

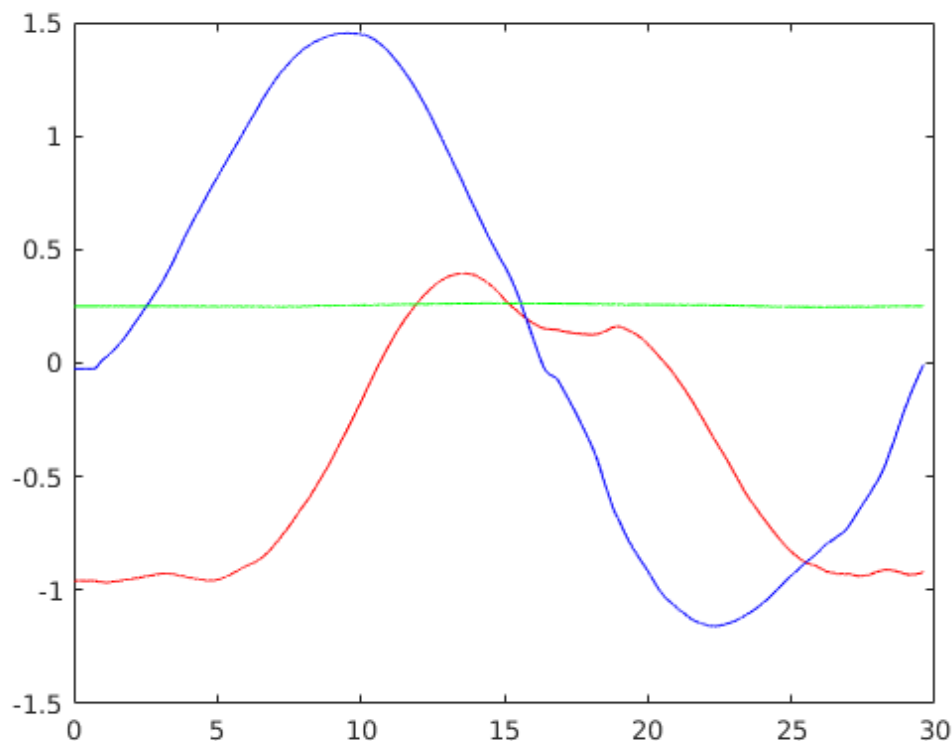
Lap1_Group3_Volunteer_11

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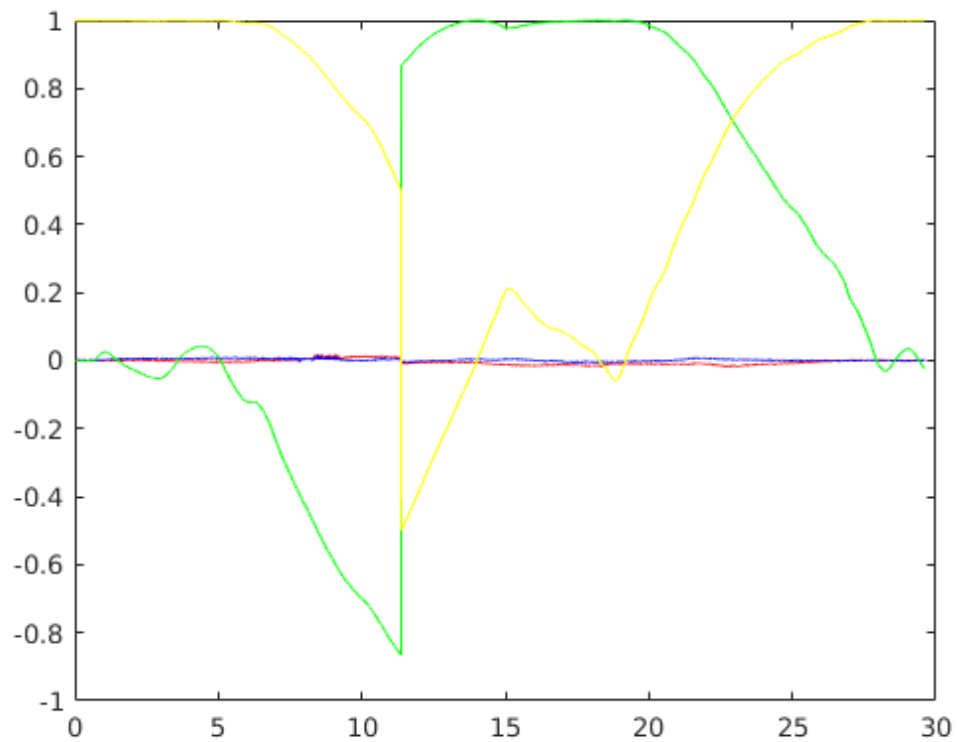
Plotting Linear Position of the Robot from Motion Capture data

```
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');
```



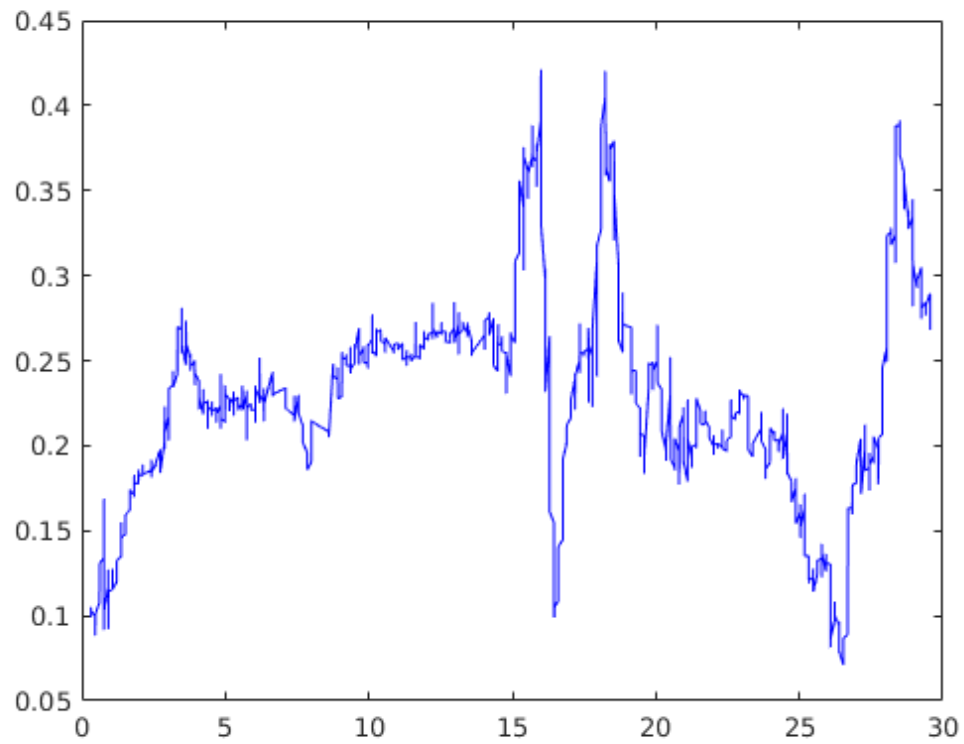
Plotting Orientation of the Robot from Motion Capture data

```
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');
```



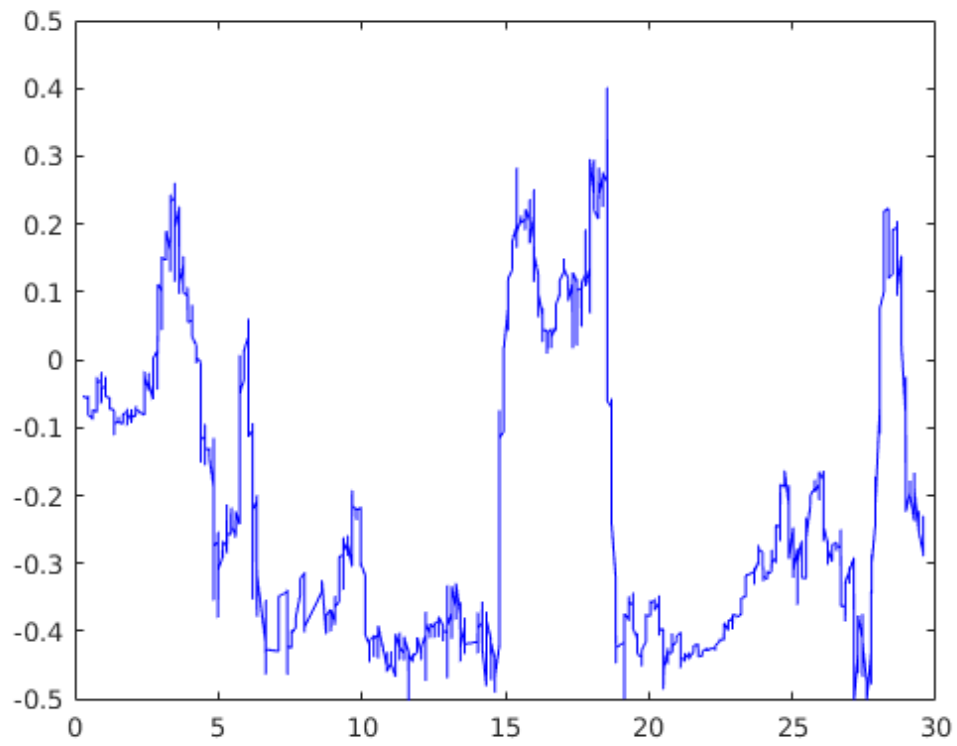
Plotting Linear Acceleration of the Wrist on axis X, from Smartwatch Data

```
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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