLE_STATE: //idle state
209                 calibrationHold = false;
210                 node = imu01_node;
211                 message = CALIBRATE_MESSAGE;
212                 LED_thread->setMode(SOLID);
213                 LED_thread->setColor(0, 0, 0); //LED is off
214                 state = BUTTON_WAIT_STATE;
215                 break;
216             case SET_RESPONSE_STATE:
217                 LED_thread->setMode(SOLID);
218                 if (node == imu01_node) {
219                     LED_thread->setColor(0, 255, 0); //LED is solid green
220                 }
221                 else {
222                     LED_thread->setColor(0, 0, 255); //LED is solid blue
223                 }
224                 if (! calibrationMessages.isEmpty()) {
225                     response = calibrationMessages.shift();
226                     if (message == VERTICAL_MESSAGE) { //check if it is the last message to send
227                         if (node == imu02_node) { //if you send the last message to the last
228                             node, end calibration
229                             state = IDLE_STATE;
230                         }
231                         else { //otherwise send messages to the next node
232                             node++;
233                             message = CALIBRATE_MESSAGE;
234                             state = BUTTON_WAIT_STATE;
235                         }
236                     }
237                 }
238                 message++; //send the next of the messages
239                 state = BUTTON_WAIT_STATE;
240             }
241             break;
242             case BUTTON_WAIT_STATE:
243                 if (digitalRead(BUTTON) && !ignoreButton) { //button can be pressed again
244                     calibrationHold = true;
245                     ignoreButton = true;
246                     state = SEND_STATE;
247                 }
248                 if (!(digitalRead(BUTTON) && ignoreButton)) { //button debouncing to prevent
249                     multiple sending
250                     ignoreButton = false;
251                 }
252                 if (calibrationHold) {
253                     LED_thread->setMode(BLINK);
254                     LED_thread->setDuration(1000, 1000); //blinking at 1 s on, 1 s off
255                     LED_thread->red = 0;
256                     if (node == imu01_node) {
257                         LED_thread->setColor(0, 255, 0); //LED is green
258                     }
259                     else {
260                         LED_thread->setColor(0, 0, 255); //LED is blue
261                     }
262                 }
263                 break;
264             case SEND_STATE:
265                 success = broadcast(node, message);
266                 state = SET_RESPONSE_STATE;
267                 break;
268             case ERROR_STATE:
269
270

```

```

269 LED_thread->setMode(BLINK);
270 LED_thread->setDuration(2000, 2000); //blinking at 200 ms on, 2 ms off
271 LED_thread->setColor(255, 0, 0); //LED is red
272 break;
273 }
274 }
275 }
276 }
277 };
278
279 //create thread for running wireless communication
280 DataThr ad incomingData = DataThread();
281
282 //create thread to handle led timing
283 LEDThread ledThread = LEDThread();
284
285 //create thread to handle calibration
286 CalibrationThread calibrationThread = CalibrationThread();
287
288 //create thread for each servo
289 ServoThread servo1Thread = ServoThread(SERVO_E_LOW);
290 ServoThread servo2Thread = ServoThread(SERVO_A);
291 ServoThread servo3Thread = ServoThread(SERVO_D);
292 ServoThread servo4Thread = ServoThread(SERVO_G);
293 ServoThread servo5Thread = ServoThread(SERVO_B);
294 ServoThread servo6Thread = ServoThread(SERVO_E_HIGH);
295
296 //ThreadController makes sure to run each task at the correct time
297 ThreadController controller = ThreadController();
298
299 //Setup Code, runs once
300 void setup() {
301
302     SPI.begin();
303     radio.begin();
304     network.begin(90, guitar_node); //network address 90 and address of this device
305     radio.setDataRate(RF24_ZMFRFS); //data rate of ZMFRFS for all radios in the network
306
307     pinMode(BUTTON, INPUT);
308     pinMode(NEOPIXEL_PIN, OUTPUT);
309     calibrationHold = false;
310     ignoreButton = false;
311
312     led.begin();
313     led.setBrightness(40);
314     led.show(); //initialize LED to off
315
316
317     servo1Thread.servo.attach(SERVO_E_LOW);
318     servo2Thread.servo.attach(SERVO_A);
319     servo3Thread.servo.attach(SERVO_D);
320     servo4Thread.servo.attach(SERVO_G);
321     servo5Thread.servo.attach(SERVO_B);
322     servo6Thread.servo.attach(SERVO_E_HIGH);
323
324     servo1Thread.servo.write(servoStop[servo1Thread.name - 1]);
325     servo2Thread.servo.write(servoStop[servo2Thread.name - 1]);
326     servo3Thread.servo.write(servoStop[servo3Thread.name - 1]);
327     servo4Thread.servo.write(servoStop[servo4Thread.name - 1]);
328     servo5Thread.servo.write(servoStop[servo5Thread.name - 1]);
329     servo6Thread.servo.write(servoStop[servo6Thread.name - 1]);
330
331     ledThread.itsLit = false;
332     ledThread.setDuration(500, 500);
333     ledThread.setColor(0, 0, 0); //LED is off
334     ledThread.setMode(SOLID); //solid color mode with all colors off
335
336     calibrationThread.LED_thread = &ledThread; //calibration thread takes in the
    LEDThread declared

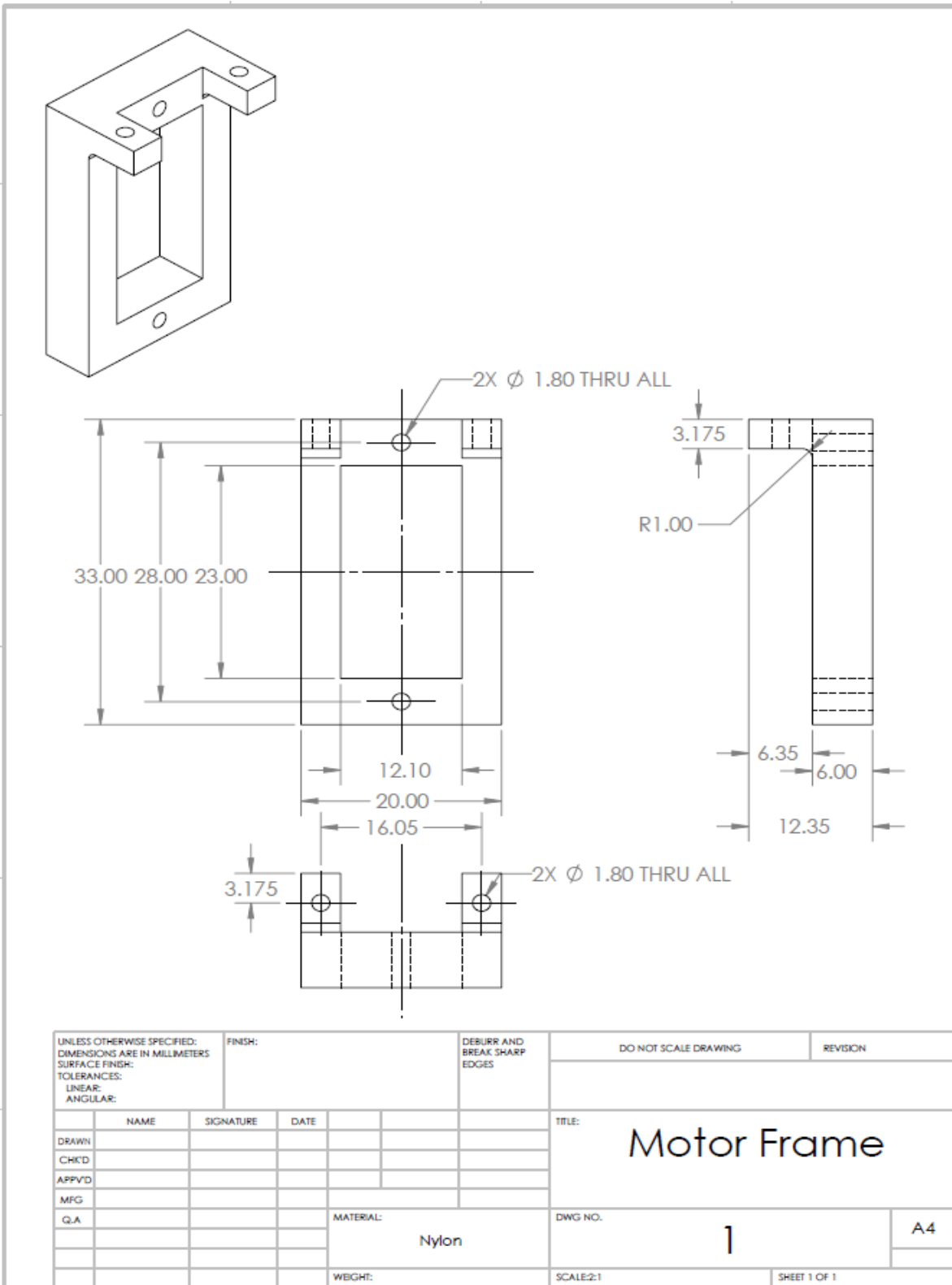
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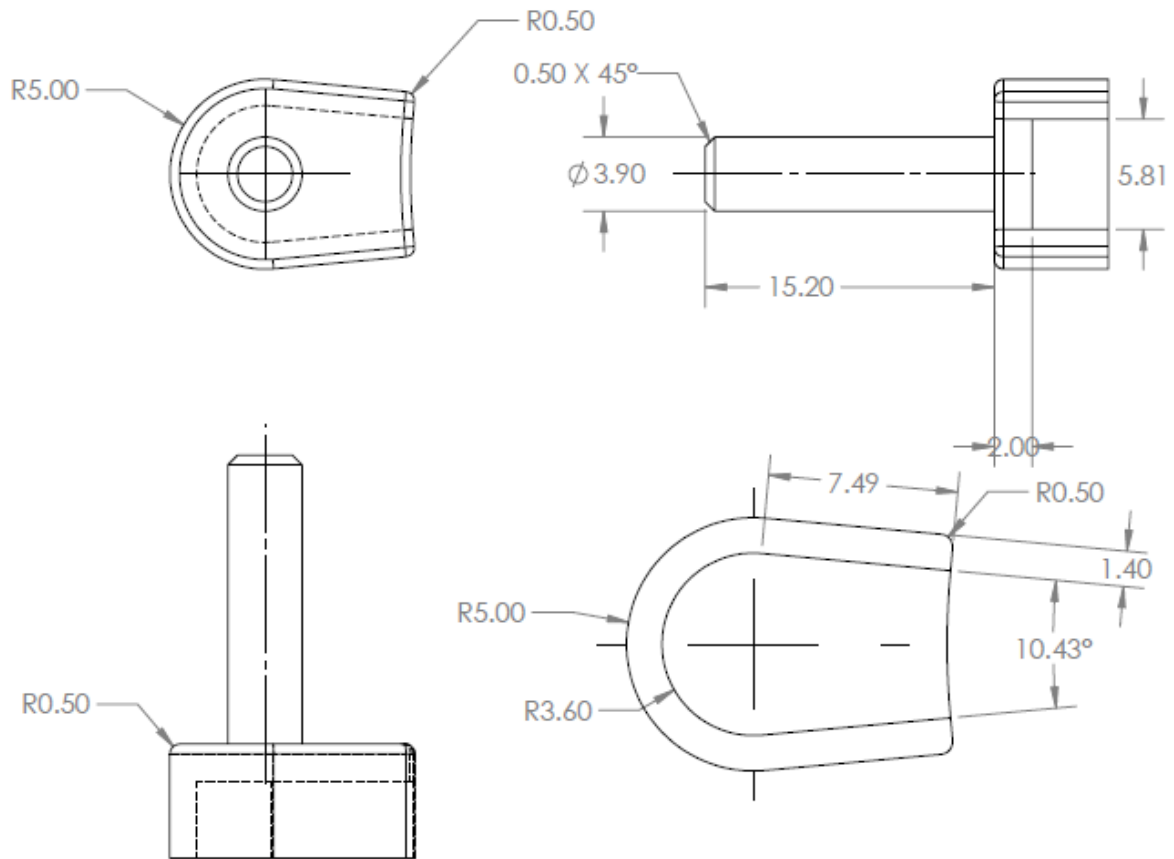
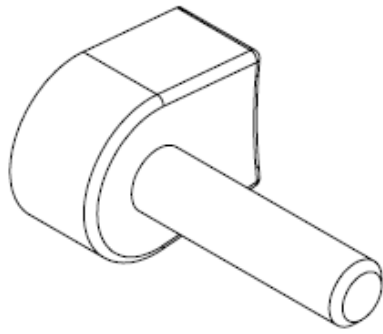
```

337 calibrationThread.state = calibrationThread.IDLE_STATE;
338 //add all threads to the thread controller
339 controller.add(&incomingData);
340 controller.add(&calibrationThread);
341 controller.add(&ledThread);
342 controller.add(&servo1Thread);
343 controller.add(&servo2Thread);
344 controller.add(&servo3Thread);
345 controller.add(&servo4Thread);
346 controller.add(&servo5Thread);
347 controller.add(&servo6Thread);
348 controller.add(&ledThread);
349
350
351 }
352
353 //Main Loop of Program
354 void loop() {
355     network.update();
356     controller.run();
357 }
358
359

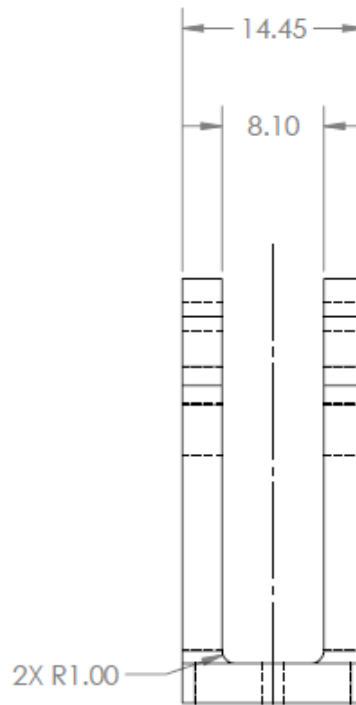
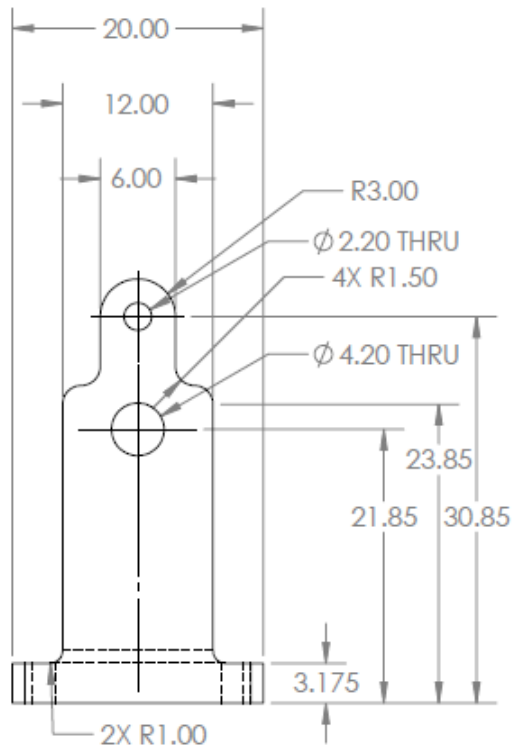
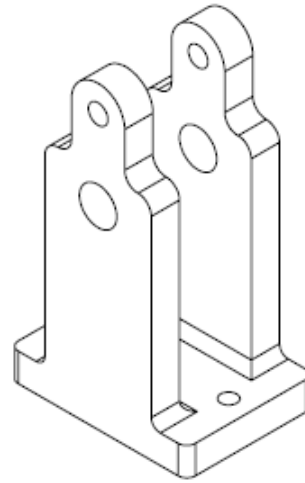
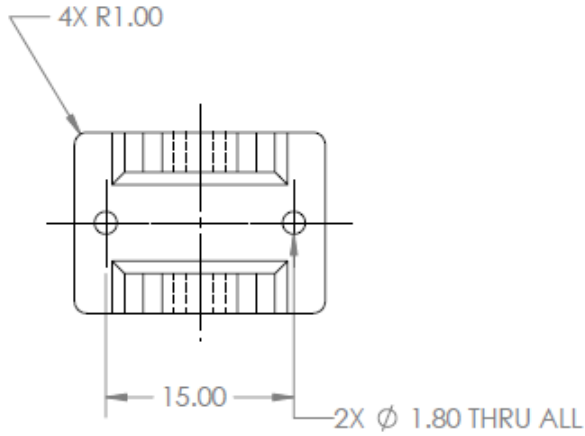
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Appendix J: Plucker Design Drawings

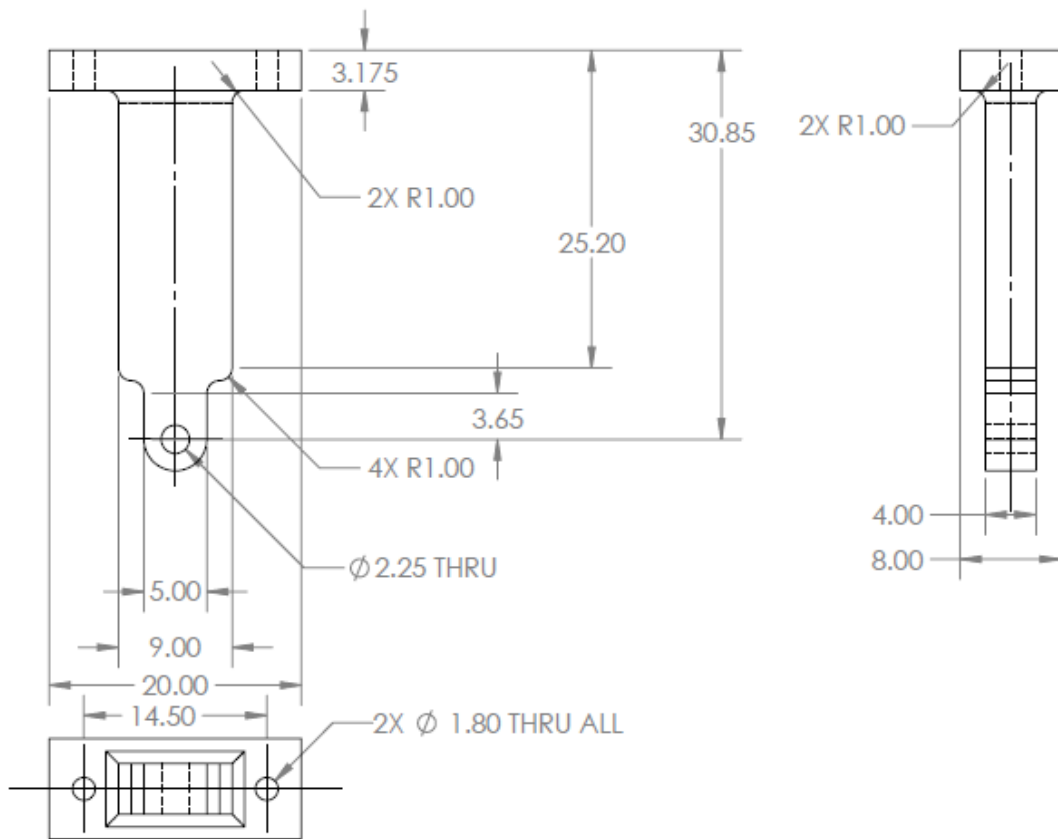
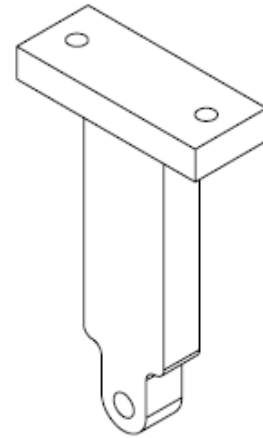




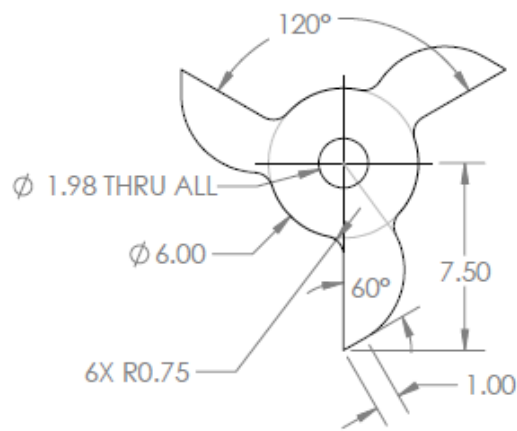
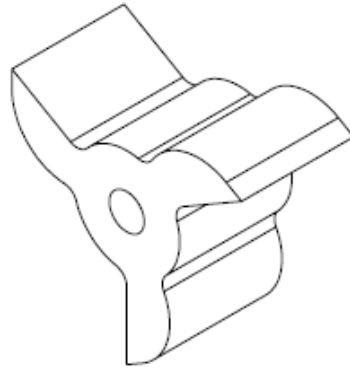
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DRAWN				SIGNATURE		DATE		TITLE: Upper Shaft			
CHK'D											
APP'VD											
MFG											
Q.A						MATERIAL: ABS Plastic (3D Printed)		DWG NO. 2		A4	
						WEIGHT:		SCALE:3:1		SHEET 1 OF 1	



UNLESS OTHERWISE SPECIFIED: DIMENSIONS ARE IN MILLIMETERS SURFACE FINISH: TOLERANCES: LINEAR: ANGULAR:				FINISH:		DEBURR AND BREAK SHARP EDGES		DO NOT SCALE DRAWING		REVISION	
NAME				SIGNATURE		DATE		TITLE: <h1 style="text-align: center;">Gear Frame</h1>			
DRAWN								MATERIAL: Nylon (3D Printed)			
CHKD											
APPVD											
MFG											
Q.A								DWG NO. <h1 style="text-align: center;">3</h1>		A4	
								SCALE:2:1		SHEET 1 OF 1	

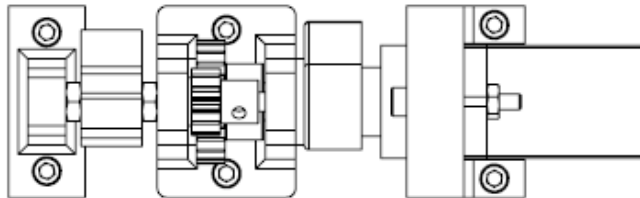
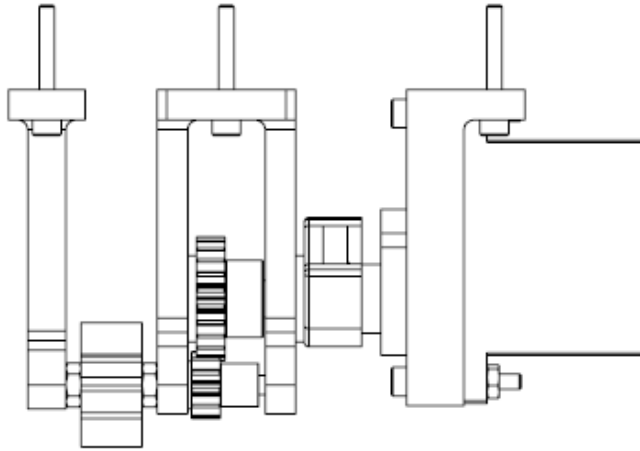
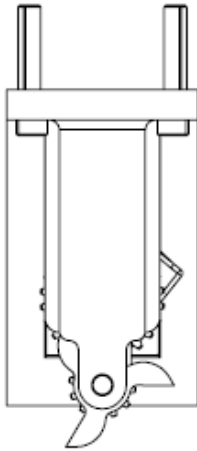
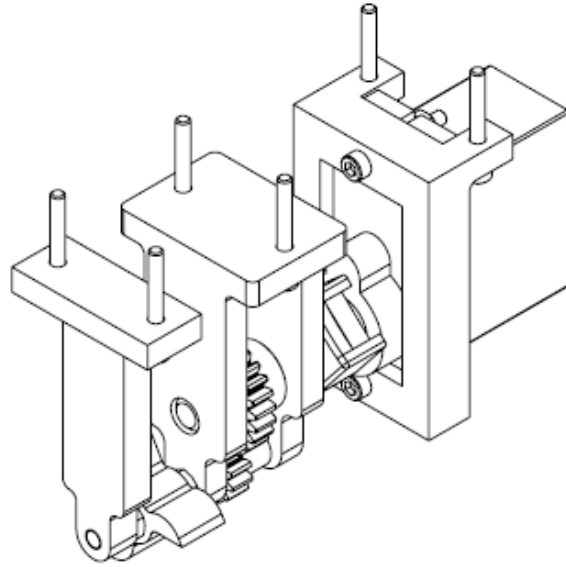


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								TITLE: Shaft Mounting							
DRAWN				NAME		SIGNATURE						DATE			
CHK'D															
APP'VD															
MFG															
Q.A															
				MATERIAL:		Nylon (3D Printed)		DWG NO.		4					
				WEIGHT:				SCALE:2:1		SHEET 1 OF 1					
										A4					

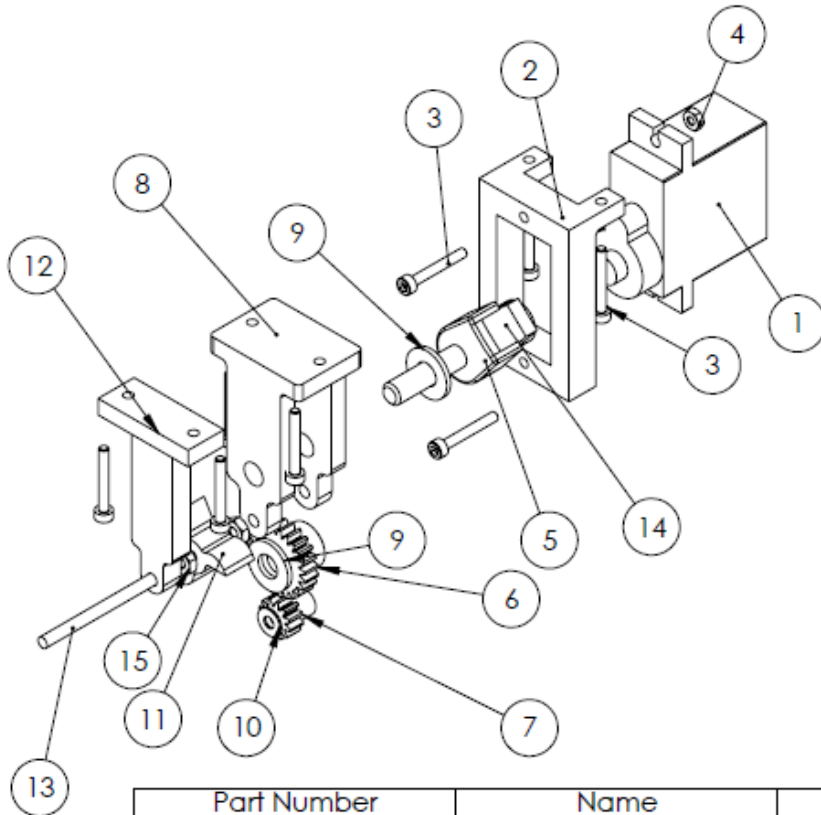


Thickness: 6.00 mm

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NAME		SIGNATURE		DATE		TITLE:		Rotary Plectrum	
DRAWN		CHK'D		APP'VD		MFG		Q.A.	
						MATERIAL:		DWG NO.	
						ABS Plastic (3D Printed)		5	
						WEIGHT:		SCALE:4:1	
								SHEET 1 OF 1	
								A4	



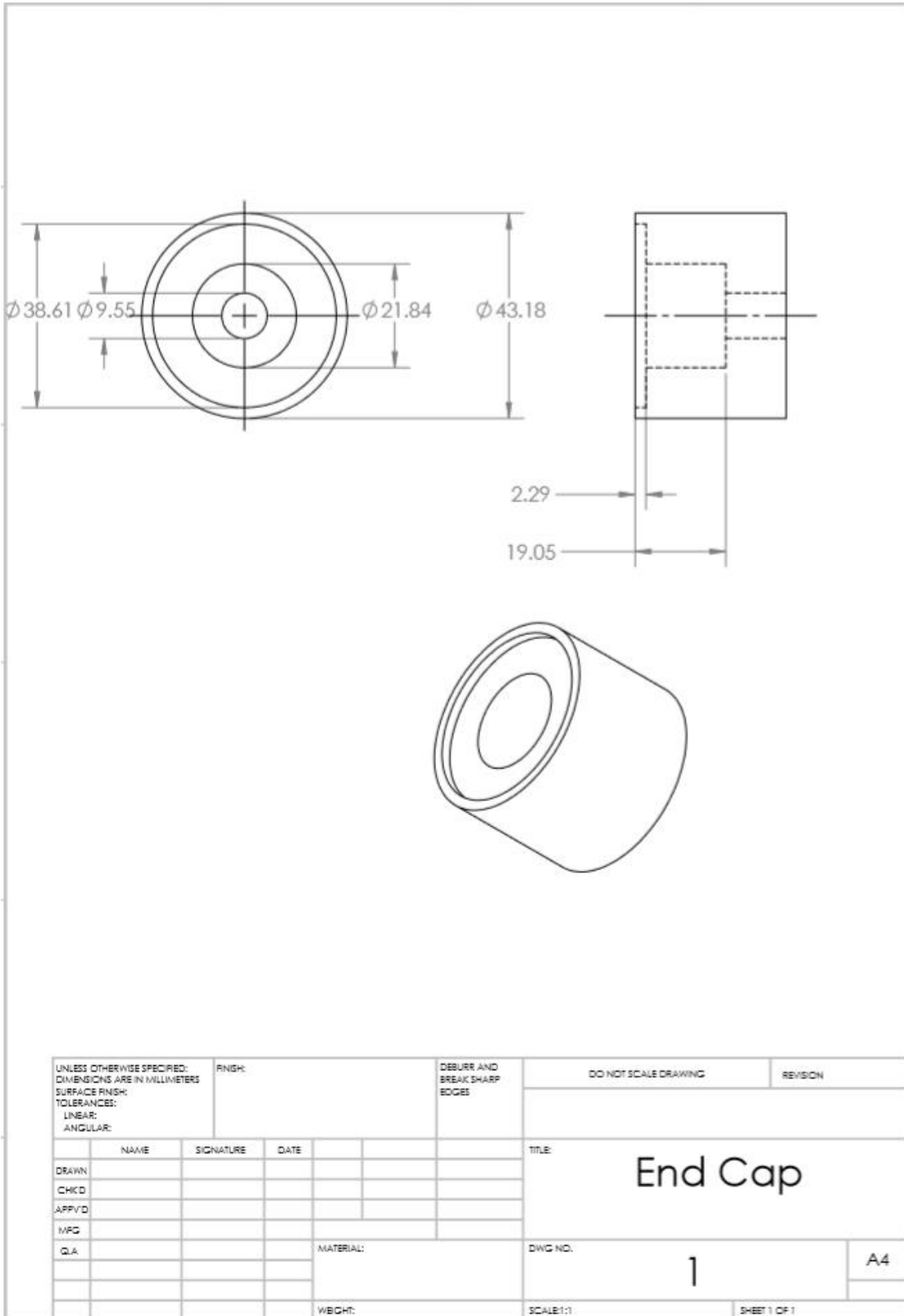
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DRAWN				NAME		SIGNATURE		DATE		TITLE:	
CHKD										Plucking Mechanism	
APPVD											
MFG										DWG NO.	
Q.A										6	
										A4	
										SHEET 1 OF 2	
										SCALE:1:1	
										WEIGHT:	

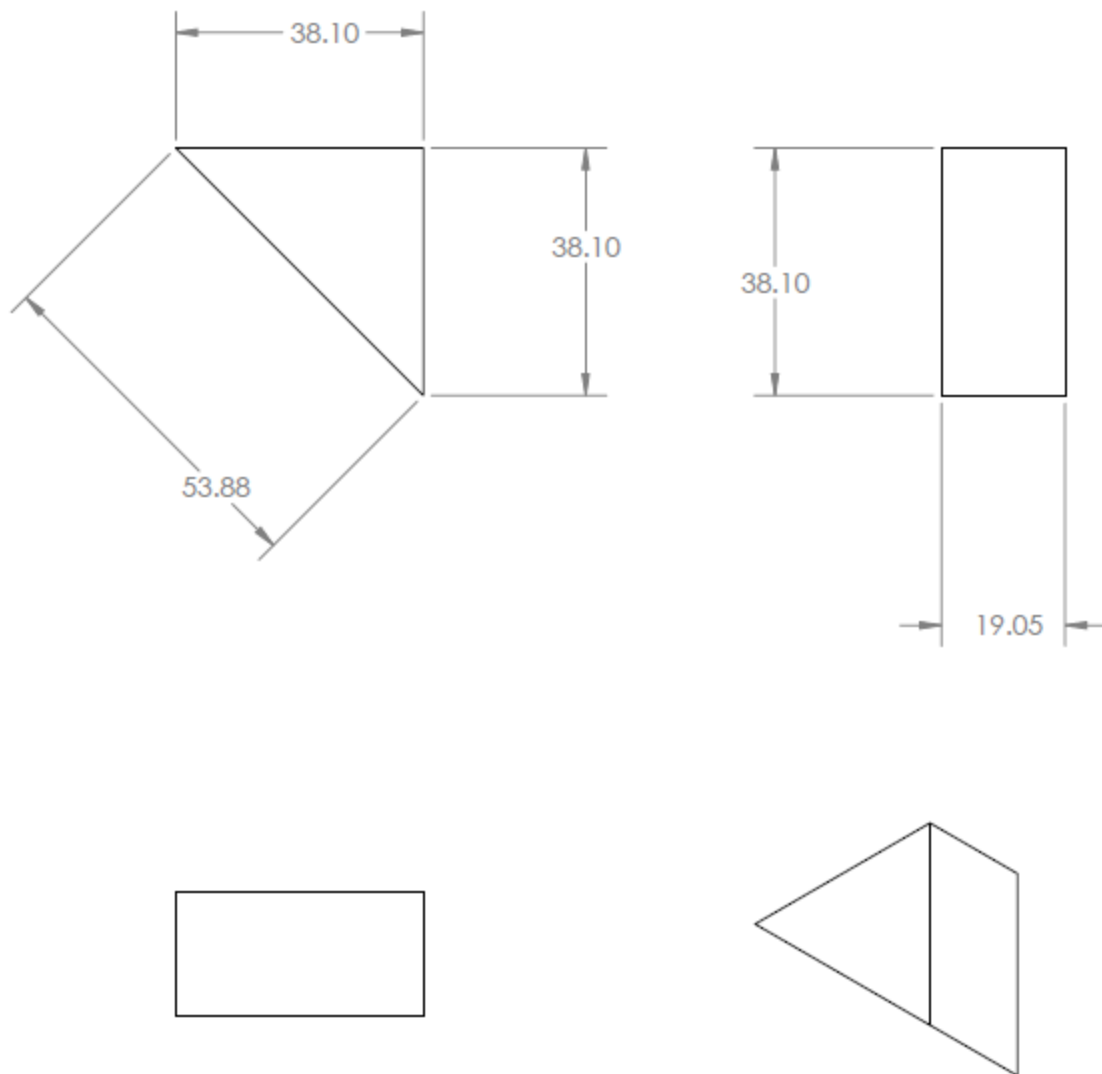


Part Number	Name	Quantity
1	Servo Motor	1
2	Motor Frame	1
3	M1.6x14mm Screw	8
4	M1.6 Nut	2
5	Upper Shaft	5
6	12mm Gear	1
7	6mm Gear	1
8	Gear Frame	1
9	M4 Washer	2
10	M2 Washer	1
11	Plectrum	1
12	Shaft Mounting	1
13	2mm Threaded Rod	1
14	Servo Armature	1
15	M2 Nut	2

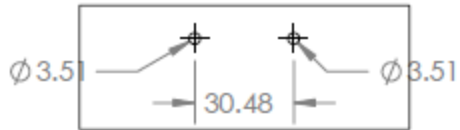
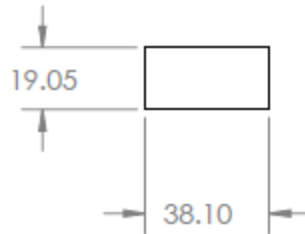
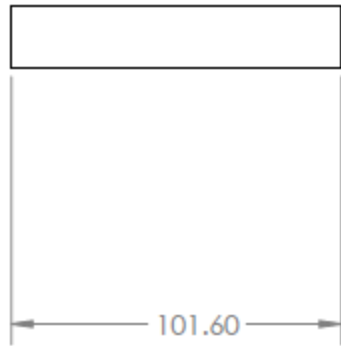
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NAME	SIGNATURE	DATE			TITLE: <h1>Plucking Mechanism</h1>	
DRAWN						
CHK'D						
APP'VD						
MFG						
Q.A			MATERIAL:	DWG NO.	7	A4
			WEIGHT:	SCALE:1:1	SHEET 2 OF 2	

Appendix K: Frame Design Drawings

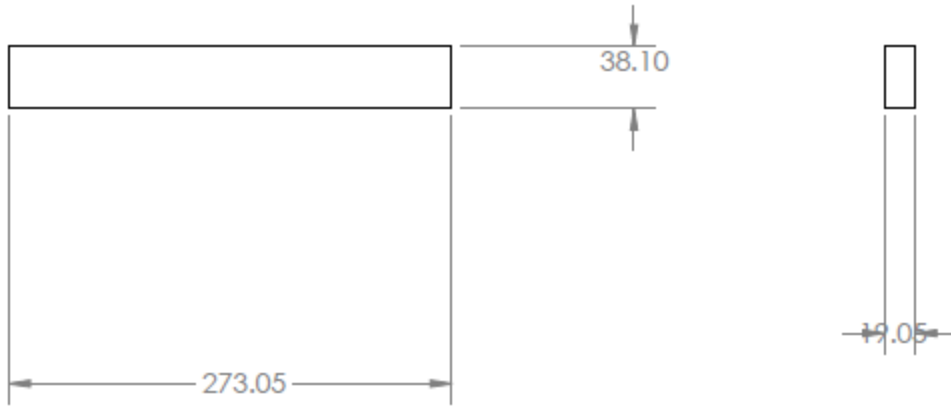




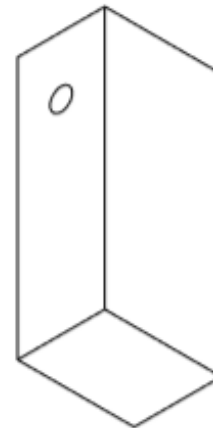
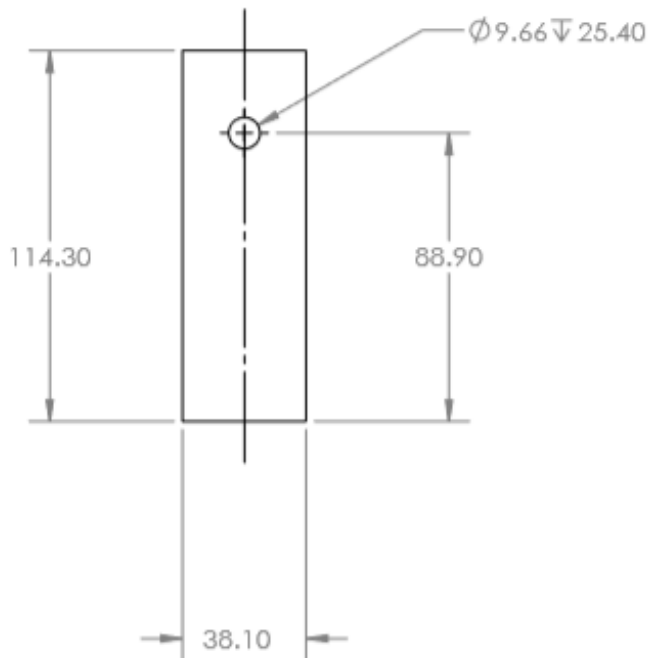
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DRAWN		SIGNATURE		DATE		TITLE:		Angled Support	
CHK'D						DWG NO.		2	
APP'VD						MATERIAL:		A4	
MFG						WEIGHT:		SCALE:1:1	
QA						SHEET 1 OF 1			



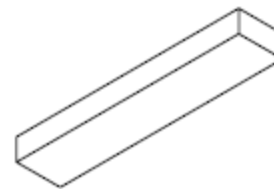
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DRAWN			SIGNATURE		DATE		TITLE:		Neck Support				
CHK'D							DWG NO.					3	
APPV'D							MATERIAL:					A4	
MFG							WEIGHT:					SCALE:1:2	
QA												SHEET 1 OF 1	



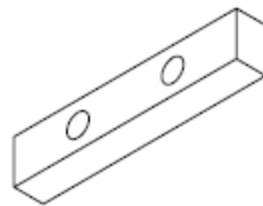
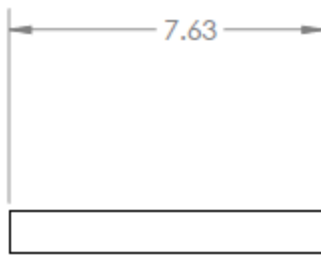
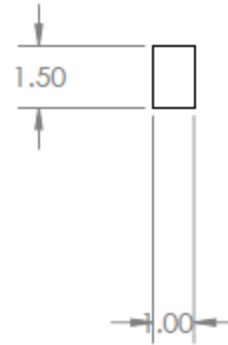
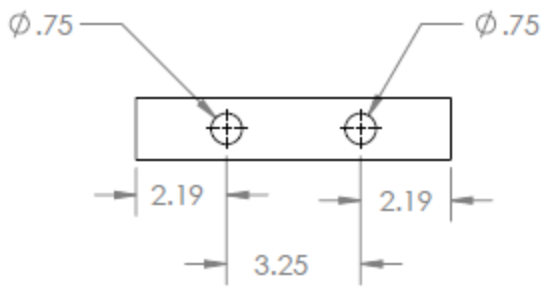
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DRAWN		SIGNATURE		DATE		TITLE:		Bottom Supports		
CHK'D						DWG NO.				
APPV'D						4				A4
MFG						SCALE:1:1				SHEET 1 OF 1
QA						MATERIAL:				
						WEIGHT:				



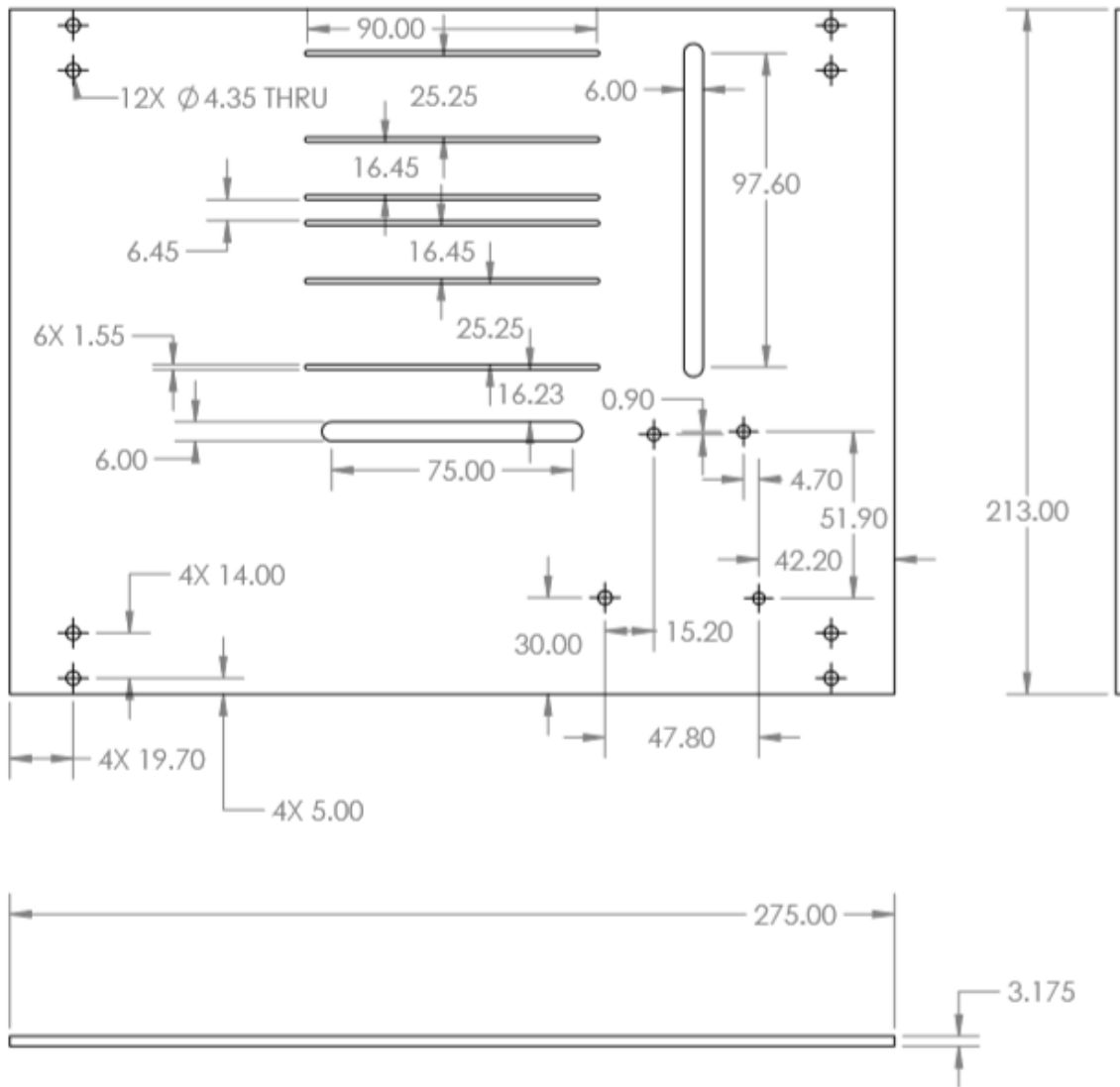
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DRAWN			SIGNATURE		DATE		TITLE:		<h1>Button Strap Holder</h1>				
CHKD							DWG NO.					<h1>5</h1>	
APP'D							SCALE: 1:1						
MFG							WEIGHT:						
Q.A.													



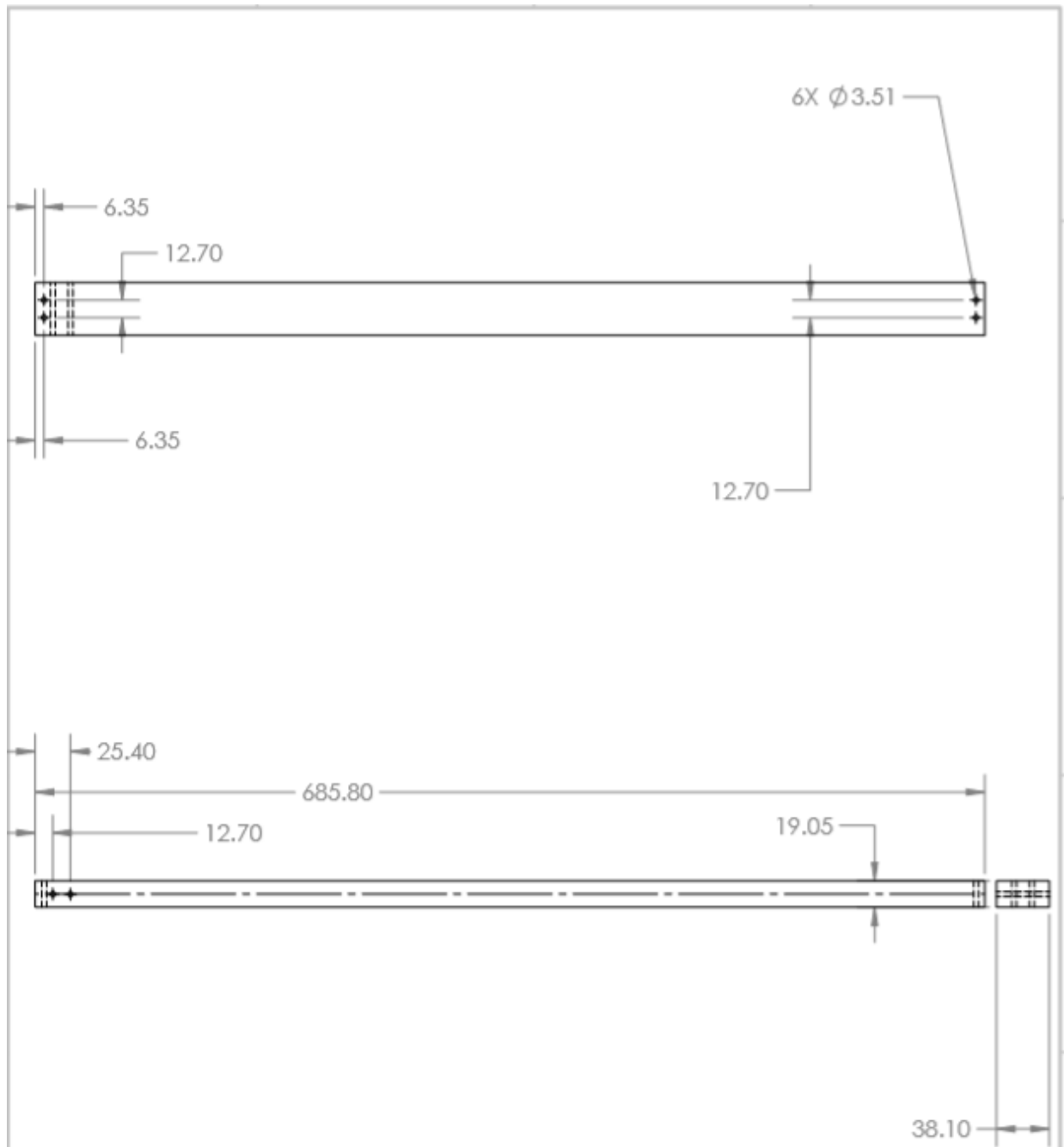
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NAME		SIGNATURE		DATE		TITLE: Short Frame			
DRAWN						DWG NO. 6			
CHK'D									
APP'VD						A4			
MFG									
Q.A				MATERIAL:		SCALE:1:4			
				WEIGHT:		SHEET 1 OF 1			



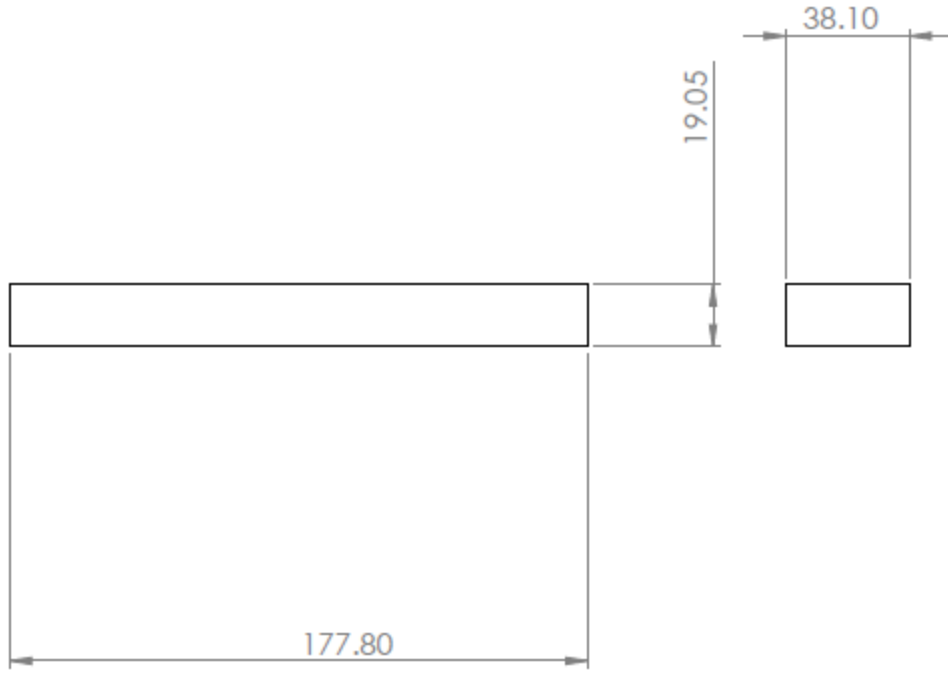
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DRAWN			SIGNATURE		DATE		TITLE:		<h1>Threaded Rod Holder</h1>				
CHK'D							DWG. NO.					<h1>7</h1>	
APPV'D							SCALE:1:1						
MFG							SHEET 1 OF 1						
Q.A							WEIGHT:						



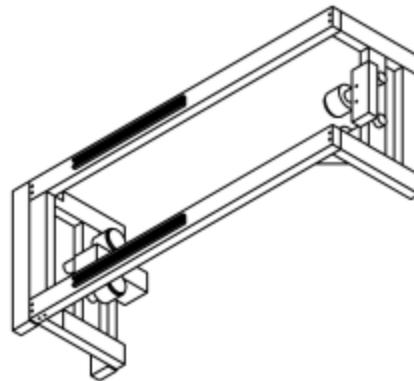
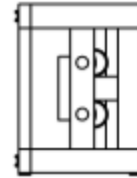
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DRAWN				SIGNATURE		DATE		TITLE: Slotted Baseplate			
CHKD											
APPVD											
MFG											
Q.A						MATERIAL:		DWG NO. 8		A4	
						WEIGHT:		SCALE:1:8		SHEET 1 OF 1	



UNLESS OTHERWISE SPECIFIED: DIMENSIONS ARE IN MILLIMETERS SURFACE FINISH: TOLERANCES: LINEAR: ANGULAR:			FINISH:		DEBURR AND BREAK SHARP EDGES		DO NOT SCALE DRAWING		REVISION	
DRAWN			SIGNATURE		DATE		TITLE:		Horizontal Support	
CHKD							DWG NO.		9	
APPVD							MATERIAL:		A4	
MFG							WEIGHT:		SCALE: 1:8	
Q.A.							SHEET 1 OF 1			



UNLESS OTHERWISE SPECIFIED: DIMENSIONS ARE IN MILLIMETERS SURFACE FINISH: TOLERANCES: LINEAR: ANGULAR:		FINISH:		DEBURR AND BREAK SHARP EDGES		DO NOT SCALE DRAWING		REVISION	
NAME		SIGNATURE		DATE		TITLE:		Vertical Support	
DRAWN									
CHK'D									
APP'VD									
MFG									
Q.A				MATERIAL:		DWG NO.		10	
								A4	
				WEIGHT:		SCALE:1:2		SHEET 1 OF 1	



UNLESS OTHERWISE SPECIFIED: DIMENSIONS ARE IN MILLIMETERS		FINISH:		DESURE AND BREAK SHARP EDGES		DO NOT SCALE DRAWING		REVISION	
SURFACE FINISH:									
TOLERANCES:									
LINEAR:									
ANGULAR:									
	NAME	SIGNATURE	DATE			TITLE: Complete Guitar Frame			
DRWN									
CHKD									
APPVD									
MFG									
Q.A					MATERIAL:	DWG NO. 11		A4	
					WEIGHT:	SCALE:1:10		SHEET 1 OF 1	

Appendix L: Plucker Assembly Guide

1. General Information

1.1. Suggested Purchases

Links to purchase components are given; these were where the team bought those components, as well as possible sources for 3d-printed components; there are alternative retailers available. For 3d-printed parts, high precision is needed. The team used machines with a layer thickness of 0.001 inches and accuracy of about 0.003 inches; while these values do not represent a hard limit on precision required, lower-precision parts could have poor fits for the screws and shafts.

1.2. Tools

The following list of tools is needed to assemble the plucking device:

- Set of allen wrenches (specifically 1.5 mm and 0.028")
- Small clamp or vise to secure parts
- Needle-nose Pliers (optional)
- Thread cutters sized for 2mm shafts
- Heavy-duty Adhesive, such as 2-part epoxy
- Power drill (3/64" or #56 bit)
- 0-80 hand tap
- Craft knife or X-acto knife

1.3. Suggested Assembly Practices





The following is a list of tips to make assembly more easy


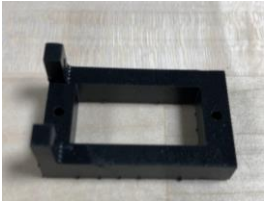




- Be careful when cutting the threaded rod; use thread cutters rather than standard clippers or a hacksaw to preserve the threads.
- Give glue time to set; different adhesives take different amounts of time to cure, and the device should not be run until the glue is at full strength.
- When tightening screws, hold the nut in place with pliers and tighten with the allen wrench.



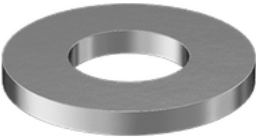
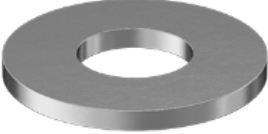


2. Assembly Instructions

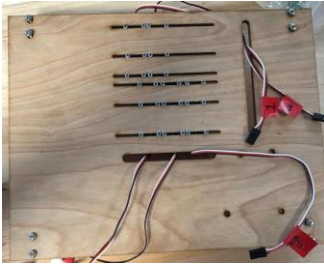

2.1. Components

The following is a list of the components required for 1 plucking device; six pluckers are required in total. For 3D-printed parts, STL files can be found on the public drive (https://drive.google.com/drive/folders/1_12EsLgG01R4oxDcKvJM7nvIhAhizcgi?usp=sharing), as well as SolidWorks part files which can be downloaded and edited if necessary.

Component	Quantity	Image	Link to purchase
Servo motor	1		https://www.pololu.com/product/2820/specs
Servo armature and set screw	1		Included with motor purchase
Upper shaft	1		3d printed (https://us.protiq.com/)
6 mm gear	1		https://www.mcmaster.com/2662N27

12 mm gear	1		https://www.mcmaster.com/2662n28
Motor frame	1		3D printed (https://us.protiq.com/)
Upper shaft (threaded)	1 (total, each device uses a short section)		https://www.mcmaster.com/90024a210
Plectrum	1		3D printed (https://us.protiq.com/)
Set Screw	2		https://www.mcmaster.com/92311a050
Fastener Screw	8		https://www.mcmaster.com/91292a311

Fastener Washer	6		https://www.mcmaster.com/91166a170
Fastener Nut	8		https://www.mcmaster.com/90591a109
Upper Shaft Washer	2		https://www.mcmaster.com/93475a230
Lower Shaft washer	1		https://www.mcmaster.com/93475a195
Lower Shaft Nut	2		https://www.mcmaster.com/90592a075
Gear Frame	1		3D printed (https://us.protiq.com/)

Baseplate	1 Total		Laser-cut from ¼ inch wood (https://www.xometry.com/processes/laser-cutting/)
Shaft Mounting	1		3D printed

2.2. Assembly

Follow the steps below to assemble one plucking device onto the baseplate. Six devices in total are needed.

1. Slide the motor frame over the front of the motor; ensure that the 'feet' (circled in red) are on the side further from the motor shaft (circled in light blue), as shown.



2. Use two M1.6 screws and nuts (circled below) to secure the motor to its frame; position the head of the screw on the front of the motor, closer to the shaft.



3. Clip the end of the single-arm servo armature so that it is similar in shape to the slotted end of the larger gearshaft, as shown. The armature should be cut at the third small hole from the center, but the precise location is not critical.



- Slide the servo horn over the motor shaft and secure it with the accompanying set screw; the head of the screw should rest below the upper surface of the servo armature.



- Glue the motor shaft in place over the servo horns. Set this assembly aside to dry with the shaft facing upward to ensure the glue sets in the correct position.



- Cut a 26mm long segment of threaded rod, to serve as the upper shaft. Ensure that M2 nuts can be screwed onto one side of the shaft.



- Glue a plectrum onto the shaft segment, with a nut tightened onto either side of the plectrum to strengthen the connection. There should be about 3mm of shaft beyond the nut on the short side, to fit the shaft mounting, and about 14 mm on the long side, for the gear.

- When gluing the plectrums, glue three with the plectrums oriented in one direction on the shaft, and the remaining three with the opposite orientation



- Wait at least 30 minutes for the initial glue set.

9. Drill a small hole through the side of the plectrum, and insert a segment of wire and additional glue into the hole.



10. Let the glue set (2-part epoxy takes 24 hours).
11. Drill a 3/64" pilot hole in the hub of each gear, for the set screw.



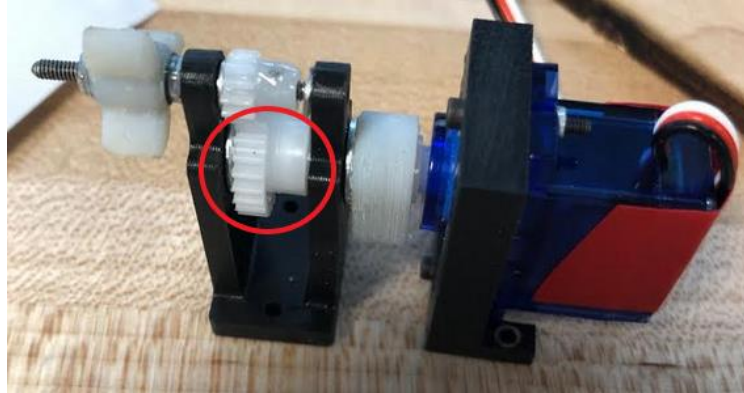
12. (optional) Tap the pilot hole (cut threads into the material) to make it easier to tighten the set screw.
13. Slide the long end of the plectrum shaft through the gear frame, an M2 washer, and through the 6mm gear. A second washer should be placed on the other side of the gear.



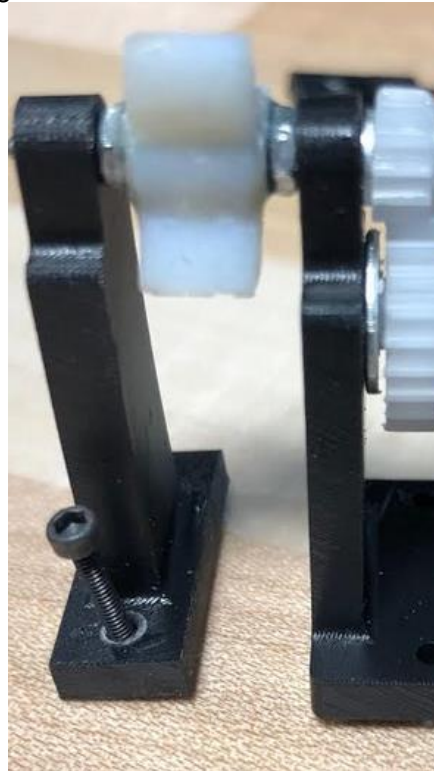
14. Apply glue to the setscrew hole. Tighten the setscrew into the hole to push glue into the shaft.



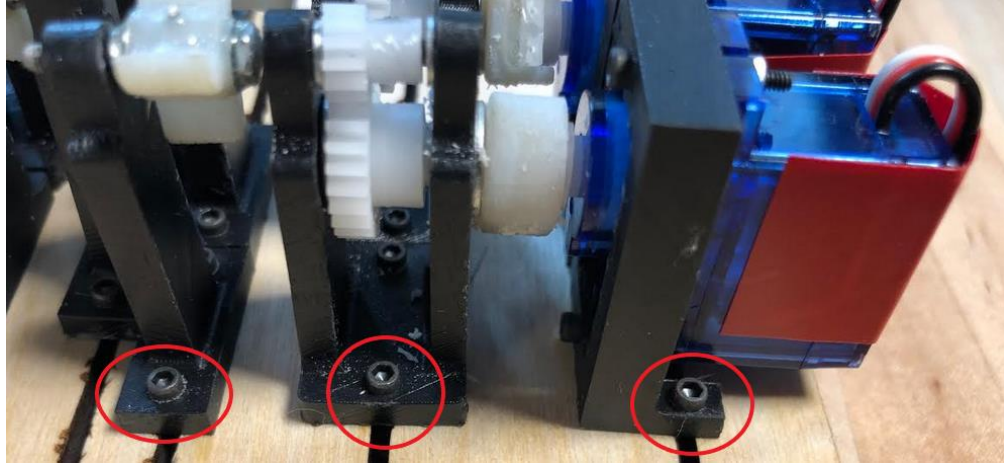
15. Remove the setscrew and repeat step 14 at least 4 times to ensure enough glue is between the shaft and gear. Leave the setscrew tightened against the shaft for additional strength.
16. Allow the glue sufficient time to cure.
17. Make sure there is no glue between the teeth of the gear; if glue is present, clear it out with a craft knife.
18. Slide the large shaft through the gear frame, and through the large 12mm gear and M4 washer.



19. Tighten the set screw on the large gear to secure the large gear to its shaft.
20. Slide the shaft mounting over the small shaft on the far side of the plectrum.



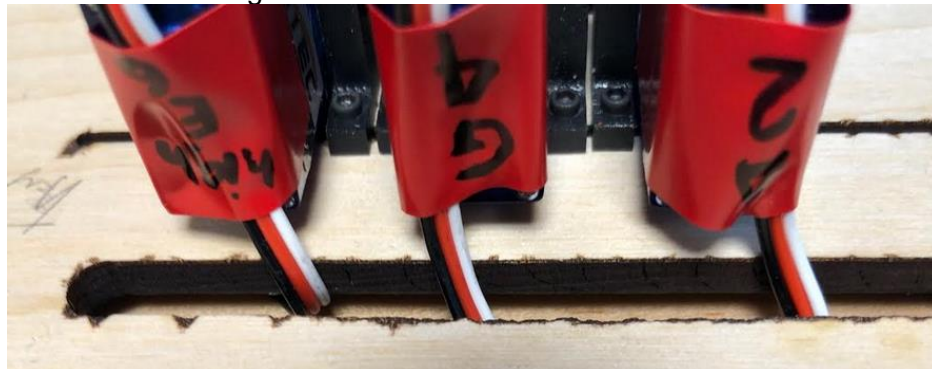
21. Position the assembly over the slots of the baseplate, with the plectrum towards the center and the motor towards the outside.
 - a. All three plucking devices on the same set of slots should have plectrums with matching orientation; the rounded side of the plectrums should face the lowest string.



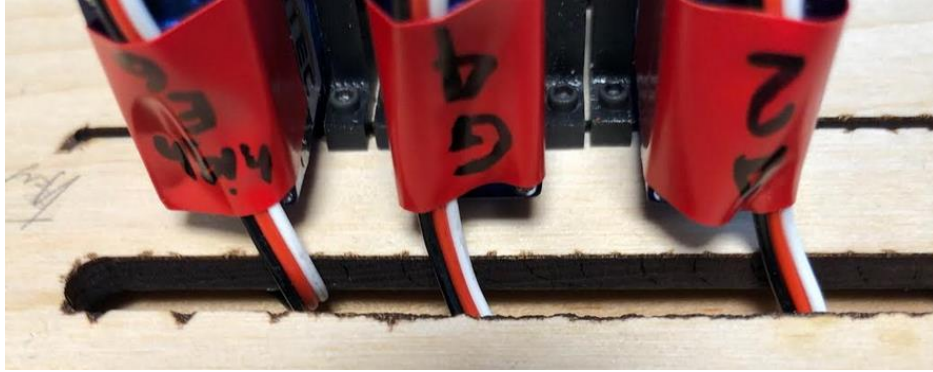
22. Slide M1.6 screws, 6 in total, through the holes on the frame and the slots on the baseplate.
23. Place a washer and nut on the end of each screw; secure the nuts but leave some looseness for adjustment.



24. Place all six plucking devices on the baseplate, following the directions above.
25. Lead the motor wires through the wide slots.



26. Use electrical tape to tape the wires to the back of the motors, keeping them away from the strings.



27. (optional) Use electrical tape to label each wire; plucking device 1 is above the low E string.

Appendix M: Frame Assembly Guide

1. General Information

1.1. Suggested Purchases

For both the different parts of the frame, the links to purchase components are given. This is where the team bought the components, but there are other alternative retailers.

1.2. Tools

The following list is all of the tools required to assembly the frame.

- Drill
- Hack Saw
- Miter Saw or Hand Saw
- Assorted Standard drill bits
- Sockets
- 2 part epoxy
- Tape Measure
- Dremel



1.3. Suggested Assembly Practices

The following is a list of tips for assembling the frame.

- For more consistent and straighter cuts use the miter saw.
- Make sure to let the E600 Industrial Adhesive cure for 72 hours before use to allow for maximum strength.
- Label the wood parts as you cut them to allow. This will help make sure that you don't mix any parts up

2. Components

The required components for assembling one of this device are in the following table.

Component	Quantity	Image	Where to purchase
Poplar Wood 1"x2"	2 8' boards		Home Depot: https://www.homedepot.com/p/Builders-Choice-1-in-x-2-in-x-8-ft-S4S-Poplar-Board-HLPO10208X/206201562
Sheetrock Screws 1"	1 package		Home Depot: https://www.homedepot.com/p/Grip-Rite-6-x-1-in-Philips-Bugle-Head-Coarse-Thread-Sharp-Point-Drywall-Screws-1-lb-Pack-1CDWS1/100162981
Sheetrock Screws 2"	1 package		Home Depot: https://www.homedepot.com/p/Grip-Rite-6-x-2-in-Philips-Bugle-Head-Coarse-Thread-Sharp-Point-Drywall-Screws-1-lb-Pack-2CDWS1/100128601
Threaded Rod 3/8"	1 24" rod		Home Depot: https://www.homedepot.com/p/Everbilt-3-8-in-16-tpi-x-24-in-Zinc-Plated-Threaded-Rod-802167/204274007

Wing Nut	4		Home Depot: https://www.homedepot.com/p/Everbilt-3-8-in-16-tpi-Coarse-Stainless-Steel-Wing-Nut-800231/204274212
Nut	1 package		Home Depot: https://www.homedepot.com/p/Everbilt-25-Piece-per-Bag-3-8-in-16-TPI-Zinc-Plated-Hex-Nut-802364/204274093
Washers	1 package		Home Depot: https://www.homedepot.com/p/Everbilt-3-8-in-Zinc-Plated-Flat-Washer-25-Pack-802324/204276362
Mouse Pad	1		Best Buy: https://www.bestbuy.com/site/insignia-mouse-pad-black/7536185.p?skuld=7536185
Low-Profile Sleeve Bearing Carriages and Guide Rail (Part # 6723K5 & 6723K9)	2 rails, 4 plastic carriages		McMaster-Carr: https://www.mcmaster.com/linear-shafts
3D Printed End Caps	4		3d printed (https://us.protiq.com/)

3. Assembly

3.1. Pre-Assembly

Before the assembly of the frame, it is easier to do all the cutting and measuring. Below is a list of parts that will need to be cut with names that can be used to identify them by later.

Using the 2x1 Poplar Wood

1. Horizontal Supports: 2 pieces 27"
2. Short Frame: 5 pieces 7" $\frac{5}{8}$
3. Bottom Supports: 2 pieces 10 $\frac{3}{4}$
4. Angled Supports: 4 pieces
5. Neck Rest: 1 pieces 4 $\frac{1}{2}$
6. Vertical Supports: 4 pieces 7"

Using any piece of wood that fits the requirements

1. Button Strap Holder: 1 piece 2"x1 $\frac{1}{2}$ "x4 $\frac{1}{2}$ "

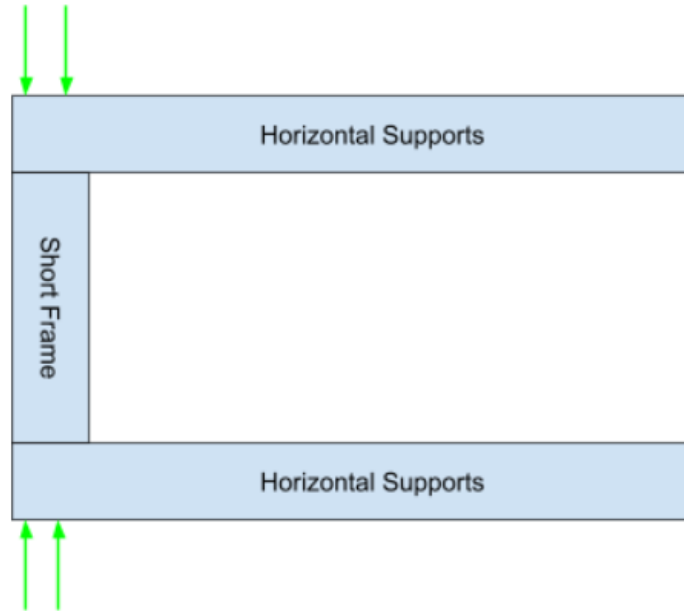
For the Threaded Rod Supports

1. Threaded Rod: 4 pieces 4 $\frac{1}{2}$
2. Mouse Pads: 4 pieces

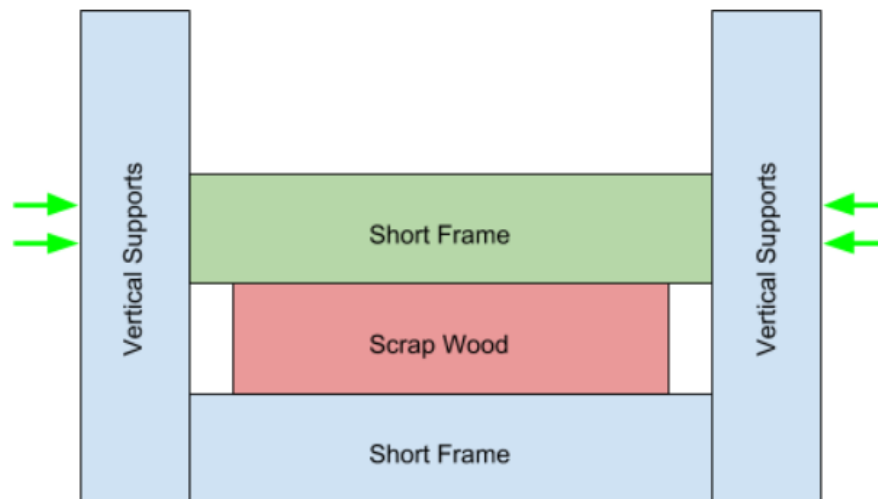
3.2. Assembling the Wooden Structure

It is recommended that you pre-drill holes before drilling in screws to help prevent splitting, but it is not required.

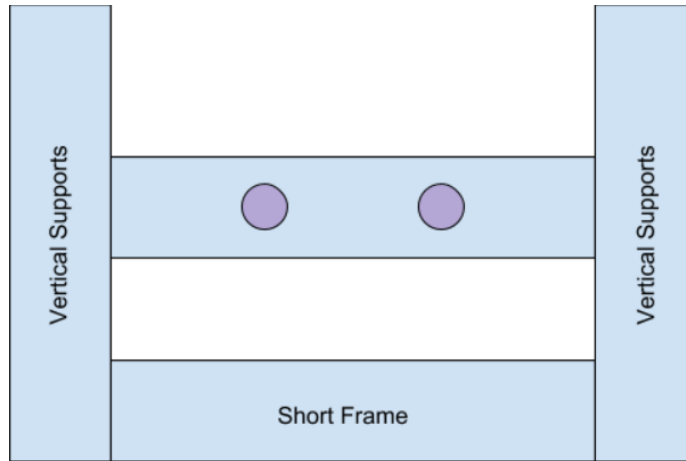
1. Take the two horizontal supports and place them parallel to each other, lie them flat on a solid flat surface and place a short frame support in between and perpendicular to the two longer pieces so it is flush with one of the end
2. Using 4 2" sheetrock screws, screw the three pieces together. There should be 1 screw at each of the arrows shown in the following image. The place where this short frame has been placed will now be designated at the bottom of the entire assembly to help with future orientation.



3. Set the U-shaped frame piece aside and grab all 4 vertical supports and 2 short frame pieces.
4. Repeat steps 1 and 2 but instead for each U-shaped frame piece use 2 vertical supports and 1 short frame piece.
5. Grab another 2 short frame piece and any scrap piece of poplar that is shorter than $7 \frac{5}{8}$
6. Take one the U-shaped frames made from the vertical supports and frame piece and place the scape piece of wood in between the two vertical up against the short frame piece. This will not be attached to anything as it serves just as a spacer.
7. Next take one of the loose short frame pieces and place it in between the vertical supports and the scrape wood spacer. The current assembly should look like the image shown below.

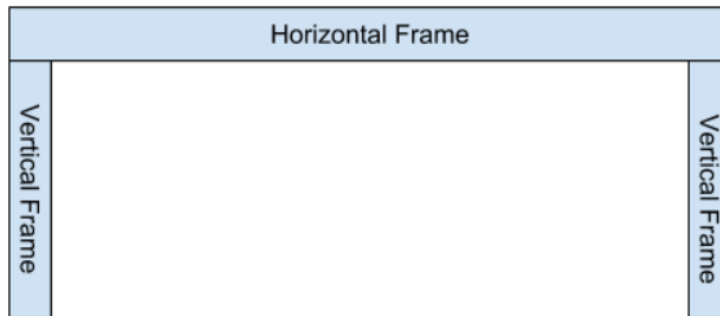


8. Based on the arrows in the previous image screw the short frame to the vertical supports using the 2" sheetrock screws.
9. Slide the spacer out of the assembly.
10. Repeat steps 7-9 for the other vertical support U-shaped frame.
11. Taking the previous two assemblies drill $2 \frac{3}{8}$ " holes on each of the center short frame pieces $3 \frac{1}{4}$ " apart as shown in purple in the image below.



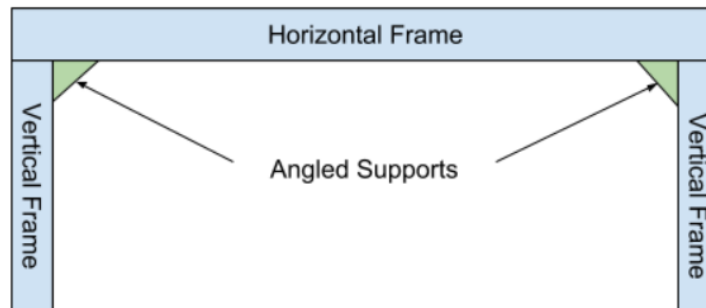
12. Get the U-shaped frame piece made from the horizontal supports and place the other two pieces on the ends as shown in the image below.

Side View

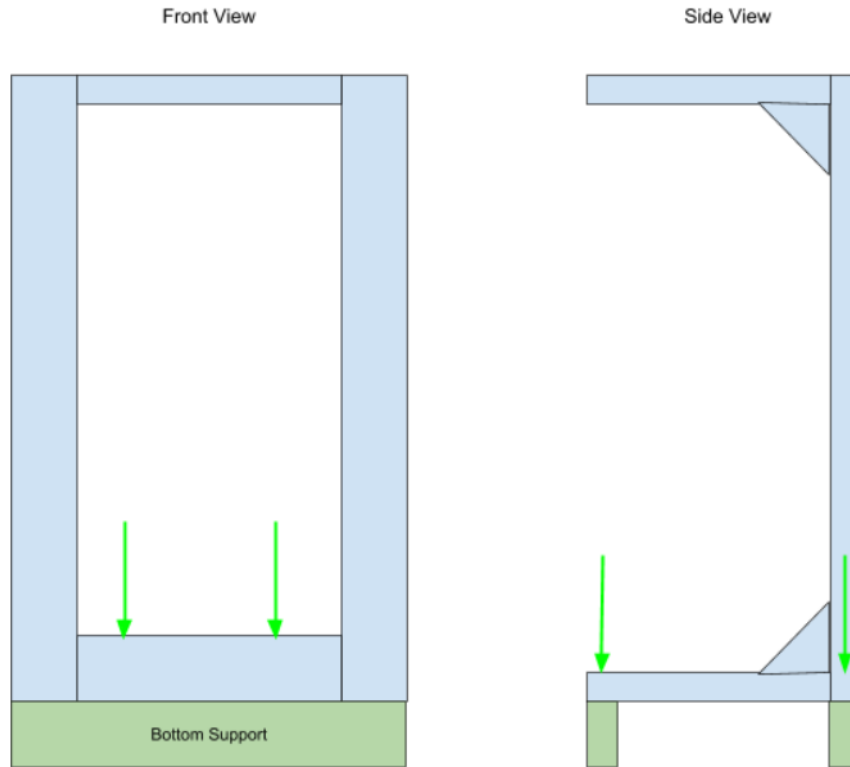


13. Gather all 4 angle supports and using the 1" screws screw one into each corner of the connections you just made together.

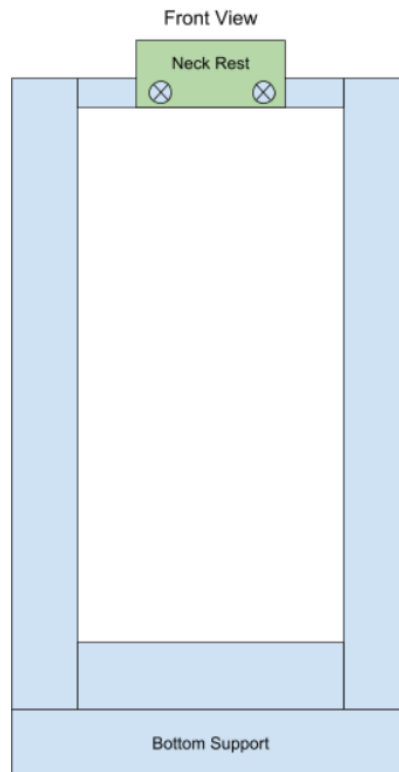
Side View



14. Locate the bottom of the assembly and the 2 bottom supports. These supports will be used to help the entire assembly stand on its own even after the threaded rods are inserted. Using the 2" screws come in from the top as indicated in the figure below, this will help keep the bottom smooth to prevent rocking.



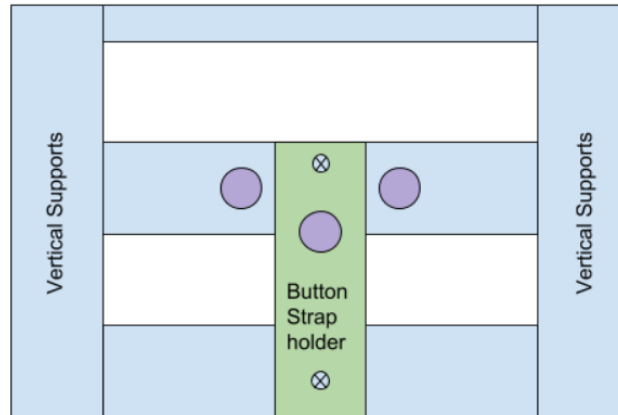
15. Take the neck rest and screw that, using the 2" screws to the top of the frame perpendicular to the holes for the threaded rods are.



16. The final piece of the wooden assembly is the button strap holder this will be screwed using the 2" screws to the bottom half of the frame centered between the vertical

supports as shown below. There should also be a deep hole in this piece that is 1" diameter, 3 1/2" high and centered across.

Cross Section of the Bottom
looking toward the ground



17. The final wooden structure will look like the image below.



3.3. Assembling the Threaded Rod Supports

Below will be the instructions for making a threaded rod support but note that there needs to be 4 total threaded rod assemblies so plan to do each step a total of four times

1. Using a sanding head of the Dremel dress up the cut ends of the threaded rod to allow for nuts to be able to screw onto it.
2. Take one of the 3D printed end caps and screw it onto one of the ends of the rod. This should be done so that the flat end of the end cap is facing the center of the rod. Keep screwing until the end of the rod that went through the cap is flush with the depressed section's surface, this will later be used to help keep the mouse pad solid as it will later sit up against it.

3. Take two of the nuts, put one on either end of the threaded rod and tighten then up against the end cap. BEWARE: you want them tight but make sure not to over tighten otherwise you could crack the plastic of the end cap.
4. Mix some of the 2 part epoxy up by following the instructions on the bottles and use it to glue the mouse pads down into the depression on the end cap, this can include sticking glue onto the end of the rod inside the end cap so that the mouse pad can also stick there.
5. Let the rods dry for 24 hours to allow for the glue to fully set.
6. Your end rods should look like this.



3.4. Combining the Assembly

1. With the glue fully set on the rods the can then be put into the frame. One threaded rod goes through each of the holes with a washer and nut on each side of the frame.
2. The final few step involve attaching the linear slide tracks. These sit on the front face of the horizontal pieces, the need to be parallel to each other and the spacing has to be just the right distance so that the baseplate will slide through the rails easily.
3. In order to get the spacing correct, it is recommended that you attach the inner slides to the baseplate and slide the rails on while they are not attached to anything. Then lay the rails down on the horizontal pieces and mark out the holes for one of the tracks.
4. Using a 3 m drill bit, drill holes on the mark for one of the rails.
5. Place the rail over the holes and fit the screws through. This will hold that rail in place while marking out the holes for the second rail.
6. If separated slide the in rails back through the linear slide on the guitar and mark out the holes for the second track.
7. Once all marked out drill the new holes using the 3 m drill bit.
8. Using a screwdriver and socket tighten the nuts and bolts to hold down the linear slide onto the frame.
9. Without the guitar the finished frame will look like the one in the image below



10. To put the guitar in the frame, make sure all the end caps are retracted as far as the can go. Stick the neck in between the 2 horizontal supports and lay it on the neck rest. The

using a slight amount of force push the bottom back of the frame down so it flexes until you can slide the strap button into the large block with the hole that will hold in in place.

11. Slide the baseplate onto the linear slides
12. Using a ruler push the guitar either up or down the frame to adjust the distance of the strings the bottom of the baseplate. The goal distance is ~36 mm.
13. Once the guitar is at the correct distance away from the baseplate tighten the end caps up to the body of the guitar.

Appendix N: PCB Assembly Guide

1. General Information

1.1. Suggested Purchases

For both the wearable device PCB and the guitar PCB, the links to purchase components are given. This is where the team bought the components, but there are other alternative retailers.

1.2. Tools

The following list is all of the tools required to assembly the devices.

- Soldering iron
- Soldering “Helping Hands” or “Third Hand” stand
- Needle-nose pliers
- Flat-nose pliers
- X-ACTO knife
- Wire cutters
- Multimeter (optional)
- Breadboard (optional)

1.3. Suggested Assembly Practices

The following is a list of tips for assembling the devices.

- To cut female headers easily, count the number of pins and then use needle-nose pliers to pull out the pin next to the amount needed. Score the plastic housing with the X-ACTO knife and break the section away from the rest. See this video for more assistance: <https://youtu.be/qDG3VFMSMPQ>
- Sometimes components can be stabilized when soldering by plugging pins (that won't be soldered!) into a breadboard
- Probing the leads with the multimeter after soldering is important to ensure that no pins have been unintentionally connected.


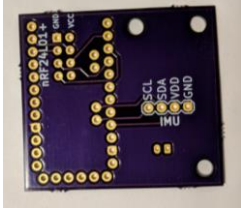

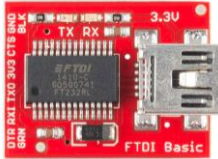


1.4. Files to Download





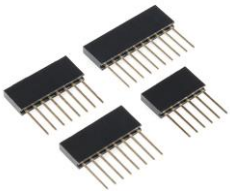


- To edit the printed circuit boards or to order more of them. The files are located in this folder: <https://drive.google.com/open?id=1LfEdh0aBH9-G25blmzNXmDTE7EtxqKcL>
- To have more boards manufactured, upload the GBRS zip files for either the wearable device or guitar device to an online manufacturer such as Osh Park.
- To open the PROJECT zip files and make edits to the boards, download Kicad here: <http://kicad-pcb.org/download/>

2. Wearable Device

2.1. Components

The required components for assembling **one** of this device are in the following table. For this project, two identical devices allow the user to pluck two strings at once.

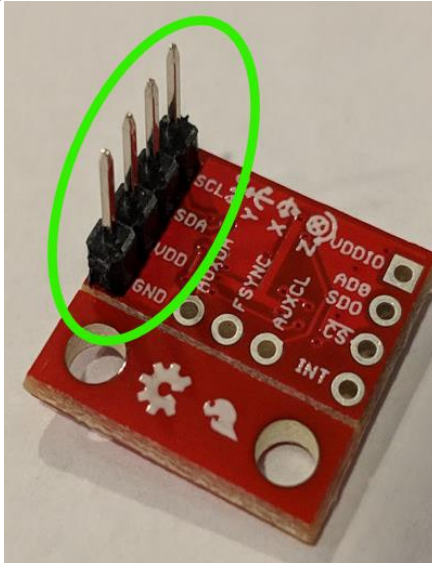
Component	Quantity	Image	Link to purchase
Rosin Core Solder	1		homedepot.com/p/Bernzomatic-0-5-oz-Rosin-Core-Solder-327788/100494065
Printed Wearable Device Board PCB	1		Upload the ZIP file containing the .gbr files to oshpark.com
Arduino Pro Mini 328-3.3V/8MHz	1		sparkfun.com/products/11114
FTDI Basic Breakout - 3.3V	1		sparkfun.com/products/9873
IMU Breakout MPU-9250	1		sparkfun.com/products/13762
nrf24L01+ Transceiver Module	1		amazon.com/dp/B00Q9O868G/ref=twister_B07434GZWL?encoding=UTF8&psc=1 (Sold in 10pcs)

400mAh Lithium Ion Battery	1		sparkfun.com/products/13851
LiPo Charger Micro USB (requires micro USB cable and wall wart to be used, which are not listed)	1		sparkfun.com/products/10217
JST Vertical Connector	1		sparkfun.com/products/8613
Female Headers	2		sparkfun.com/products/115
Arduino Stackable Header Kit - R3	1 (can be shared across building 2 units)		sparkfun.com/products/11417
Break Away Headers - Straight	1		sparkfun.com/products/116
Electrolytic Decoupling Capacitor - 10uF/25V	1		sparkfun.com/products/523

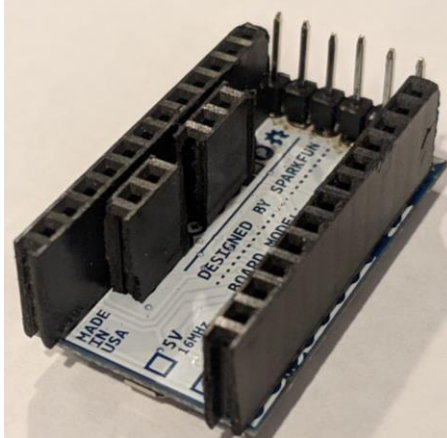
2.2. Assembly

Follow the steps below to assemble one wearable device unit.

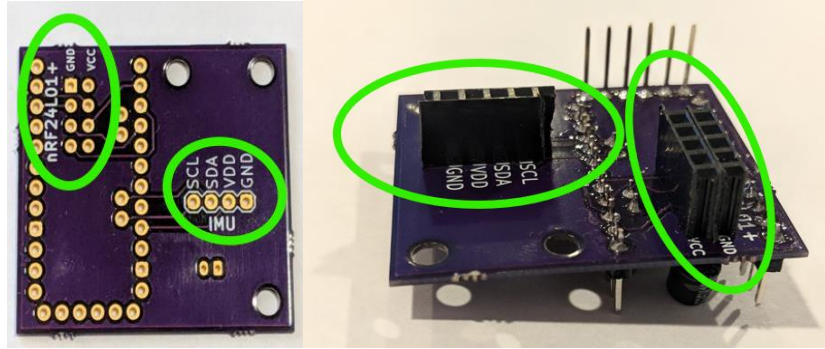
1. Cut the male headers to size. Two sections of 12 pins, two sections of 2 pins, one section of 6 pins, and one section of 4 pins are needed.
2. Cut the female headers to size. Two sections of 12 pins, two sections of 2 pins, and three sections of 4 pins are needed
3. Cut one stackable header to a length of 6 pins.
4. Trim the capacitor leads to 3mm.
5. Solder the 4 pin section of male headers to the IMU SCL, SDA, VDD, and GND pins as shown in the following image



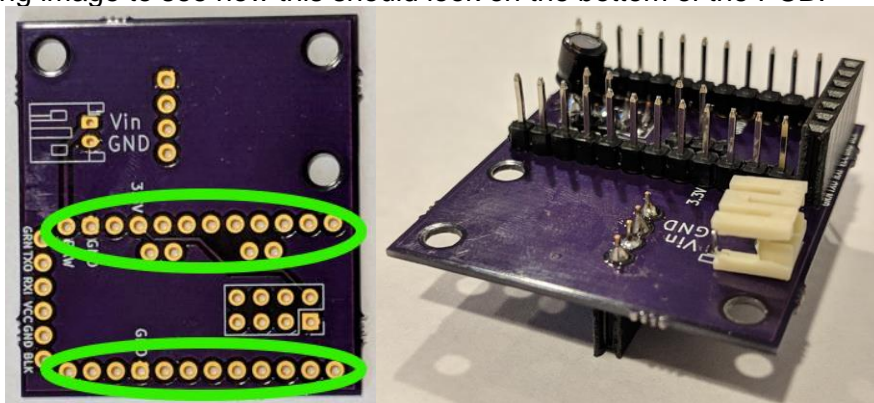
6. Solder the 6 pin section of male headers to the Programming Header pins (BLK, GND, VCC, RXI, TXO, GRN) and the 12 pin and 2 pin sections of female headers to the rest of the pins on the Arduino Pro Mini as shown in the following image.



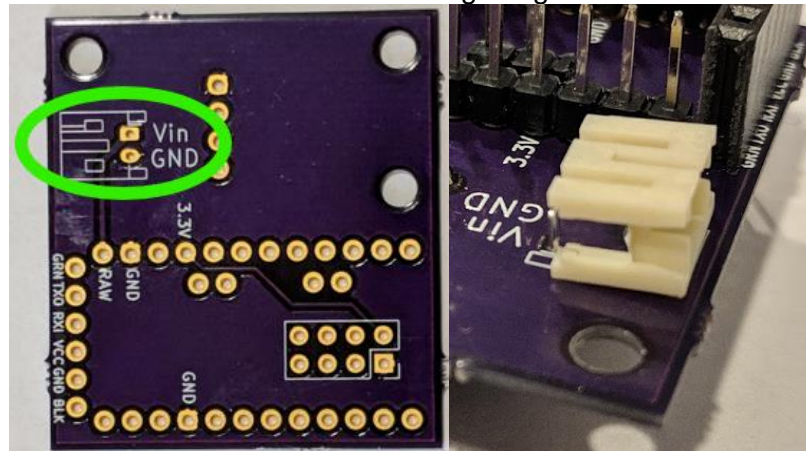
7. Put the PCB such that the "IMU" and "nrf24L01+" screen printing facing up. This will be referred to as the top of the PCB.
8. Solder the 4 pin sections of female headers to that side of the PCB into the holes labeled for the IMU and nrf24L01+ as shown in the following image



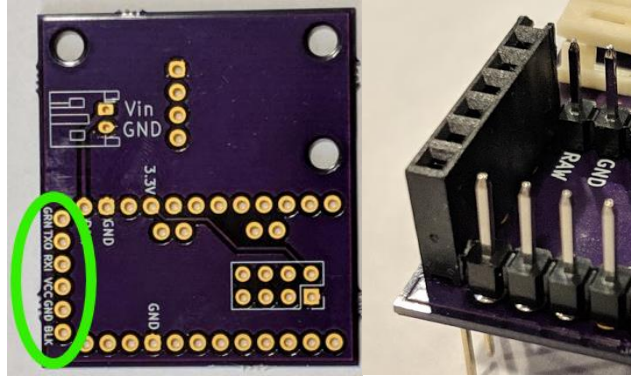
9. Solder the 12 pin and 2 pin sections of male headers by plugging the short side of the header up into the PCB and leaving the long side of the PCB to face out the other side of the board. See the preceding image for how this should look on the top of the PCB and the following image to see how this should look on the bottom of the PCB.



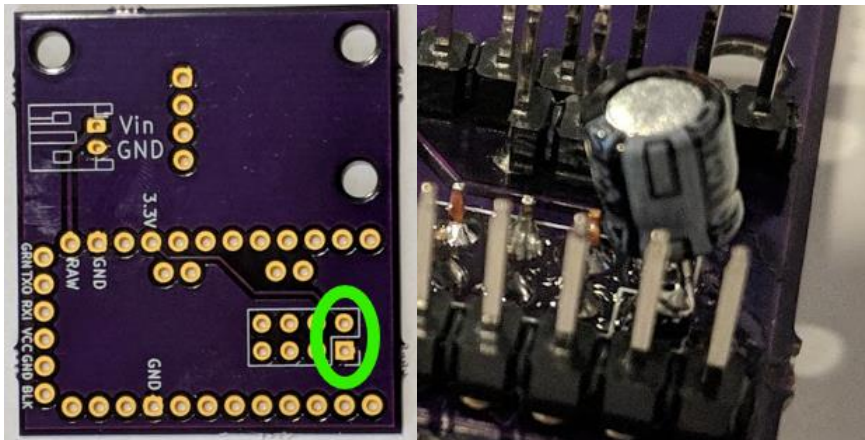
10. Flip the PCB over so that the bottom side is facing up.
11. Solder the JST vertical connector into the holes marked Vin and GND such that the plug is facing out of the PCB as shown in the following image



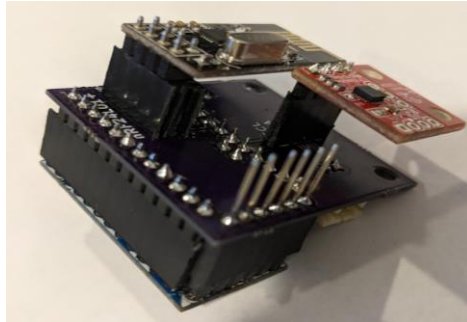
12. Solder the 6 pin section of the stackable header to the pins labelled BLK, GND, VCC, RXI, TXO, GRN, shown in the following figure



13. Solder the capacitor to the VCC and GND leads sticking up from the previously soldered female headers of the nrf24L01+. It is very important that the polarity of the capacitor is correct. The negative symbol, as in the following images, must be connected to the GND pin which is boxed in.




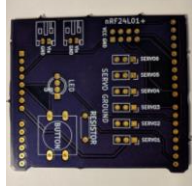



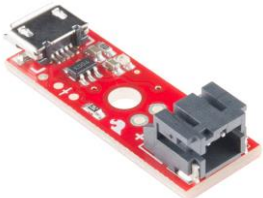
14. Plug the components as shown in the following image, with the IMU and nrf24L01+ on the top of the board and the Arduino Pro Mini on the bottom of the board!







3. Guitar Device

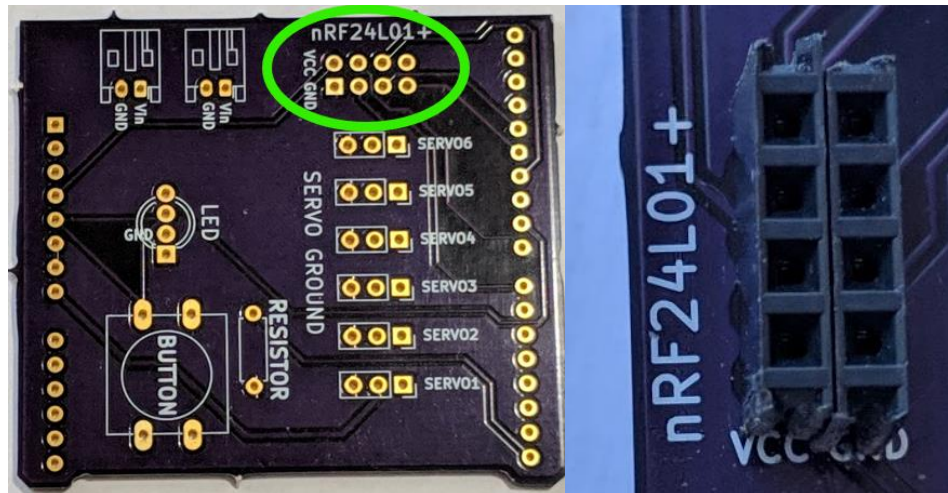
3.1. Components

The required components for assembling this device are in the following table.

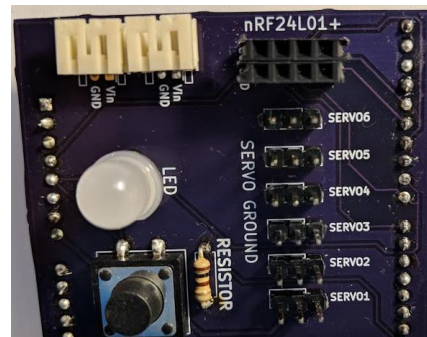
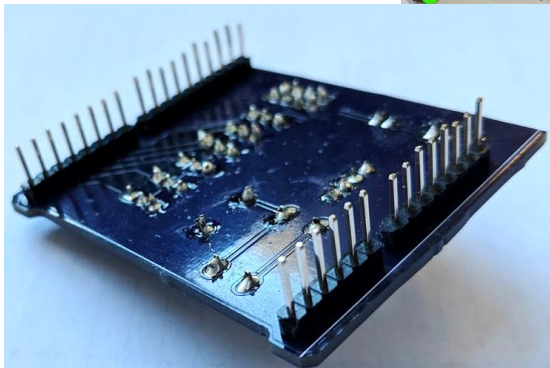
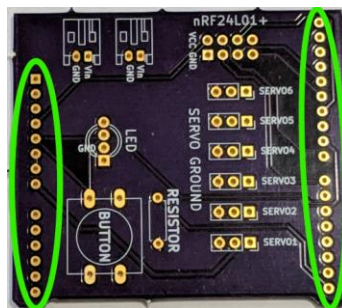
Component	Quantity	Image	Link to purchase
Rosin Core Solder	1		homedepot.com/p/Bernzomatic-0-5-oz-Rosin-Core-Solder-327788/100494065
Printed Guitar Board PCB	1		Upload the ZIP file containing the .gbr files to oshpark.com
Arduino UNO - R3	1		sparkfun.com/products/11021
nrf24L01+ Transceiver Module	1		amazon.com/dp/B0009O868G/ref=twister_B07434GZWL?encoding=UTF8&psc=1 (Sold in 10pcs)
1Ah Lithium Ion Battery	2		sparkfun.com/products/13813
LiPo Charger Micro USB (requires micro USB cable and wall wart to be used, which are not listed, two could be purchased to charge the batteries at the same time)	1		sparkfun.com/products/10217

JST Vertical Connector	2		sparkfun.com/products/8613
Female Headers	1		sparkfun.com/products/115
Break Away Headers - Straight	2		sparkfun.com/products/116
Electrolytic Decoupling Capacitor - 10uF/25V	1		sparkfun.com/products/523
FEETECH FS90R Micro Continuous Rotation Servo	6		pololu.com/product/2820/specs
100Ω Resistor	1		sparkfun.com/products/14493
Momentary Pushbutton Switch	1		sparkfun.com/products/9190

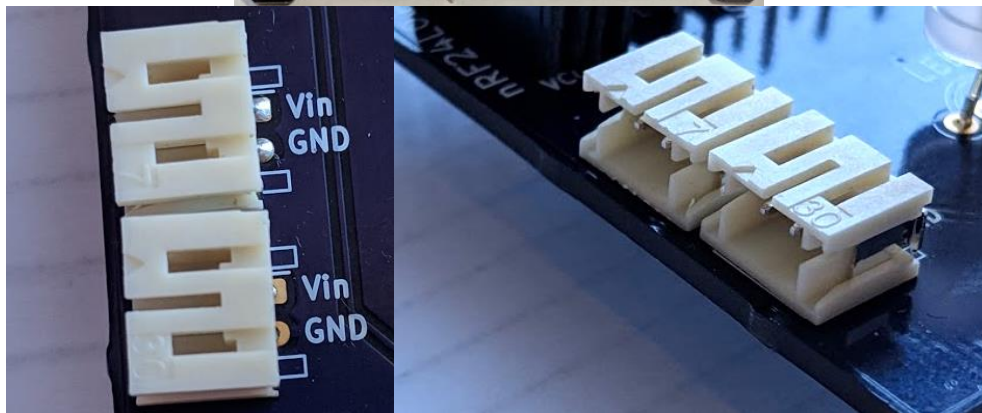
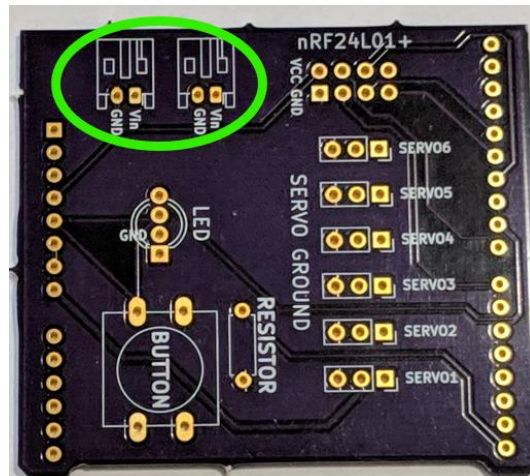
LED - RGB Addressable, PTH, 8mm Diffused	1		sparkfun.com/products/ 12877
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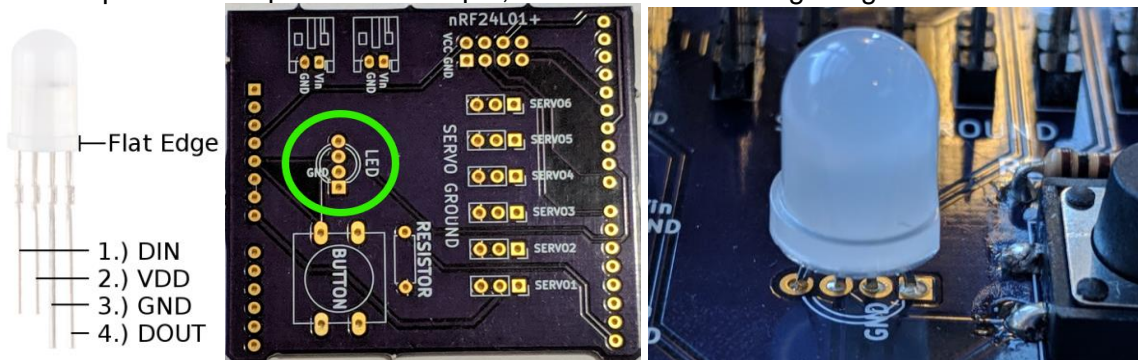
8. Solder the two 10 pin, two 8 pin, 6 pin sections of male headers by plugging the short side of the header up into the PCB and leaving the long side of the PCB to face out the other side of the board. See the following images to see what this looks like on both sides of the PCB.



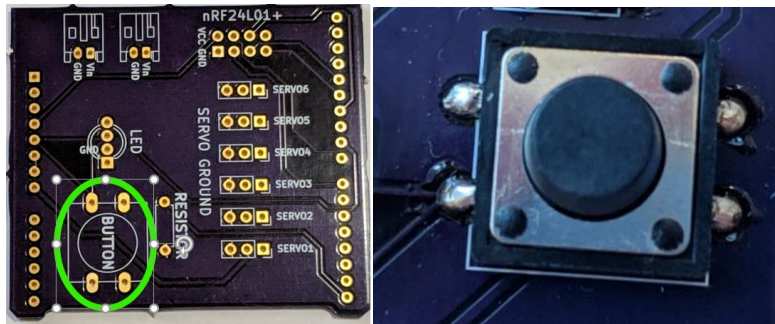
9. Solder the JST vertical connector into the holes marked Vin and GND such that the plug is facing out of the PCB as shown in the following images.



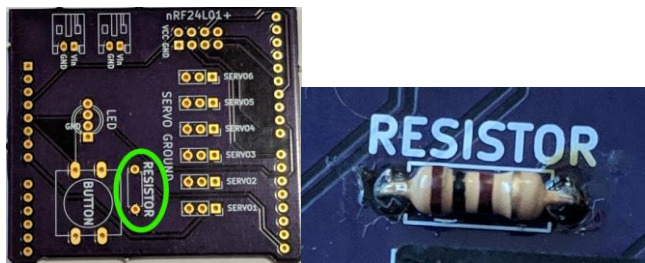
10. Separate the leads of the LED such that it will plug into the PCB. Trim the leads such that a solderable amount is left on the other side of the board. Plug the LED into the PCB such that the flat edge of the bulb is facing towards the spot for the button. The GND pin will line up with labelled pin, shown in the following images



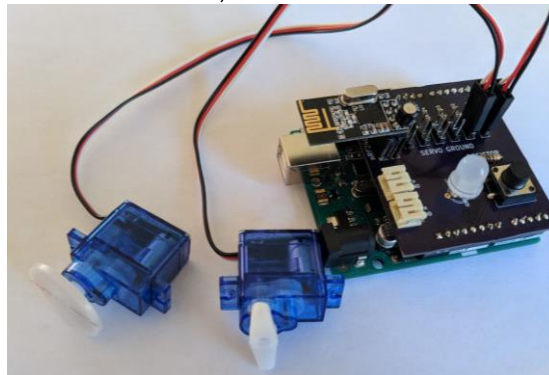
11. Plug the button into the square labelled for it. It will require some force to do this. Solder all 4 pins of the button to the PCB, shown in the following image



12. Bend the resistor leads such that it will plug into the holes labelled for it. Trim the leads such that a solderable amount is left on the other side of the board, shown in the following image



13. Plug the PCB into the Arduino UNO, and the nrf24L01+ and servos into the PCB!



Appendix O: UI User’s Guide

1. Setting Up the Arduino Software IDE

1.1. Download

To program the Arduino boards, the software is needed to run the supplied program files.

Go to the Arduino website’s Getting Started page: arduino.cc/en/Guide/HomePage

There is an option to “Code online on the Arduino Web Editor,” but this is not advised as there are many third-party libraries that are required for this project.

Scroll down to the “Install the Arduino Desktop IDE” and follow the instructions for the operating system you own.

1.2. Preparing each Arduino

There are specific setup guides for the Arduino UNO and Pro Mini. Follow both of these such that you have the proper software drivers for each board.

Arduino UNO: arduino.cc/en/Guide/ArduinoUno

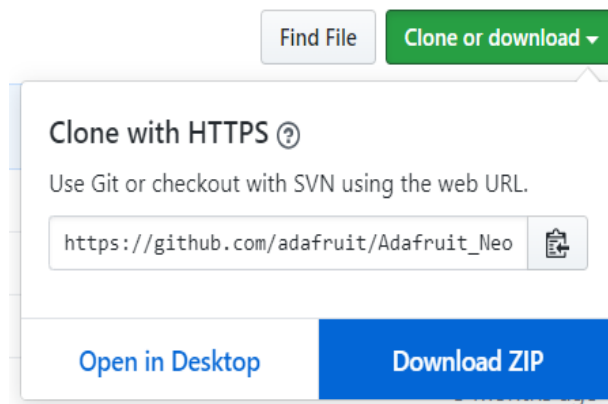
Arduino Pro Mini: arduino.cc/en/Guide/ArduinoProMini

1.3. Setting up Libraries

For both the guitar and wearable devices, third party code libraries are needed. You can put these in the Arduino Libraries folder on your computer to make them accessible to any Arduino programs that you write.

When the Arduino IDE was installed, this folder was created in your documents. Navigate here with the file path Documents → arduino → libraries. Unzip the libraries here.

To download a library from GitHub, click the green “Clone or Download” button on the right part of the page, and choose “Download Zip,” as shown in the following figure.



For the guitar device, download these libraries:

- Arduino NeoPixel: github.com/adafruit/Adafruit_NeoPixel
- Arduino Thread: github.com/ivanseidel/ArduinoThread
- Circular Buffer: github.com/rlogiacco/CircularBuffer

For the wearable device, download these libraries:

- SparkFun MPU-9250 9 DOF IMU Breakout: github.com/sparkfun/SparkFun_MPU-9250_Breakout_Arduino_Library

Libraries used by both components

- RF24: github.com/nRF24/RF24
- RF24 Network: github.com/nRF24/RF24Network

2. Programming the Wearable Devices

2.1. Download the Code

Download the final_wearable_device.zip from this folder:

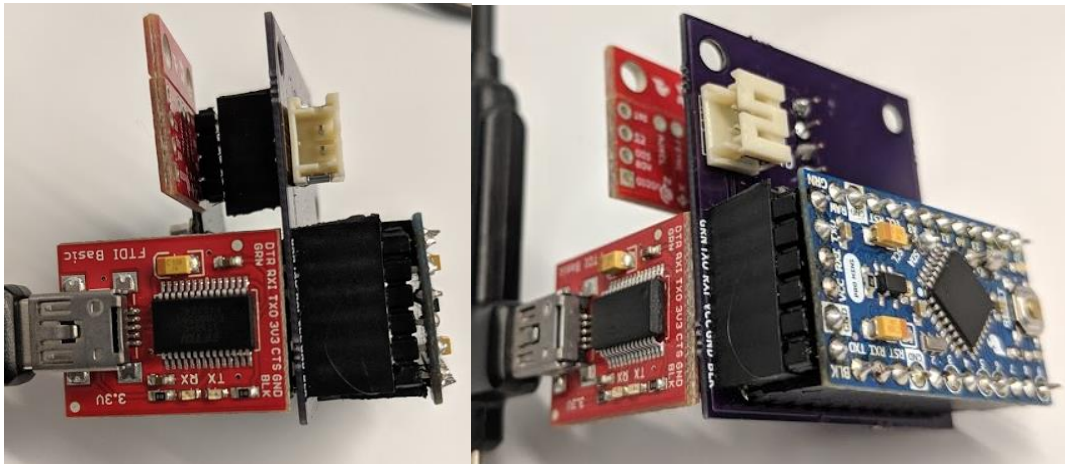
<https://drive.google.com/drive/folders/1-QPQxh47PpdBu0v1Eli7cAf32kYZGA2?usp=sharing>
and save it to the Documents → arduino folder.

2.2. Opening the Project

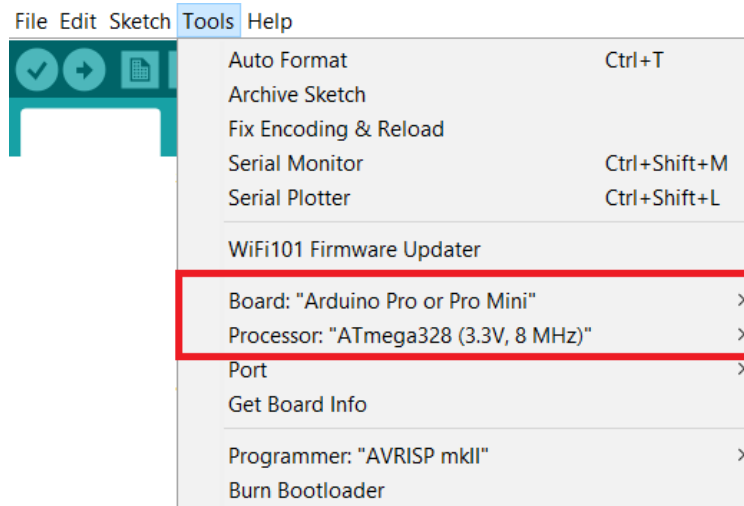
Open final_wearable_device.ino project.

2.3. Uploading Code to the Arduino Pro Mini

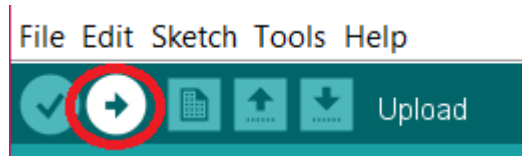
To program the device, plug the FTDI Basic Breakout into the stackable header pins facing the top of the board, such that the BLK, GND, VCC, RXI, TXO, GRN pins match up, shown below.



Then plug the FTDI Basic Breakout into a mini USB cable and into a computer. In the Arduino IDE, make sure the settings under the Tools menu match the correct board, as shown in the following image.



Upload the code to the board using the upload button, shown in the image below.



2.4. Running the Device

Once the program has successfully been uploaded to the board, unplug the FTDI board. Plug the battery into the JST connector.

3. Programming the Guitar Device

3.1. Download the Code

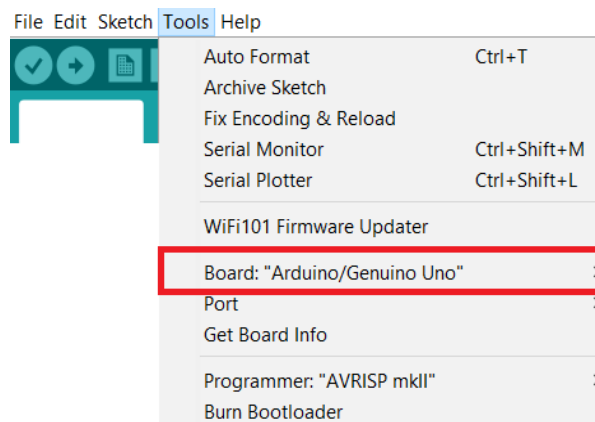
Download the GuitarDeviceCode.zip from this folder: <https://drive.google.com/drive/folders/1-QPQxh47PpdBu0v11Eli7cAf32kYZGA2?usp=sharing> and save it to the Documents → arduino folder.

3.2. Opening the Project

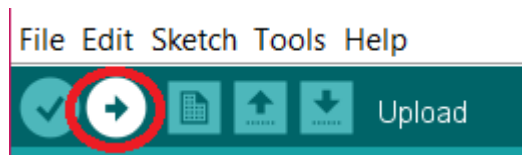
Open GuitarDeviceCode.ino project.

3.3. Uploading Code to the Arduino UNO

To program the device, remove the PCB from the Arduino first. This is important as pins 0 and 1 are being used by the button and a servo, but must share functionality with the USB connection. After removing the PCB, then plug in the USB cable to the Arduino and computer. In the Arduino IDE, make sure the settings under the Tools menu match the correct board, as shown in the following image.



Then, upload the code to the board using the upload button, shown in the image below.



3.4. Running the Device

Once the program has successfully been uploaded to the board, unplug the USB cable. Plug the PCB back into the Arduino and both batteries into the JST connectors. Make sure to plug the batteries in to the PCB before plugging any servos into the board, because the batteries cannot handle the instantaneous current draw of all servos turning on at the same time.

Appendix P: Final Cost and Bill of Materials

Parts	Unit Cost	Quantity	Total Cost	Link
6mm gear	\$2.05	6	\$12.30	https://www.mcmaster.com/2662n27
12mm gear	\$2.09	6	\$12.54	https://www.mcmaster.com/2662n28
2mm shaft (300 mm length)	\$4.32	1	\$4.32	https://www.mcmaster.com/94185a571
0-80 set screws (pkg. of 50)	\$8.78	1	\$8.78	https://www.mcmaster.com/92311a050
M1.6 washers (pkg. of 100)	\$1.44	1	\$1.44	https://www.mcmaster.com/91166a170
M2 washers (pkg. of 100)	\$1.06	1	\$1.06	https://www.mcmaster.com/93475a195
M4 washers (pkg. of 100)	\$2.05	1	\$2.05	https://www.mcmaster.com/91166a230
M1.6 hex nuts (pkg. of 50)	\$9.13	1	\$9.13	https://www.mcmaster.com/90591a109
M2 hex nuts (pkg. of 100)	\$1.12	1	\$1.12	https://www.mcmaster.com/90592a004
M1.6 socket-head screws (pkg. of 25)	\$8.16	2	\$16.32	https://www.mcmaster.com/91292a311
Servo motors	\$4.95	6	\$29.70	https://www.pololu.com/product/2820/specs
4mm shaft (3D printed)	\$0.45	6	\$2.70	
Plectrum (3D printed)	\$0.30	6	\$1.80	
Motor Frame (3D printed)	\$2.25	6	\$13.50	
Gear Frame (3D printed)	\$2.55	6	\$15.30	
Gearshaft Mount (3D printed)	\$1.35	6	\$8.10	
Baseplate (Laser-cut)	\$10.00	1	\$10.00	
IMU Casing Top (3D Printed)	\$1.40	2	\$2.80	
IMU Casing Bottom (3D Printed)	\$1.68	2	\$3.36	
Poplar 1"x2"x8' Board	\$10.16	2	\$20.32	
Sheetrock Screw 2 1"	\$6.97	1	\$6.97	
Sheetrock Screws 2"	\$6.97	1	\$6.97	
Threaded Rod 3/8"x24"	\$1.97	1	\$1.97	
Wing Nut 3/8" 16 tpi	\$1.18	4	\$4.72	
Nut 3/8" 16 tpi	\$2.97	1	\$2.97	
Washers 3/8"	\$3.45	1	\$3.45	
Mouse Pad	\$4.99	1	\$4.99	
Low-Profile Sleeve Bearing Carriages	\$0.05	4	\$0.20	
Guide Rail	\$5.35	2	\$10.70	

End Caps (3D printed)	\$2.54	4	\$10.16	
Rosin Core Solder	\$3.97	1	\$3.97	https://www.homedepot.com/p/Bernzomatic-0-5-oz-Rosin-Core-Solder-327788/100494065
Wearable Device PCB (set of 3)	\$10.90	1	\$10.90	https://oshpark.com/
Guitar Device PCB (set of 3)	\$21.55	1	\$21.55	https://oshpark.com/
Arduino Pro Mini 328-3.3V/8MHz	\$9.95	2	\$19.90	https://www.sparkfun.com/products/11114
Arduino UNO - R3	\$22.95	1	\$22.95	https://www.sparkfun.com/products/11021
FTDI Basic Breakout - 3.3V	\$15.50	1	\$15.50	https://www.sparkfun.com/products/9873
IMU Breakout MPU-9250	\$14.95	2	\$29.90	https://www.sparkfun.com/products/13762
nrf24L01+ Transceiver Module (Pack of 10)	\$11.98	1	\$11.98	https://www.amazon.com/dp/B00O9O868G/ref=twister_B07434GZWL?encoding=UTF8&psc=1
400mAh Lithium Ion Battery	\$4.95	2	\$9.90	https://www.sparkfun.com/products/13851
1Ah Lithium Ion Battery	\$9.95	2	\$19.90	https://www.sparkfun.com/products/13813
LiPo Charger Micro USB	\$8.95	1	\$8.95	https://www.sparkfun.com/products/10217
JST Vertical Connector	\$0.95	4	\$3.80	https://www.sparkfun.com/products/8613
Female Headers	\$1.50	5	\$7.50	https://www.sparkfun.com/products/115
Arduino Stackable Header Kit - R3	\$1.50	1	\$1.50	https://www.sparkfun.com/products/11417
Break Away Headers - Straight	\$1.50	3	\$4.50	https://www.sparkfun.com/products/116
Electrolytic Decoupling Capacitor - 10uF/25V	\$0.45	3	\$1.35	https://www.sparkfun.com/products/523
100Ω Resistor (pack of 20)	\$1.20	1	\$1.20	https://www.sparkfun.com/products/14493
Momentary Pushbutton Switch	\$0.50	1	\$0.50	https://www.sparkfun.com/products/9190
LED - RGB Addressable, PTH, 8mm Diffused (pack of 5)	\$2.95	1	\$2.95	https://www.sparkfun.com/products/12877
TOTAL:			\$428.44	