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**Ariac Box Inspector (PS6)**

**GITHUB LINK: [https://github.com/vrk12/EECS376\\_PS6](https://github.com/vrk12/EECS376_PS6)**

For this assignment, I wrote the function `compute_shipment_poses_wrt_world` and completed the function `model_poses_wrt_box`.

The format of the `compute_shipment_poses_wrt_world` function closely followed that of the `get_box_pose_wrt_world` function. I wrote my own helper function (`compute_shipment_world_pose`) that is similar to the `compute_stPose`. This function uses `xformUtils` to compute the pose with respect to the world rather than the object. In this case, my function treated the box as the cam from `compute_stPose`, and obviously treated the world as the world. The product in my helper function is like the part in the `compute_stPose` function. Together with this helper function and the for loop in my main `compute_shipment_poses_wrt_world`, the function loops through all of the products, computes their pose wrt the world, and then pushes it back to the `desired-models_wrt_world`.

I just added 4 lines to the `model_poses_wrt_box` function that use the `xformUtils` to compute the pose. These lines are similar to those of the helper function I wrote or those in the `compute_stPose` function.