Trajectory Generation

1. When testing the navigate, welding, assembly, and pick/place applications, most of the code stayed the same. What is the advantage of doing so for Industrial Manipulators?

2. The duration between the various setpoints was all set by a single constant in all the applications. This ensures a consistent time between numerous waypoints. List the downside to this regarding the welding application.

3. Why does welding fail when the duration is set to 0.25s?

4. Why was the particular sequence of waypoints selected for this task?