Assignment 6 – ECE4560

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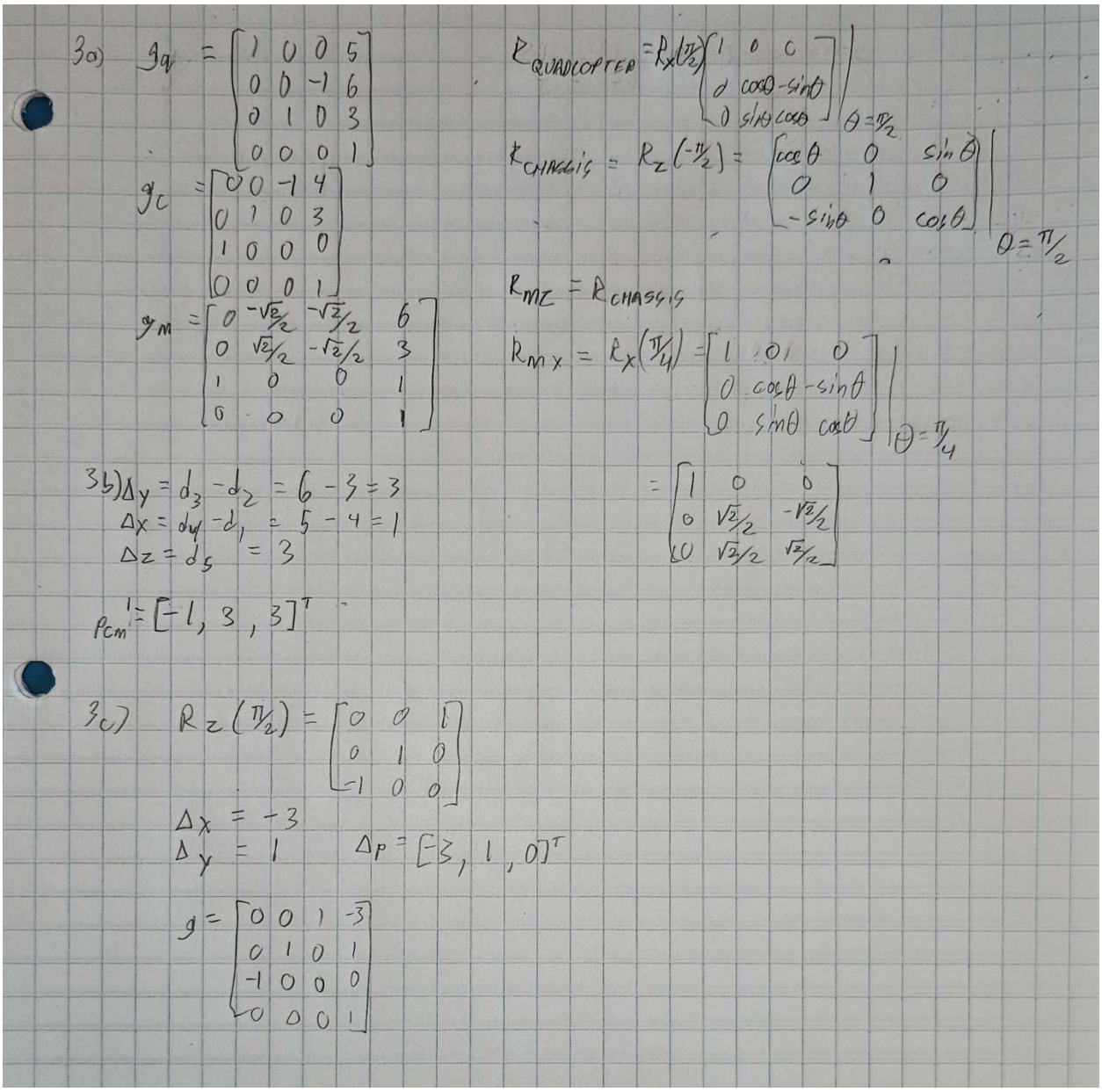
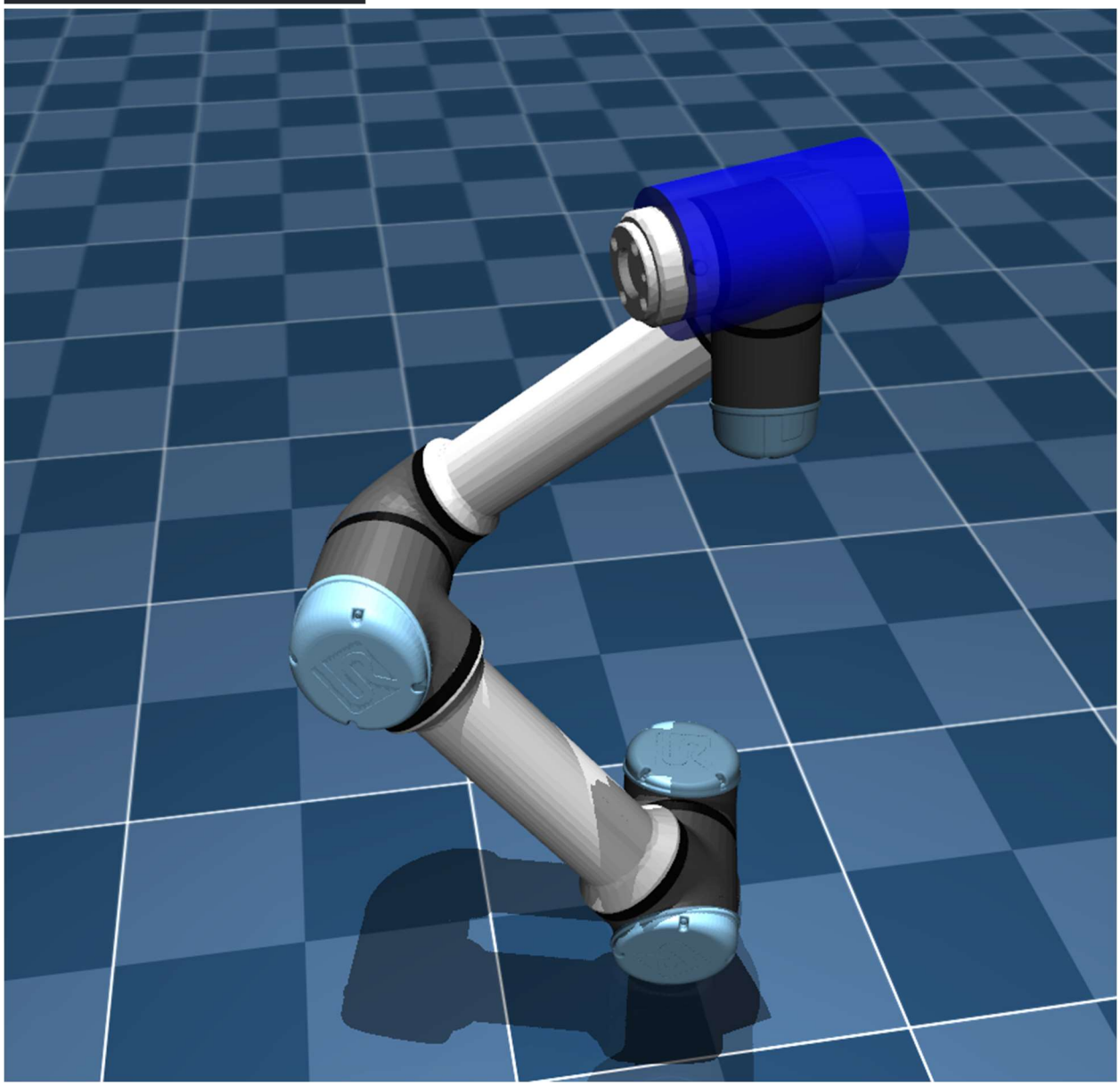
1. 5 hours
2. Completed the survey.



4.

```python
# Obtain all Rotation Matrices
R1 = rot_z(theta1) # This rotation is in
R2 = rot_y(theta2)
R3 = rot_y(theta3)
R4 = rot_y(theta4)
R5 = rot_z(-theta5)
R6 = rot_y(theta6)

# Obtain all Displacement Vectors
d1 = np.array([[0], [0], [0.163]]) # This
d2 = np.array([[0], [0.138], [0]])
d3 = np.array([[0.425], [-0.131], [0]])
d4 = np.array([[0.392], [0], [0]])
d5 = np.array([[0], [0.127], [0]])
d6 = np.array([[0], [0], [-0.1]])
# dt = np.array([[0], [0.1], [0]])
```



5. Rodrigo went to perform the checkoff for our group.

Finishing the robotic arm code was relatively straightforward, all we had to do was write the get_xx() functions to gain the transformation matrices based on the robot definition of each frame for each DOF.