
User Manual: Section Robot Visualization

In this section the following **options** are available for plotting:

1. Select "Nomenclature" to view the cable-driven robot design.
2. Select "Wrench Feasible Workspace" to view the workspace on the corresponding axes.
Note: Make sure all parameters relevant to the type of robot you are designing are specified on the corresponding tables, otherwise an error message will be displayed.
3. Select "Interference-Free Workspace" to view only the workspace on the corresponding axes.
4. Select "Nomenclature" and any other checkbox to view the designed robot and the corresponding workspace on the same axes.

To view your final selection press the **"plot"** button.

To view the data generated during simulation press the **"data"** button. This will generate a document "SimulationArachnisPlanar" or "SimulationArachnisSpatial" with the following information:

- Robot Parameters
- Required Wrench Set
- Values of an indicator function 's' and the grid of poses (a measure of the ability of the robot to balance the required wrench set throughout the grid of poses)
- Tables with robot, posture and task parameters.

To stop the simulation at any time press the **"cancel"** button.

Note: A **progress bar** on the down-right corner will signalize the progress of the simulation and data generation.