Arm Lab-Group 13

2.1 The viable points will be represented by grid, because it is relatively easy to compute intermediate waypoints.

2.2 The robot will reach the goals using Wavefront Planning. The biggest benefit to using Wavefront for this lab is because the configuration created for part 1 made it easy to define the world in part2 by converting the configuration space to a binary grid. We defined ones for obstacles and zeros for reachable space, then performed the Wavefront Planner. Besides, it was useful to use this method since we used Wavefront planning for the Motion Planning lab; it was the most convenient method to update the strategy to fit the arm-lab.

2.3 Using two PID controls with a feed forward; one PID constant for each link.