Computer Graphics

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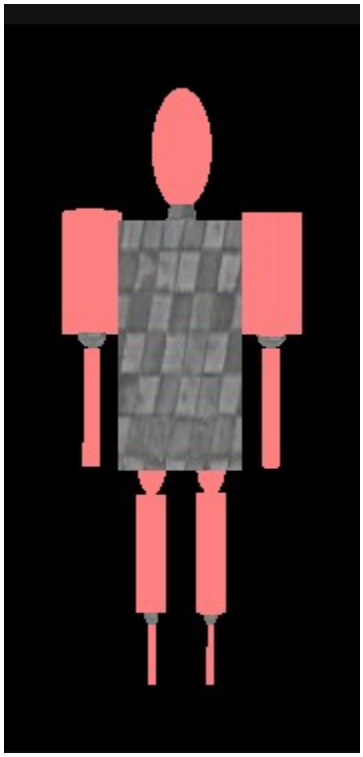
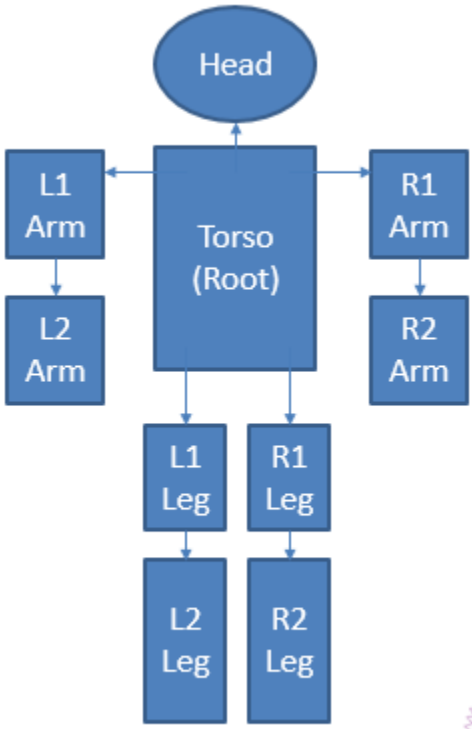
1. **Screenshot**



2. Hierarchy Diagram



I followed the hierarchy diagram in the specification sheet given in the powerpoint, where I use a sphere as pivot to act like a joint for the robots. The only difference is that I did not use a pivot to attach the upper part of the arms to the torso, and directly attached to the body as I found that it was functionally similar

3. Functions in Program, IDE, and version

In the program, there is multiple functions that are important:

Update animations - This function will play the animation and i s triggered by pressing the **‘P’ key** which will play an animation to set the robot to a ‘ready’ position

Reset positions - This function does the opposite of update animations and animates it going back to the ‘resting’ position, and is triggered by pressing the **‘L’ key**

Mouse_callback - This function allows us to move the mouse and help control the camera

Process_input - Takes in the input to trigger animations

Create_shader- streamlines the process of creating shaders

How to run:

1. Download all the necessary files
2. Make sure all the libraries are imported correctly (this should already be the case if you are downloading my code folder and extracting it)
3. Click the ‘local window debugger’ button in Visual Studio

IDE used - I used Visual Studio 2019 when running the program, and I used some libraries, which includes glm, stb, glfw, and glad.