

Iman's ***ROS*** to-do list

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October 22, 2018

1 November 2018

• BEFORE THE PRESENTATION

- ☐ Create ROS URDF for IRB1400
- ☐ Create a ROS node to provide service to do inverse kinematics
- ☐ Create a ROS node to subscribe to service
- ☐ verify the solution for forward kinematics and inverse kinematics in matlab
- ☐ Create a ROS node to calculate forward kinematics and inverse kinematics
 - ☐ Orientation and the solution for Euler, RPY and Rodrigues formula
- ☐ Create ROS launch file
- ☐ Create A demo with your sensors
- ☐ Start Presentation slides: Beamer Latex

• BEFORE THE PRESENTATION: MATLAB VALIDATION

- ☐ Validate forward kinematics (FK)
 - ☐ Code and validate the orientation formula for Euler's, RPY, and Rodrigues formula
- ☐ Code the inverse kinematics (IK)
- ☐ Validate both the FK and the IK
- ☐ Create a simple simulation from MATLAB?