

## Lap1\_Group1\_Volunteer\_25

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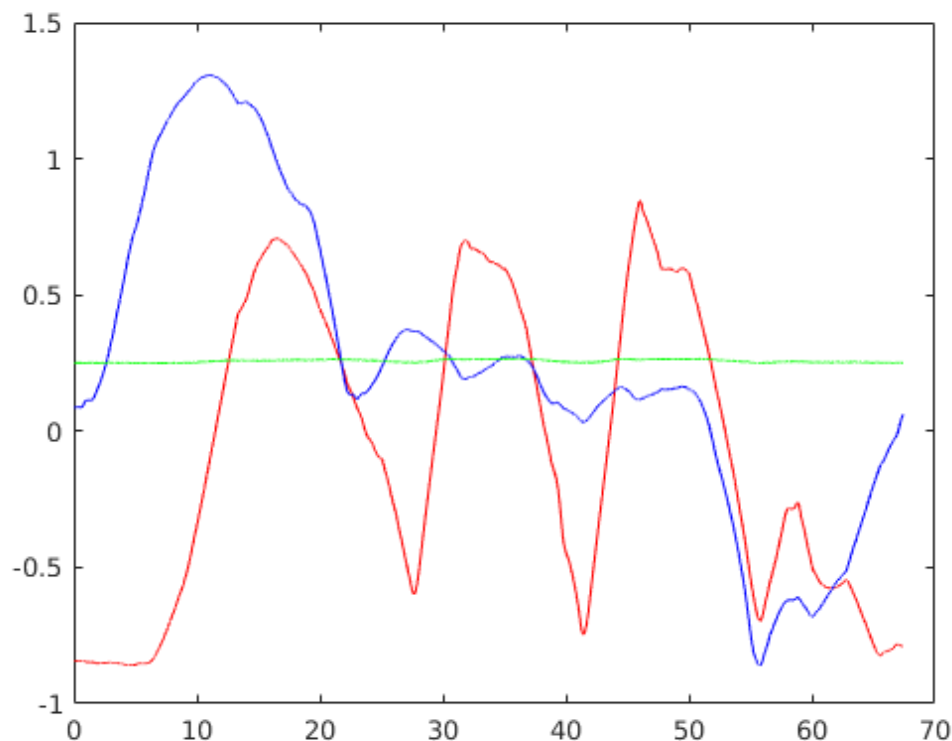
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- Plotting Linear Position of the Robot from Motion Capture data
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- Plotting Linear Acceleration of the Wrist on axis X, from Smartwatch Data
- Plotting Angular Velocity of the Wrist about axis Z, from Smartwatch Data

### Plotting Linear Position of the Robot from Motion Capture data

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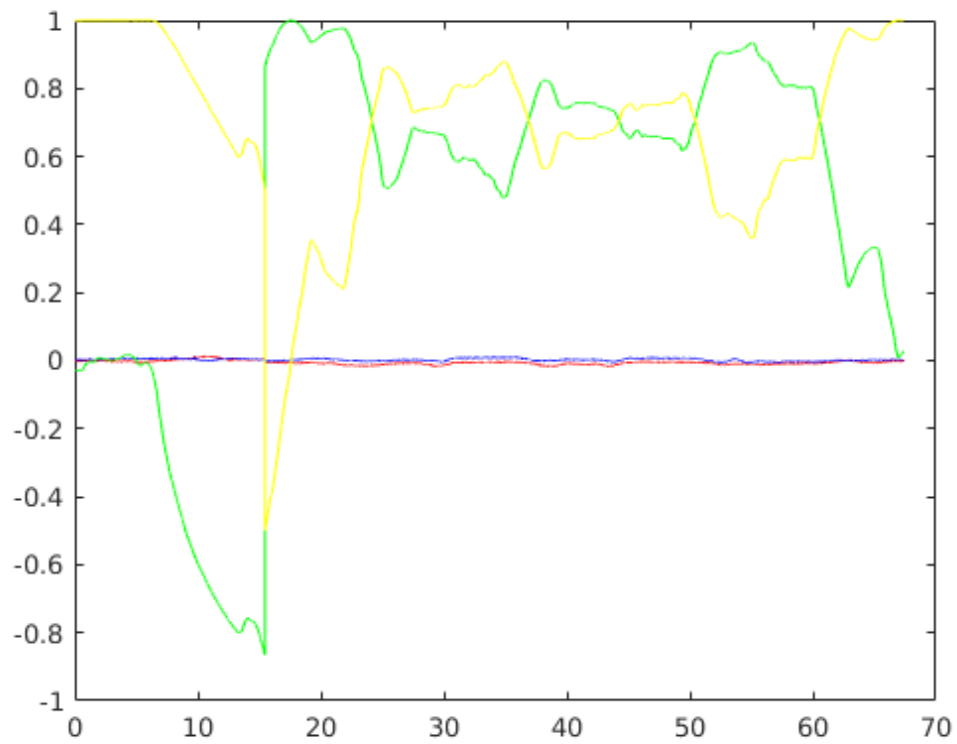
```
plot(dataMoCap.time,dataMoCap.pos_x,'color','r','DisplayName','pos_X'); hold on;  
plot(dataMoCap.time,dataMoCap.pos_y,'color','b','DisplayName','pos_Y'); hold on;  
plot(dataMoCap.time,dataMoCap.pos_z,'color','g','DisplayName','pos_Z');
```



### Plotting Orientation of the Robot from Motion Capture data

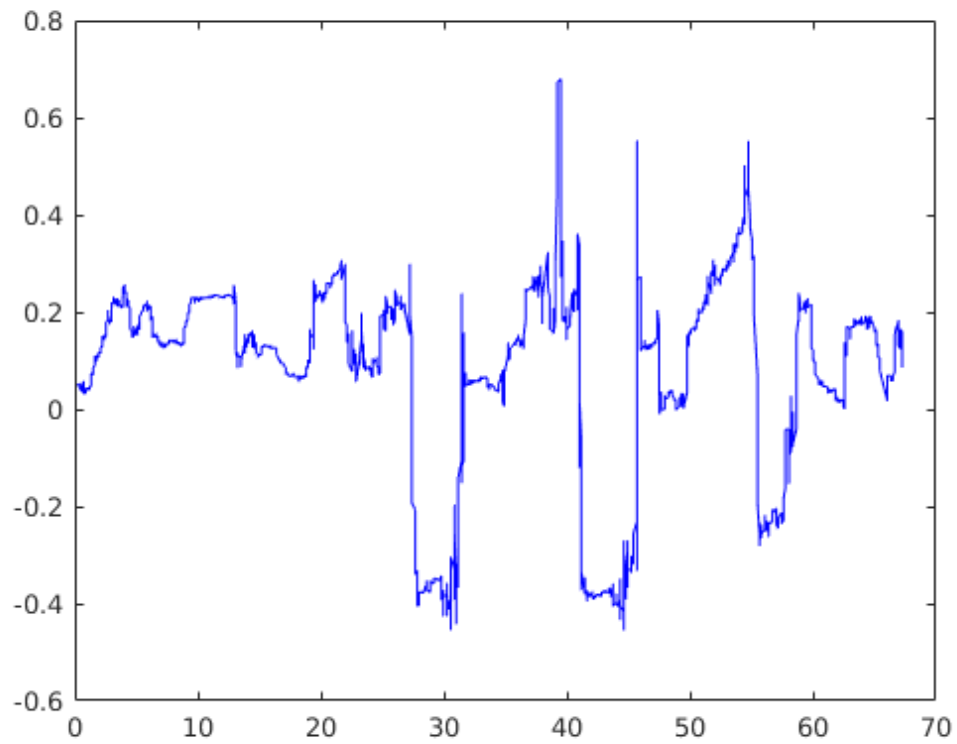
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```
figure;  
plot(dataMoCap.time,dataMoCap.ori_x,'color','r','DisplayName','ori_X'); hold on;  
plot(dataMoCap.time,dataMoCap.ori_y,'color','b','DisplayName','ori_Y'); hold on;  
plot(dataMoCap.time,dataMoCap.ori_z,'color','g','DisplayName','ori_Z'); hold on;  
plot(dataMoCap.time,dataMoCap.ori_w,'color','y','DisplayName','ori_W');
```



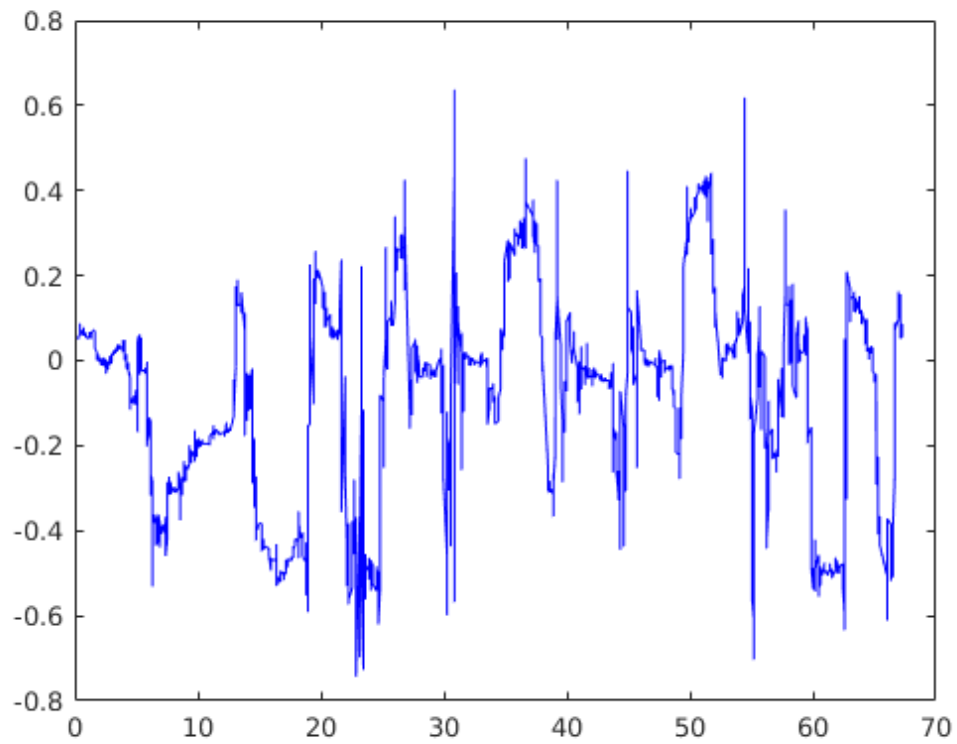
### Plotting Linear Acceleration of the Wrist on axis X, from Smartwatch Data

```
figure;  
plot(dataCommand.time,dataCommand.l_vel_x,'color','b','DisplayName','Accel_X');
```



### Plotting Angular Velocity of the Wrist about axis Z, from Smartwatch Data

```
figure;  
plot(dataCommand.time,dataCommand.a_vel_z,'color','b','DisplayName','AngVel_Z');
```



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*Published with MATLAB® R2017a*