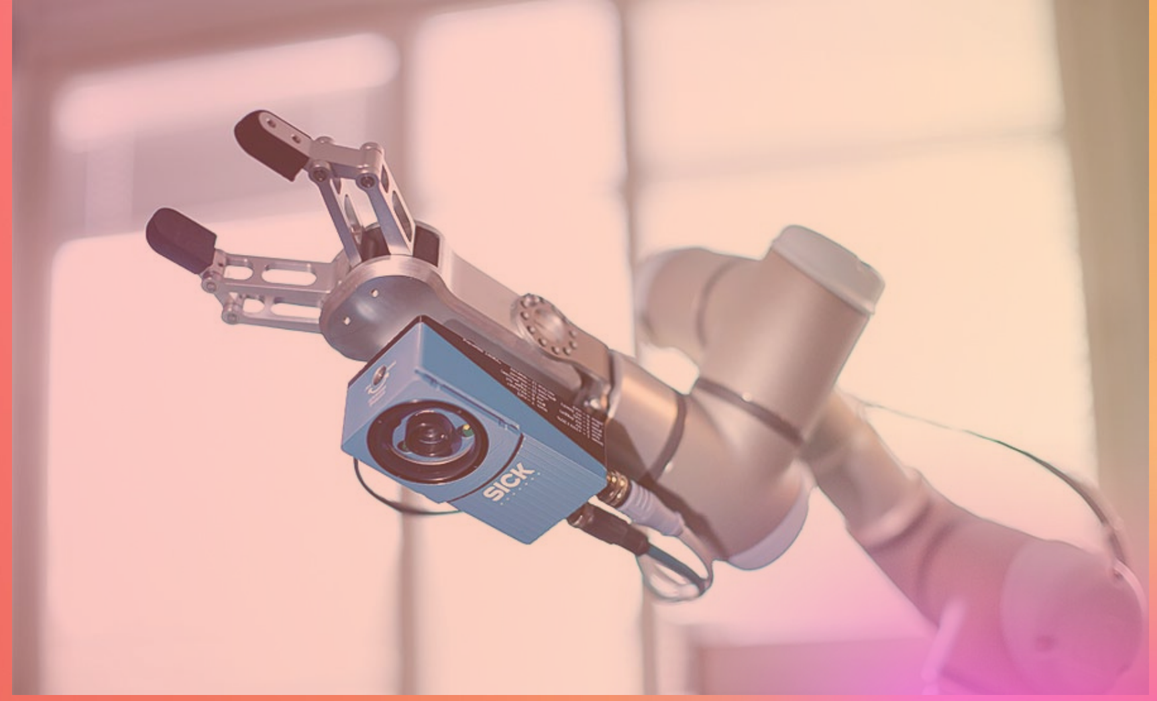
01

INVERSE KINEMATICS SOLVER FOR 6 DOF MANIPULATOR



ACME ROBOTICS
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PHASE-I STATUS | OCTOBER 18, 2021

Deliverables for Phase-I

OBJECTIVE 1

Implement Skeleton Code and implement IK Solver.

OBJECTIVE 2

Create a test suite for all the methods and classes.

OBJECTIVE 3

Verify the output using FK Solver and simulate the output.

Design and Development

- Revised UML and Activity diagram after design iterations.
- Developed IK solver using modern C++ with Test-Driven Development
- Used Continous Integration tools such as travis and coverall to check build errors
- Maintained Version Control System using git
- Created a test suite using google unit tests

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Project Timeline

SPRINT-1

Proposed a Solution for the manipulator IK Solver.

SPRINT-1

Developed an IK solver baseline model

SPRINT-2

Simulating the IK Solver trajectory.

SPRINT-2

Verifying and Release the Software

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THANK YOU!

LET US KNOW IF YOU HAVE QUESTIONS
OR CLARIFICATIONS.