Coding for the irb120 position was done using position control, where a position was sent to each joint at a frequency of 1Hz and using boilerplate codes present the new positions were constantly published to which the robot was subscribed.

The coding began by understanding the topics available and then using example codes present, one could send a trajectory as a bundled package.

An interesting observation was that robot is able to collide with itself and pass through itself also, collision with ground however is not possible if the tool flange hits the ground first, however if the other parts hit the ground, the robot can intersect and pass through it.