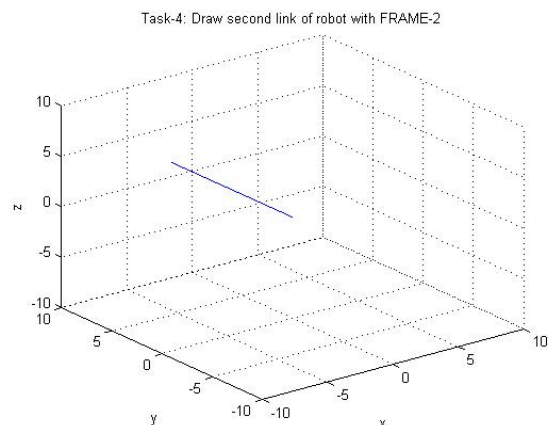
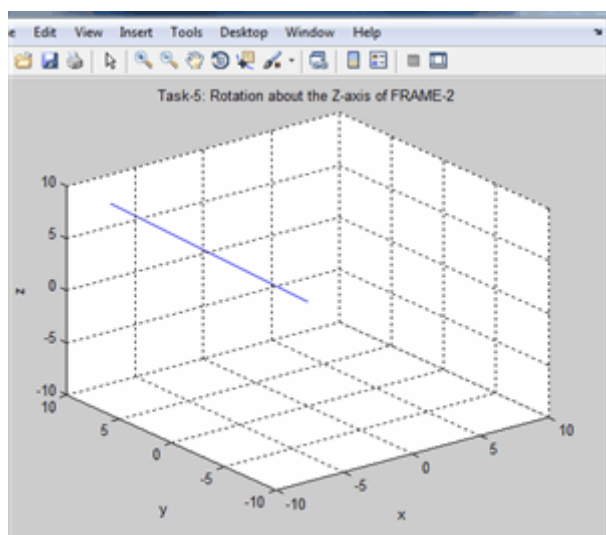


1. Items done this session:

Task-4: Draw second link of robot with (0,0,0), (0,12,0) in FRAME-2.



Task-5: Write a function TRANS1_2 to convert the points representing the second link.

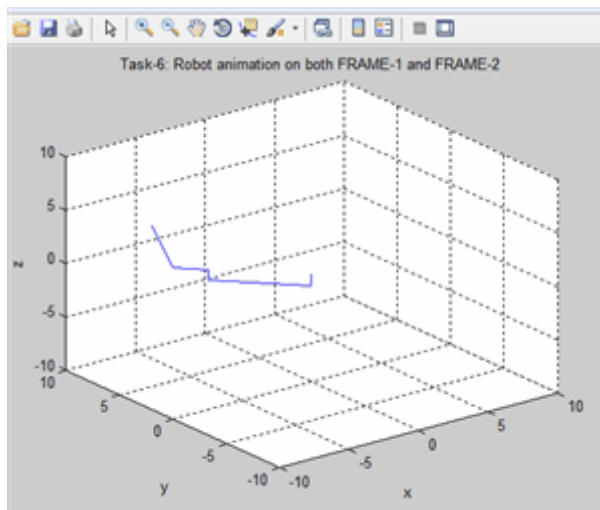


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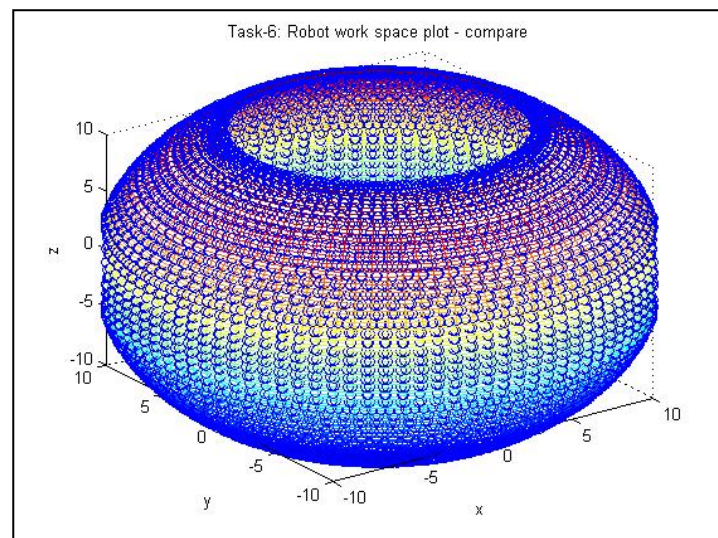
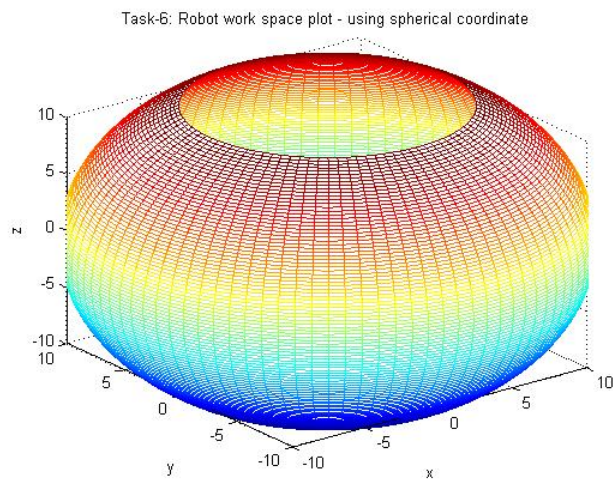
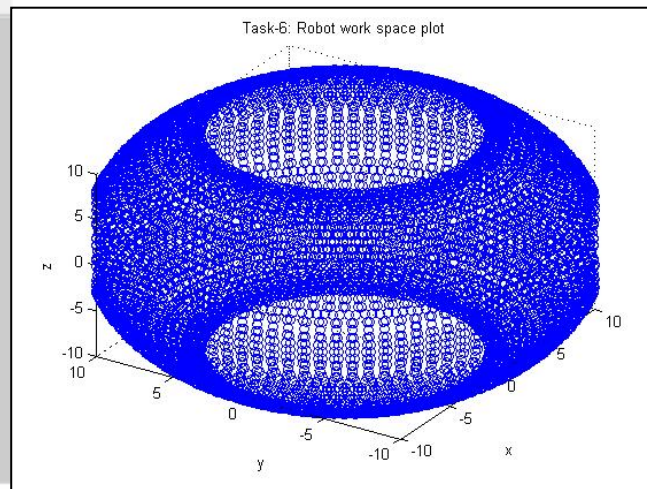
Task-6: Write a separate function representing the work envelope of the two-link robot.

The left graph below is the animation of all links moving from ($\theta_1=0$, $\theta_2=0$) to ($\theta_1=100$, $\theta_2=100$).

The right graph is work space plotting by end effect of the robot and sampling 100 points for each variables $\theta_1=[0:360]$ and $\theta_2=[0:360]$.



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2. Items for next session:

Keep working on Task-7

3. Problems / Concerns: