FINAL PROJECT

POSITION KINEMATICS FOR DELTA ROBOT

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**TEAM NUMBER:** FINAL PROJECT-4

**GOAL**:

**DELTA ROBOT- DESIGN AND QUALITATIVE ANALYSIS:**

* Degrees of Freedom -
* Kinematic arrangement - RRR
* Symbolic representation -
* Homogeneous Transformation -

**METHOD:**

1. Forward Kinematics derivation:
2. Inverse Kinematics derivation:

**PSEUDO-CODE:**

**EVALUATION:**

1. Forward Kinematics: 3 TEST CASES WITH FIGURES
2. Inverse Kinematics: 3 TEST CASES WITH FIGURES

**ANALYSIS:**

* Comparison with expected results:
* When does it work well? And when does it not?
* Any differences from expected result?
* Workspace

**RELATION TO COURSE:**

**FUTURE SCOPE OF PROJECT:**