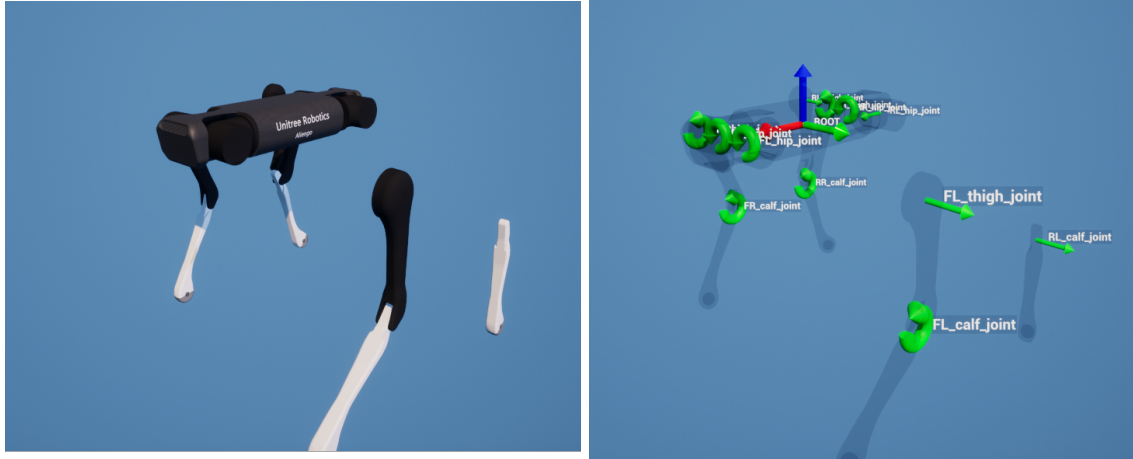


KAIST ME553 Robot Dynamics

Instructor: Jemin Hwangbo, Mechanical Engineering

Exercise 5

You will be using the same Aliengo model for this exercise. You should download or clone the exercise repo here: https://github.com/jhwangbo/ME553_2023. The robot model is given below. You should check the exact properties in the URDF.



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

In exercise 5, you will be writing a function to compute the generalized acceleration for the given generalized coordinate, velocity, and force using **Articulated Body Algorithm**.

Deliverable: A single header file named "exercise_5_STUDENTID.hpp".

Exercise 5 Deadline: by the end of 31st of May, 2023