

2D ROBOT MANIPULATOR VISUALIZER

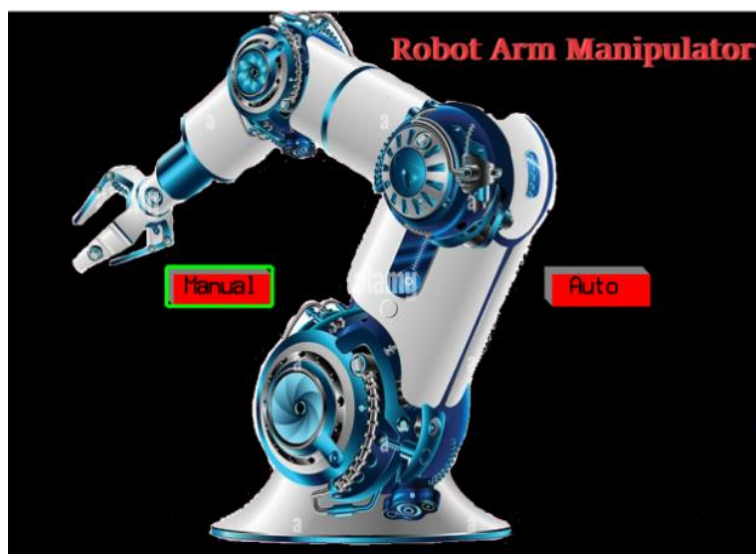
TEAM LA PRIMA +

24-780 A: ENGINEERING COMPUTATION

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 2. The simulations are solely to be used for Educational or Industrial purposes. Team La Prima + does not promote any kind of illegal activities and the product's use case for unauthorized activities is strictly prohibited.
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USER GUIDE



INTERFACE

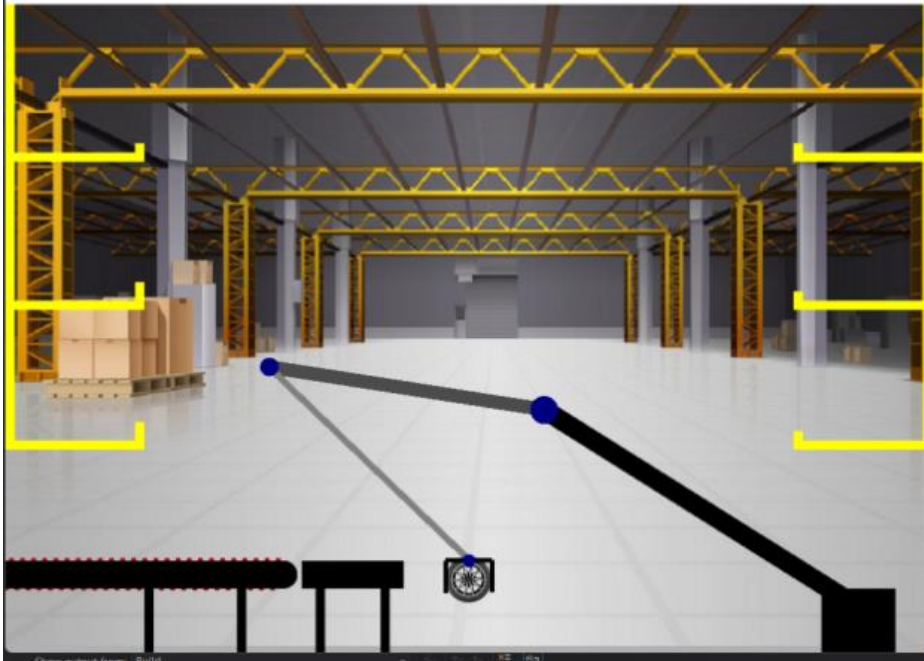
1. The user will be greeted with an Interface window as shown in the image above. User can select Manual or Auto mode using **LEFT** or **RIGHT** arrow keys. User should press **ENTER** after deciding which mode to select.

AUTO MODE

User has the liberty to select any object and observe it coming from the conveyor then getting picked by the arm and finally getting placed on its designated shelf (like an ASRS System).

The user has the liberty to choose objects by pressing one of the following buttons:

- Press Button **S**: For object, **SPRING**.
 - Press Button **B**: For object, **BOX**.
 - Press Button **P**: For object, **SODA CAN**.
 - Press Button **G**: For object, **GEAR**.
 - Press Button **T**: For object, **TIRE**.
 - Press Button **F**: For object, **BALL**
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MANUAL MODE

User has the liberty to explore the potential of the arm in Manual Mode. In manual mode, user must choose which object to pick and place using the following commands:

- Press Button **S**: For object, **SPRING**.
- Press Button **B**: For object, **BOX**.
- Press Button **P**: For object, **SODA CAN**.
- Press Button **G**: For object, **GEAR**.
- Press Button **T**: For object, **TIRE**.
- Press Button **F**: For object, **BALL**.

The User can move the robotic arm using the **UP**, **DOWN**, **LEFT** and **RIGHT** Keys. The user can then pick the objects using the end effector of the robotic arm using **SPACE** Key (Provided the end effector is in proximity of the selected object). The user can place the object in a specific shelf using the **SPACE** Key.

The object will traverse to its next destination after placing it in the shelf indicating that the system is ready for its next iteration and user should select the next object.