NaoGolf比赛(New)

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笔记本：	NaoRobotClub		
创建时间：	2019/11/23 12:39	更新时间：	2019/11/23 16:27
作者：	1349619363@qq.com		
URL：	about:blank		

2019年11月23日：
hitball流程
```
self.GPositionJointNamesR = ["RElbowRoll", "RShoulderRoll",
"RShoulderPitch", "RElbowYaw", "RWristYaw", "RHand"]
self.GgolfPositionJointAnglesR1 = [1.4835298641951802,
0.061086523819801536, 1.4172073526193958, 1.6022122533307945,
0.038397243543875255, 0.12]
```
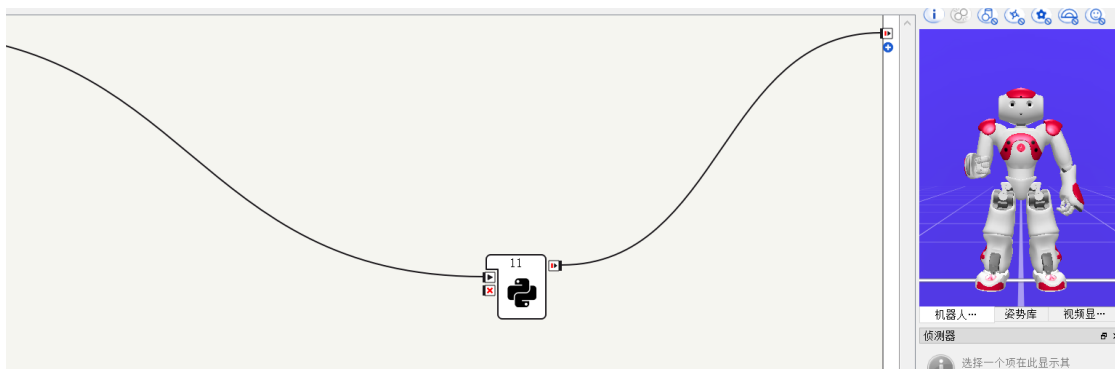


```
self.GgolfPositionJointAnglesR2 = [1.4835298641951802,
0.061086523819801536, 1.1, 1.6022122533307945,
0.038397243543875255,
0.12]
```
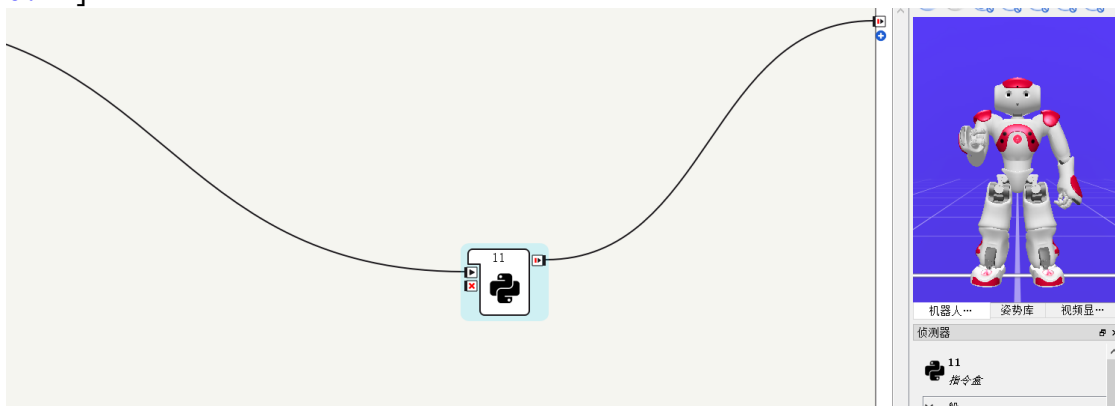


```
self.GgolfPositionJointAnglesR3 = [1.4835298641951802,
0.061086523819801536, 1.4172073526193958,
1.6022122533307945,0.767944870877505, 0.12]
```
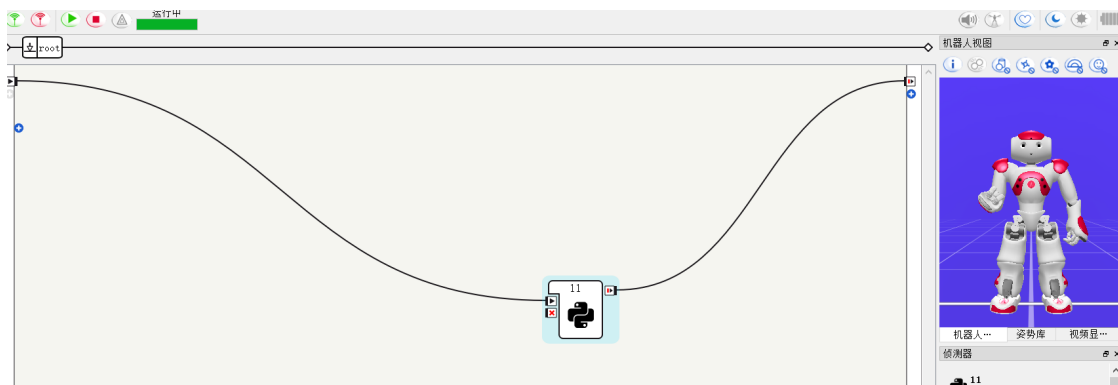
```
self.GgolfPositionJointAnglesR11 = [1.4835298641951802,
0.061086523819801536, 1.4172073526193958,
1.6022122533307945,-0.538397243543875255, 0.12]
```
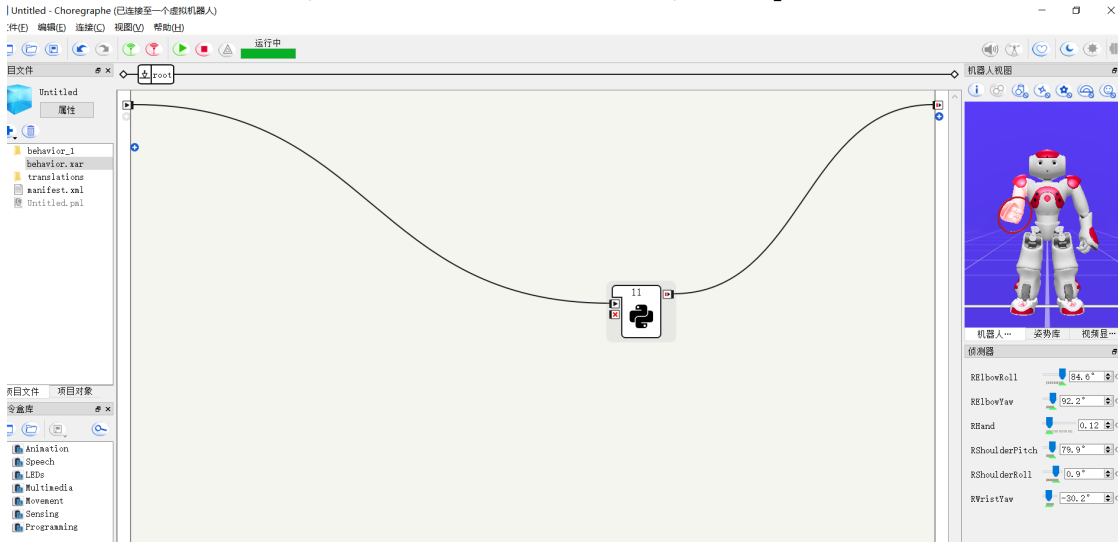


```
self.PositionJointNamesR = ["RShoulderPitch", "RShoulderRoll",
"RElbowYaw", "RElbowRoll", "RWristYaw", "RHand"]
self.golfPositionJointAnglesR5 = [1.35787, 0.05760, 1.50098,
1.50971, 0.0, 0.6]
self.motionProxy.angleInterpolationWithSpeed(self.PositionJointNamesR,
self.golfPositionJointAnglesR5, 1)
```
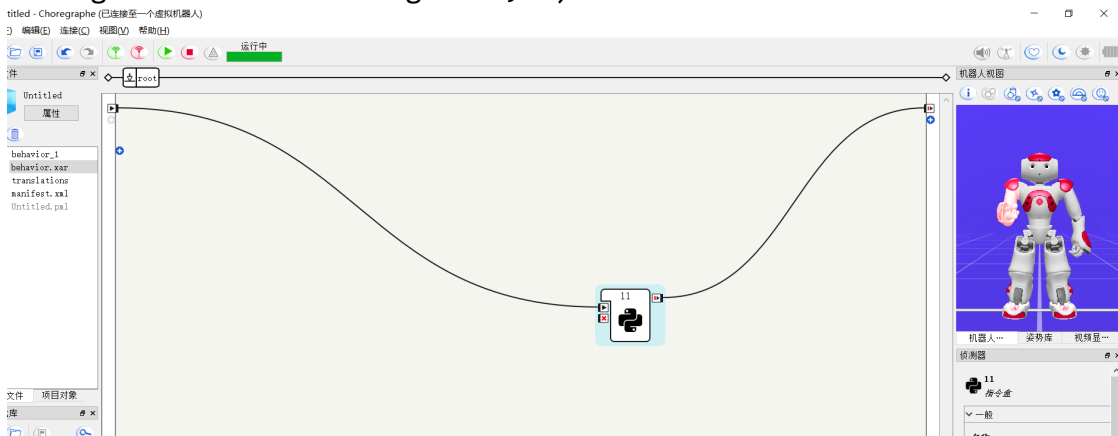


```
self.motionProxy.angleInterpolationWithSpeed(self.PositionJointNamesR,
self.golfPositionJointAnglesR6, 0.1)
self.golfPositionJointAnglesR6 = [1.35787, 0.05760, 1.50098,
1.50971, 0.0, 0.10]
```

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机器人··· 姿势库 视频显···

侦测器

RElbowRoll	85.9°
RElbowYaw	86.5°
RHand	0.59
RShoulderPitch	77.0°
RShoulderRoll	0.9°
RWristYaw	-0.6°