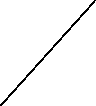
# 1) int Validate\_move(float motor angles[])

Objective : The goal here is to get the angles between two arms. Those angles will be used to calculate if the movement is “valid”. A movement is considered valid if the angles (forward and backwards) between two arms do not exceed their physical limit.

Methodology:

Example with the angles between the L2 and L3 of the robot:



Ө2’ = (180 – 90 - Ө2)

Ө3’ = (Ө3 – 90)

α = 180 – Ө3’ - Ө2’

Eternal angle = 360 - α

# 2)

