Department Of Computer Science, University of Bath

Inverse Kinematics Coursework

Garoe Dorta Perez, Dave Hibbitts, Ieva Kazlauskaite, Richard Shaw

November 12, 2014

1 Objective

aaa

2 Related Work

What People do?

3 Procedure

What we did?

3.1 Start with Matlab

1. Issues
2. How we solve them
3. Why we use what we use (e.g. Inverse Jacobian)

3.2 Port the code to C++, OpenGL

1. Issues
2. How we solve them

3.3 Exploration

The following properties are to be explored.
1. Some way of indicating where the remote end of the linkage should move to in 3-space.
2. A way to change the physical properties such as rate at which the joints can change and the slow-out and slow-in of the movement of the end of the linkage as it leaves it current position and approaches the target position respectively.
3. Whether to model and thereby vary the flexibility of the rods.
We are allowed to work out something for one joint and explain how we'd apply it to other and so on.

3.4 Summary and Conclusion

What the final thing would look like if we had more time to work on it?