Report

Task1: Forward Kinematic

Product of exponentials FK formula: 

Where M is home position of robot. M = ,

S is the matrix of screw vectors that consists of 3 rotational components Sw and 3 translational components Sv

S =

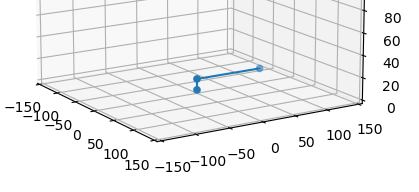
Task2: Jacobian

Product of exponentials Jacobian calculated by following algorithm:

Task3: visualization

Visualization goes same way as in previous home tasks by following algorithm:

1. Calculate Forward kinematic for next joint
2. Store joint coordinates
3. Repeat till endeffector



*Figure 1 – robot visualization in home position*

GitHub: https://github.com/EriKarasik/ARHW6