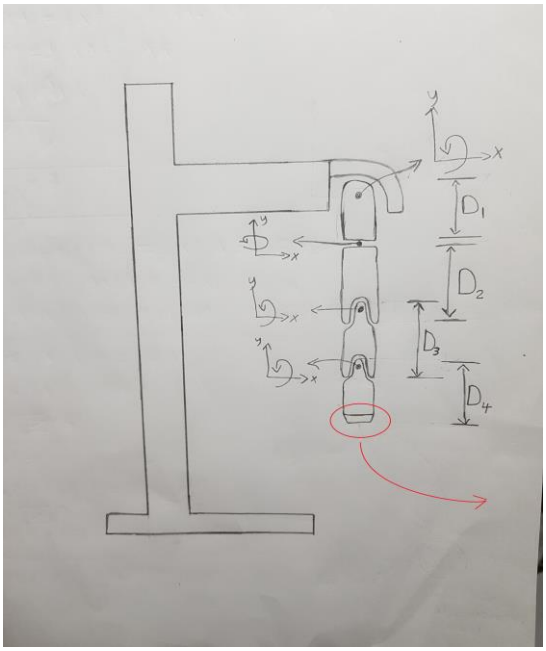
Requirement:

Controlled Robotic Arm mounted on a fixed T-shaped structure.

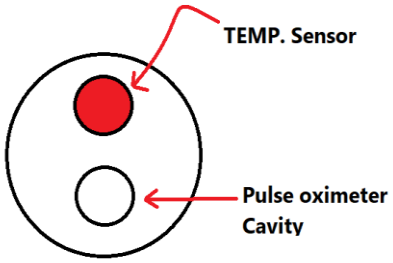
THE MAIN TARGERT IS:

Control the robot arm and move it in points (X, Y, Z) in space.

Embedded in the arm an IR temperature sensor + a cavity for a pulse oximeter sensor.



Robotic Arm



The end of the arm at which the sensors will be embedded.

Suggested total length of the arm is 65 cm:

- Part1: 15 cm
- Part2: 20 cm
- Part3: 15 cm
- Part4: 15 cm

Degree of freedoms:

illustrated in the diagram.

Expected behavior:

The arm is expected to go from point (X_A ,Y_A , Z_A) to point(X_B ,Y_B , Z_B) in space, to **illustrate** this **controlled** movement the arm will move to a point where it can take the patient temperature, also we can move the arm to a specific point and then the patient will be asked to put his/her finger in pulse oximeter cavity to take the heart rate reading.