## Engineering Design GNG1103C Lab C01 Group 5

**Professor David Knox** 

March 08, 2022

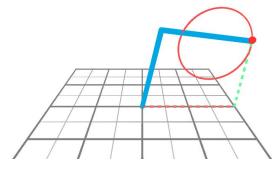
Igor Sek, Andrew Edginton, Osaigbovo Ogbeide, Lianyi Chen.

#### **Inverse Kinematics**

 Live tracking of movements on a graphed plane for reference

Motors calibrated for consistency

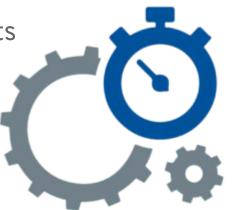
Python Based allowing for expansion in complexity



### Safety

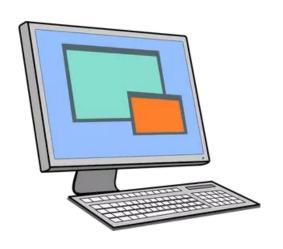


- Physical shut-off switch for emergency stop
- GUI for simple operation
- Calibration and simple assembly for consistent results
- Thorough testing to ensure safety

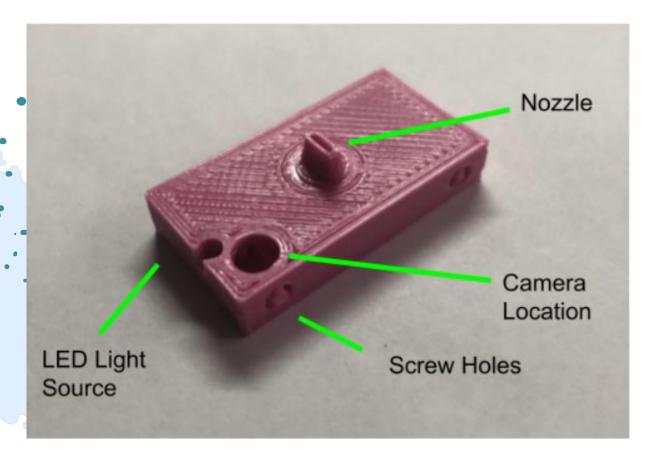


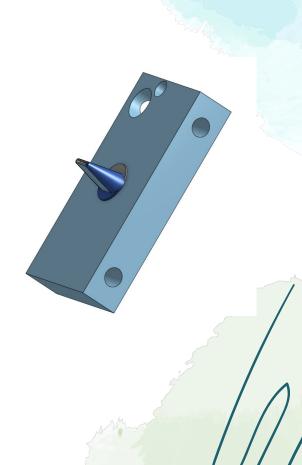
#### User's Interface

- Controlled through computer application
- Built in nozzle without index arms to increase reliability
- Remote connectivity to the robot for livestream and remote operation



#### **End Effector**





# Feedback/Questions