1. In this project, we have two parts
2. Here, we define and interpolate the path of the tool tip. We use object.key file where 5 key frames are given and using hermite, we generate .ang file which we copy in object folder. Thus, we find robot executing circular motion.
3. In 2nd part, we are given rotation matrices which we convert into quaternions interpolate the movement of the object and then convert the quaternions again into rotation matrix. Thus, using the matrix, we use Catmull-Rom to generate the trajectory for the object.

B) Top-level script – Rotation to Quaternion, Quaternion to Rotation, Quaternion Interpolate

C) Connection between Quaternions & catmull-rom