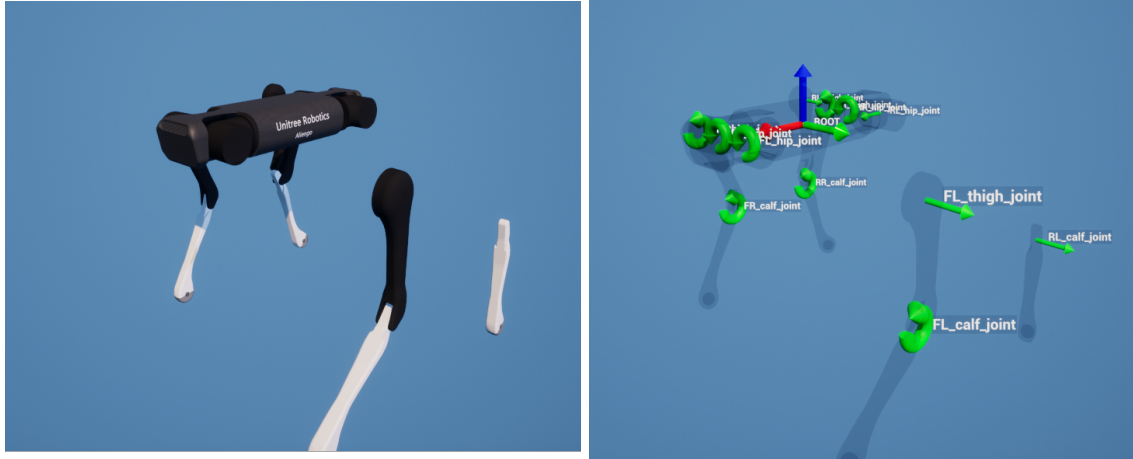# KAIST ME553 Robot Dynamics

Instructor: Jemin Hwangbo, Mechanical Engineering

Exercise 3, 4

You will be using a **modified** Aliengo model for this exercise. You should download or clone the exercise repo here: https://github.com/jhwangbo/ME553_2023. When you run raisimUnreal2.exe and exercise_3.exe or exercise_4.exe, you should see this screen.

Note that some of the joints have been switched to prismatic joints.

In exercise 3, you will be writing a function to compute the mass matrix of the system given the G.C..

In exercise 4, you will be writing a function to compute the nonlinearity of the system given the G.C. and G.V..

Deliverable: A single header file named "exercise_3_STUDENTID.hpp" and "exercise_4_STUDENTID.hpp" for each exercise. Use the provided template. You should replace "STUDENTID" with your real student id number. Submit it on KLMS.

Exercise 3 Deadline: by the end of 5th of May, 2023
Exercise 4 Deadline: by the end of 12th of May, 2023