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| Issue No. | Position | problem | Remarker |
| 1 | Notebook 4.1 | Function trannimate(T0, T1) | Bug for multi inputs |
| 2 | Notebook 4.1 | Function tr.jtraj() | Optional variables don’t work |
| 3 | Notebook 5.1 | eval | Doesn’t support symbolic calculation |
| 4 | Notebook 5.1 | Toolbox doesn’t have Planar1 model(DH robot model ) |  |
| 5 | Notebook 5.2 | eval |  |
| 6 | Notebook 5.3 | Transl2 | Transl2 in spatialmath doesn’t support symbolic calculation |
| 7 | Notebook 5.6 | The base of the robot model can’t be changed |  |
| 8 | Notebook 6.1 | Ikine\_a doesn’t match ikine6s in matlab well |  |
| 9 | Notebook 6.1  Notebook 6.2  Notebook 6.3 | ikine\_a | Can’t get the solution for the HTM in the pdf file |
| 10 | Notebook 6.4 | hyper3d(20) | Can’t find this function in the toolbox |
| 11 | Notebook 7.1 | Vellipse doesn’t work |  |
| 12 | Notebook\_dynamics | twolink | Missing twolink model in the toolbox |
| 13 | Notebook 8.1 | simulink |  |
| 14 | Notebook\_Control | Simulink |  |