

# Daily Meeting (24.03.2026)

**Attendees:** Pierre-Yves, Alexandre, Jeremy, Cédric, Marco, Nathan, Kevin, Louis

**Location:** 23N415 | **Time:** 9h05-9h40 | **Scribe:** Cédric

## Kevin

Hier:

- **Improve quality of generated images:** research about FreeU
- Finalized commit PR; Integration GenAI

Ajd:

- Test FreeU Solution to decrease noise of generated texture
- Fine-tuning & Generation of a custom dataset for the training phase of t2t mv-adapter

## Marco

Show:

- **Output of the mv-adapter training:** file and input/output image of the training

Hier:

- Research on training mv-adapter (architecture), this work but we do not have a data train set big enough

Ajd:

- Continue training on mv-adapter model

## Alexandre

Hier:

- **Collage support canard to the wooden plaque:** solve support stability issue
- Plan the promotional site
- Work with GenAI team for prompt engineering

Ajd:

- Continue prompt engineering
- Begin promotion site

## Jeremy

Show:

- Old and new UV map

Hier:

- Redispatch the UV map to avoid point superposition

Ajd:

- Create test for team robot with less points

## Louis

Hier:

- PR for integration interface
- PR from GenAI for integration
- Begin to look for integration

Ajd:

- Integration robot part into main branch
- From **Alexandre**: change color selection -> use toggle on/off

## **PY**

Show:

- Graphs relating to the robotics team's **problems**: large discrepancies between joint positions, resulting in significant robot movements
- Animation computation point on PyBullet

Hier:

- Explore and implement PyBullet planer
  - Okay in the limit of the test

Ajd:

- Possible test on robot
- Continue work on planer

## **Nathan**

Hier:

- Integration robot in Duckify
- Init PR to merge robot code into the main project
- Work on angle optimisation for pathfinding as asked by **Pierre-Yeves**

Ajd:

- Continue angle optimisation for pathfinding

## **Cédric**

Hier:

- Added documentation and type hints
- Review and fix robot integration PR
- Add command line arguments to the main robot function

Ajd:

- Improve arguments for main function

## **Comment**

Retard:

- Traffic accident delayed the start of the meeting.

Comment:

- **Marco to Jeremy**: Possible axes missaligned between old and new UV map model
  - **Answer**: An older model is likely being used; the orientation setting needs to be changed
- **Louis to PY**: What is the total length of the robot?
  - **Answer**: around 70cm