

Instructions to run the models to predict the angles of the servos given a point in a plane

1. Upload all the ipynb and xlsx files in a jupyter notebook folder
2. Open any of the ipynb files and run the kernel
3. There are 3 ipynb files for each arm, one for the GPR model, one for the polynomial model, and one for the Tree Regressor model.
4. The files including lewansoul in the name (the brand of the robot arm) are the ones corresponding to the arm used for the project. The files including saintsmart in the name correspond to the second arm used to verify the model