[Company name]  [Company address]

Library Bot documentation

Contents

[To do 2](#_Toc101351073)

[Code structure 3](#_Toc101351074)

# To do

* Get DH parameters for robot and make class in Matlab (Patrick)
* Setting up environment (Nick)
* Setting up functions (Nhan)

# Code structure

Hans cute class:

* Create robot (constructor with base location)
* Set base location (alternative to above)
* Get current end effector position (fkine)
* Grab function (for end effector)
* Get grab status
* Get position of EVERY joint (useful for collision detection)
* Set joint limits
* Collision detects with surface (input surface [by vertexes?])