**ECE 455: Computer Project #2**

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1. There are several Matlab scripts used for this project. The top level script is proj.m, this takes the arm and trajectory files as its inputs and the other scripts are jacobian.m and actualposition.m.
2. I have successfully computed jacobian and forward kinematics, but implementing the looping condition took some time to figure out. Because, the program at the beginning became an infinite loop and kept on executing.
3. Loop condition was derived, tested by changing the number of desired points and was working fine.
4. Was testing the program by changing different variables in the trajectory file. I had given many points that are outside the workspace and changed the arm lengths and number of joints. Because of the changes there were lot of errors that popped up.
5. Finally overcame all the errors by finding the optimum deviation parameters and scaling factors using trial and error.
6. Once the program starts running please wait until you get a message like “Successful arm movement”.