[Company name]  [Company address]

Library Bot documentation

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# 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) | **Done** |  |
| Set base location (alternative to above) | **------** | Already a model.base() function by default |
| 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?]) |  |  |

* Create robot (constructor with base location) DONE
* 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?])