

COMP20170

Position and Orientation Challenge

In this Challenge, you will use everything you've learned related to position and orientation for kinematics to create a robot arm with EV3 that will position itself at the right coordinates and will identify the object to collect and move from position A to position B.

The robot must perform unique actions and calculations for the motors in order successfully grasp and move the object.

You must work in teams to identify the needs for such a task and describe in detail in your journal the position, orientation and the frame in order to locate the object.

Following the material of this topic, you need to calculate the position and orientation of the object (of your choice) relative to the manipulator's hand.

You must submit your journal, code in ROBOTC and a video of your solution.

