**Lab 9 Grading Sheet**
Robot Arm 16-311
Prof. Howie Choset
Team: _____ Final Grade:_____
Member: _____
Member: _____
Member: _____

| | | | | Try1 | Try2 | Try3 |
|---|---|---|---|---|---|---|
| Position | L2 distance to end effector | | points | Points earned | | |
| A | < 0.5 inch | | 5 | | | |
| | < 0.25 inch | | 10 | | | |
| B | < 0.5 inch | | 10 | | | |
| | < 0.25 inch | | 25 | | | |
| A | < 0.5 inch | | 20 | | | |
| | < 0.25 inch | | 30 | | | |

**Difficulty**

| | | | | | |
|---|---|---|---|---|---|
| Obstacle | 0 | 0 | | |
| No Obstacle | -30 | x | | |

**Final Grade**

| | | |
|---|---|---|
| | | |

**Questions**

| | | |
|---|---|---|
| Q1:Explain your path planning algorithm and provide any diagrams necessary to clarify it | 10 | |
| Q2:what improvements could you have made to your software design? What about your robot arm design? | 10 | |
| Q3:Diagram of your robot configuration space; please be sure to label axis and dimensions | 5 | |
| Q4:How would your planner be affected if a third arm was added? What changes would be necessary to make the robot run efficiently? | 5 | |
| Mystery Question! | 5 | |