

## Integration: Robotic system sequence issues and solutions table

Area	Activity	Issue
Picking	after MoveJ to the tin coordinates and before move L to go down	wrist does not rotate
Picking	MoveL to go down	requires current pose & variable Z to work with multiple tin sizes
Canning	MoveJ to go to canning	robot should place tin up right and its placing in flat down
Canning	MoveL to go down	requires current pose & variable Z to work with multiple tin sizes
Canning	RFID scan	DB error: no such column RFID
Packing:Valid	MoveJ to Valid	wrong pose + variable Z (optional: variable X + count valid tins)
Packing:NotValid	MoveJ to NotValid	wrong pose + variable Z (optional: variable X + count valid tins)
Packing:Valid	Release Gripper	gripper not opening to release the tin
Packing:NotValid	Release Gripper	gripper not opening to release the tin
	RFID scan	not consistent scanning

Suggested Solution	Trial Result	Reported by	Resolved by
Insert rotation values in the pose (Rx, Ry identified to be changing when rotating the wrist see "rotation_angle sheet" for reference)	provide enpoint that take joint angles and returned modified joint angles which are then converted into pose using forward kinematics	Alin	Alin, MOhammed
add variable z to tinpose in relation to the tin short (MA) axis as drawn by the elipse	provided endpoints that take a reference pose and modifies z value for picking and x value for caning	Alin	Alin, MOhammed
alter the pose including a variable Z in relation to the tin long (ma) axis as drawn by the elipse	added new move	Alin	MOhammed
add variable z to tinpose in relation to the tin long (ma) axis as drawn by the elipse	provided endpoints that take a reference pose and modifies z value for picking and x value for caning	Alin	Alin, MOhammed
alter DB by adding/fixing the required RFID column	Added timer and constrained return	Alin	Johanna
free move to correct pose + variable Z in relation to the short (MA) axis as drawn by th elipse (optional: increment counter and store x pos to calculate new x in relation to the short axis (MA) and gap between tins)	Added tin counter and initial x coordinates	Alin	Alin, MOhammed
free move to correct pose + variable Z in relation to the short (MA) axis as drawn by th elipse (optional: increment counter and store x pos to calculate new x in relation to the short axis (MA) and gap between tins)	Added tin counter and initial x coordinates	Alin	Alin, MOhammed
add/edit RG6 URcap	Found wrong apperture of the gripper and modified	Alin	Mohammed
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approach scanner closer to the tin	improved scanning consistency	Group	Johanna



