Report of the second assignment in VU-Robotics

Members:
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- Johannes Schneider
- Matthias Komar

Collaboration Approach:

- **Team Collaboration**:
  - We, Paul, Johannes, and Matthias worked collectively without explicit task divisions.
  - We progressed sequentially, implementing files step by step together.
- **Sequential Implementation**:
  - Firstly we sent all the transformations in coppelia, which was hard, because of the code editor in coppelia
  - Then we moved on to try to communicate with Moveit and make the robot move
  - Lastly we fixed some issues and problems
  - We also fine-tuned some parameters so that Franka the robot does not make many errors and only drops the cubes if there is really no way to move the cubes to the bowl

Difficulties in the project and how we solved them

- hard to find good docs and working examples
- Coppelia code editor was not ergonomic
- Many collision states in the beginning with the cubes
- offset of objects
- objects can not always be placed
- finding "hyper-parameters"
- not reliable at all