1. What cobot would be best fitted for the client between the:

	UR10e	UR3e	CRX-10iA	M1013	H2515
reach (mm)	1300	500	1249	1179	1379
payload (kg)	between 4 and 10	between 3 and 1	10	between 6 and 10	between 15 and 25

With the information we have, I chose the UR10e for three main reasons. First, the reach and the payload are within the specifications. Second, the UR is the most widely used arm. This facilitates the maintenance of the robot and it can be easily replaced by another UR arm if needed because they use the same system. Third, with the gripper I chose, we know it will be functional and quick to set up.

2. What gripper or grippers do you think would work for this solution?
You can select any grippers, or you can use the gripper documentation provided with the take home. Justify your selection.

I would be using the ROB-SET ECBPi UR gripper because with the same system, it would be able to grab the cube and the cardboard. We would only need to change from one suction cup for the cube to the 4 suction cup for the cardboard.

3. Describe the calibration procedure that an operator can go through on a daily basis after moving the tables in the application footprint.

The calibration would be the same for the two tables. First we will find a 2D vector for the two closest sides of the table to the robot. To do that, the robot would need to touch at two different positions on one specific side. Repeat for the other side. Each pair of positions gives us a vector of this side of the table. With the pair of vectors and the size of the table, we can establish the position of the table.