Inverse Kinematics - Basic

Inverse Kinematics is basically finding the parameters for a bot (angles,joint movements,etc.) so that it can reach a specific point. There are various ways to do it.

For this assignment, find the angles using trigonometry formulas with the arm length staying constant.

What you need to do:-

1. Construct a 2-link robot arm on MATLAB.

2. Plot a Circle.

3. Make the arm trace the circle.

Guidelines:-

1. Get acquainted with w basic operations of MATLAB on MATLAB OnRamp Tutorial - https://www.mathworks.com/learn/tutorials/matlab-onramp.html

2. Look up the concept of Inverse Kinematics - https://robotacademy.net.au/lesson/inverse-kinematics-for-a-2-joint-robot-arm-using-geometry/

3. Don't use any pre-built model for IK. Make your own from scratch.

Software needed:

MATLAB

Note - Take a look at 'Example' video to get a sense of what you need to do.