**Minimum requirements**

**You´ll need the Peter Corke´s RTB for Python, matplotlib, numpy, math, cmath.**

**Execute in the Anaconda CMD:**

* pip install pyquaternion
* pip install dual-quaternions

If you want to see the simulation, you must install RoboDK and its Python library. To install the library in Python:

pip install robodk

If you don´t want to see the simulation, open the Jupyter Notebook “PathPlanners – No RoboDK”. In the ZIP folder you´ll find another folder “GIFs” with the animations of the simulator.

QPI: Quintic polynomic interpolation

SCLERP: Screw Linear Interpolation

TM : Considering the turning machine

NOTM : Not considering the turning machine.