

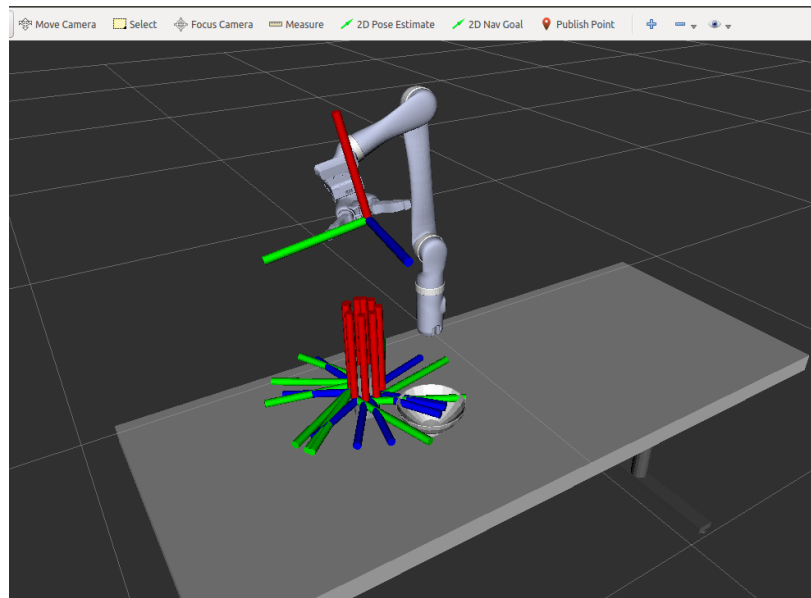
CSCI 545 – Introduction to Robotics

Lab 4 - Planning in Task-Space Regions

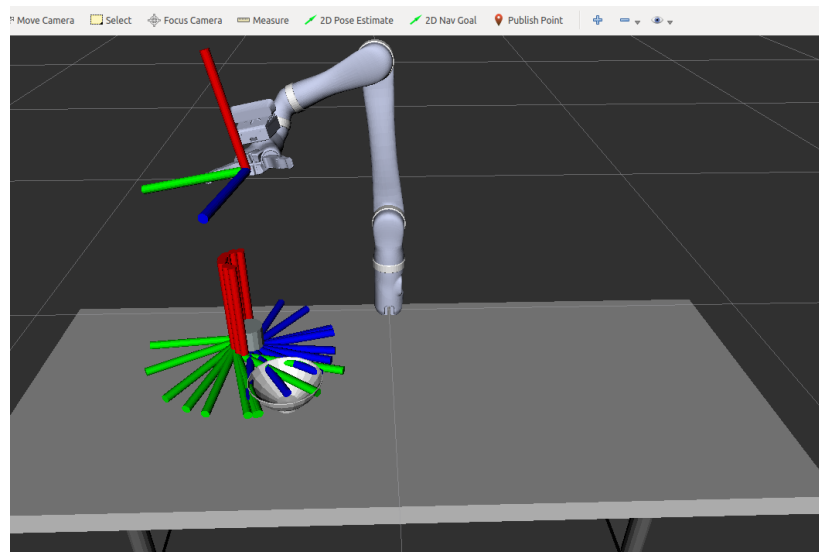
Team 17 - QuirkyBot

Zishen Wei - Jiashang Cao - Srija Madarapu - Mahya Gheini - Zhen Qin

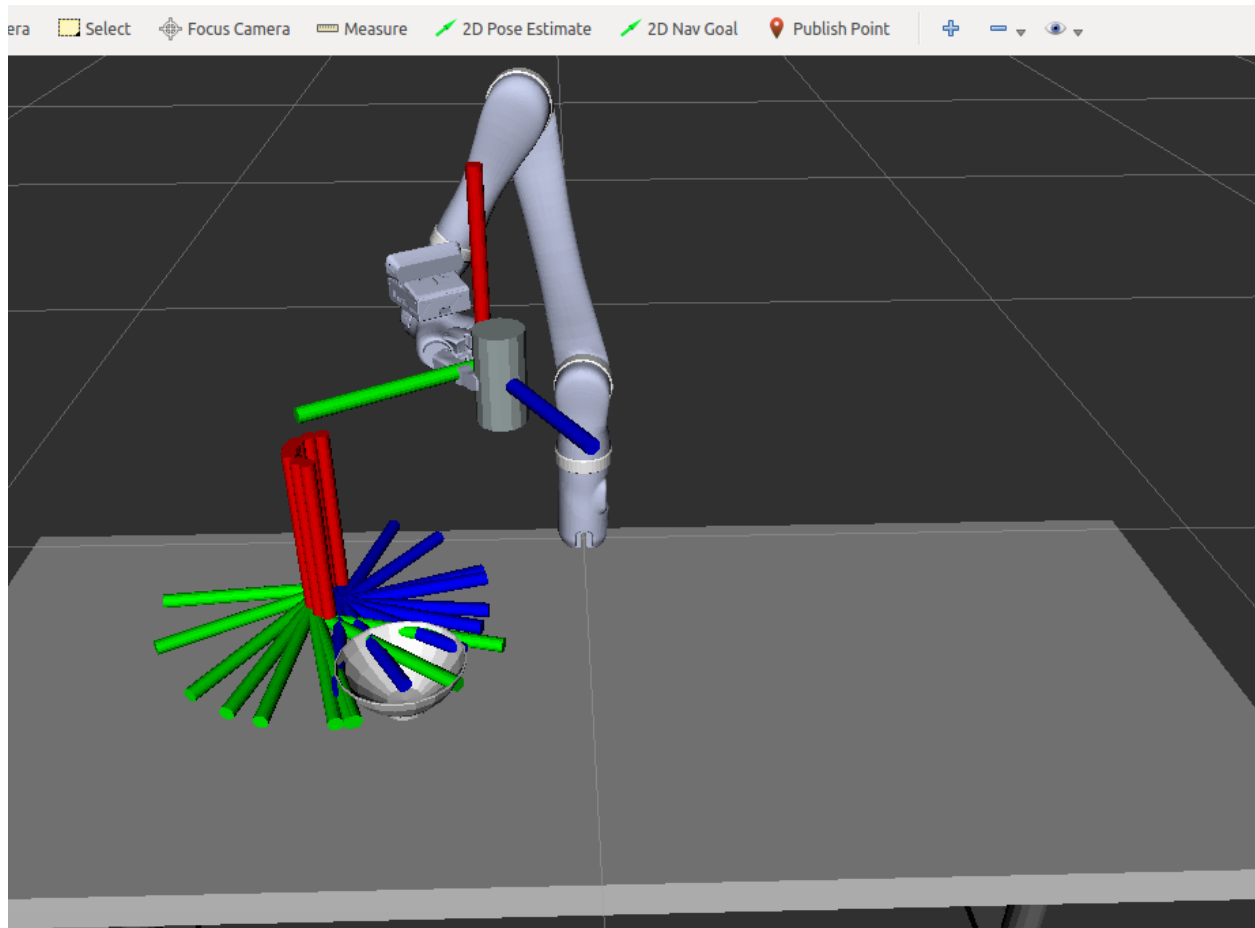
2. tsr_vis_1.png



3. tsr_vis_2.png



6. jac_vis_1.png



The final pose of the can looks a bit off from the expected location. It lifts the can up but also makes a horizontal displacement.

This is because we assume the Jacobian remains the same when the arm is moving. However, it will change as the configuration of the arm changes. Instead, we should move the arm through iterations of small displacement.