Project 1 Report

# Steps

* Install MATLAB
* Install CoppeliaSim
* Create a directory for a project
* Copy remApi.m, remoteApi.dll, remoteApiProto.m and simpleTest.m from installation directory/programming/remoteApiBindings/matlab and installation directory/programming/remoteApiBindings/lib
* Run CoppeliaSim and add simRemoteApi.start(19999) to any object, I put it in the ground.
* Run simpleTest.m and check whether a connection is made.
* Add any robot from the library to the scene and change joints type to Force/Torque
* Create a new m file and add some boilerplate code from simpleTest.m that creates a connection, checks whether it was successful, and destroy the connection after the programme finish executing.
* Create object handlers using their names from the CoppeliaSim scene using simxGetObjectHandle function.
* Issue commands to the joints using simxGetJointTargetPosition function.

# Some function prototypes

* [number returnCode,number handle]=simxGetCollectionHandle(number clientID,string collectionName,number operationMode)
* [number returnCode]=simxSetJointTargetPosition(number clientID,number jointHandle,number targetPosition,number operationMode)
* [number clientID]=simxStart(string connectionAddress,number connectionPort,boolean waitUntilConnected,boolean doNotReconnectOnceDisconnected,number timeOutInMs,number commThreadCycleInMs)
* simxFinish(number clientID)