✓ **Congratulations! You passed!**

Grade received 100%   **To pass** 80% or higher

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1. True or false? The PoE formula in the space frame only correctly calculates the end-effector configuration if you first put the robot at its zero configuration, then move joint n to θ_n, then move joint $n-1$ to θ_{n-1}, etc., until you move joint 1 to θ_1.

   1 / 1 point

   ○ True.

   ◉ False.

   ✓ **Correct**
   Of course not! The configuration of the end-effector doesn't depend on the time history of the joint values, just the current joint values.

2. Consider the screw axis $\mathcal{S}_i$ used in the PoE formula. Which of the following is true?

   1 / 1 point

   ○ $\mathcal{S}_i$ represents the screw axis of joint i, expressed in the end-effector frame {b}, when the robot is at its zero configuration.

   ○ $\mathcal{S}_i$ represents the screw axis of joint i, expressed in the end-effector frame {b}, when the robot is at an arbitrary configuration θ.

   ◉ $\mathcal{S}_i$ represents the screw axis of joint i, expressed in the space frame {s}, when the robot is at its zero configuration.

1. True or false? The PoE form' axis of joint i, expressed in the space frame {s}, when the robot is at an arbitrary configuration θ.
   then move joint n to θ_n, the

   ○ True.

   ◉ False.

   ✓ **Correct**
   Of course not! The cor

2. Consider the screw axis $\mathcal{S}_i$ u

   ○ $\mathcal{S}_i$ represents the screw

   ○ $\mathcal{S}_i$ represents the screw

   ◉ $\mathcal{S}_i$ represents the screw

   ○ $\mathcal{S}_i$ represents the screw