Automation and robotic project 1

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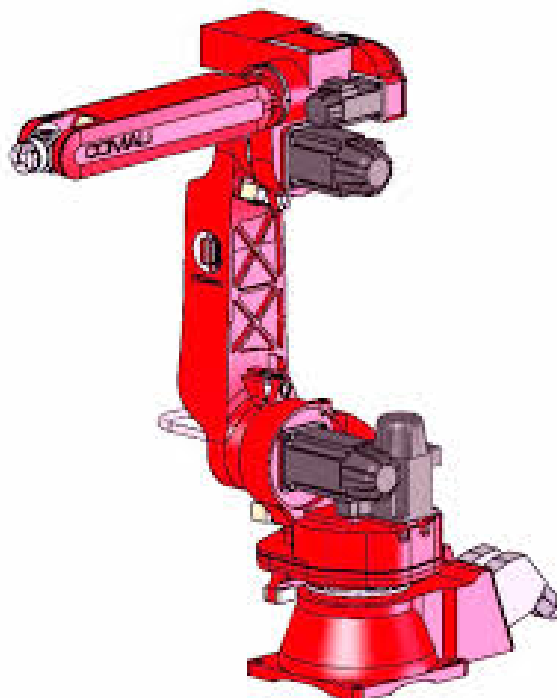
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Chapter 1

Introduction

In this project we apply the theory seen in automatic and robotic course. The aim is creating a function that returns the most important parameters for moving the end-effector of the robot. We can see it on the figure 1 with it's own axes "ANS". This parameters are the position and the orientation of the end-effector, the rotation matrix of the end-effector and the roto-translation matrix for the different input parameters (angles and translations of the joints).
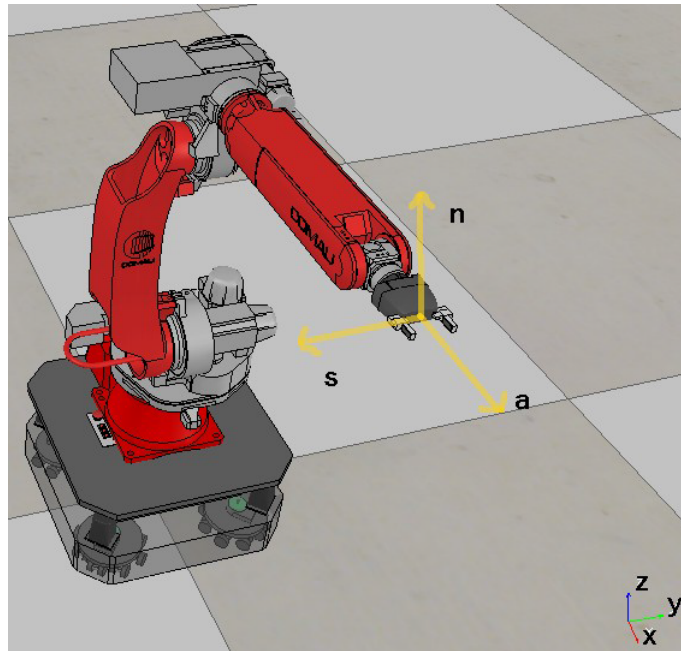

Figure 1.1: Robot smart5 six with a pince on the end-effector

The notions aboarded are roto-translation matrices,

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