Robotics and Automation Lab 6

JMHA Jayasinghe 160238R

Joint Angle	Start Configuration	End Configuration	Polynomial Function
Joint 1	0.0	−0.2	−4.0767645601022206e−07 t^5 + 5.095955700127776e−06 t^4 + −1.6986519000425915e−05 t^3 + 0.0 t^2 + 0.0 t + 0.00021233148750532393
Joint 2	0.0	0.0	−3.299711921556537e−08 t^5 + 4.124639901945671e−07 t^4 + −1.37487996773152235e−06 t^3 + 0.0 t^2 + 0.0 t + 1.7185999591440293e−05
Joint 3	0.0	0.0	−1.3970901704851715e−09 t^5 + 1.7463627131064644e−08 t^4 + −5.821209043688214e−08 t^3 + 0.0 t^2 + 0.0 t + 7.276511304610267e−07
Joint 4	0.0	0.0	−1.8468423871809142e−09 t^5 + 2.3085529839761425e−08 t^4 + −7.695176613253808e−08 t^3 + 0.0 t^2 + 0.0 t + 9.618970766567259e−07

Joint Angle	Start Configuration	End Configuration	Polynomial Function
Joint 1	0.0	−0.2	−0.00038359147682832977 t^5 + 0.004794893460354122 t^4 + −0.0159829782011804 t^3 + 0.0 t^2 + 0.0 t + −0.00021277248524498305
Joint 2	0.0	0.0	−0.00021277248524498305 −3.299773078992985e−08 t^5 + 4.1247163487412316e−07 t^4 + −1.3749054495804104e−06 t^3 +

			0.0 t^2 +
			0.0 t +
			1.718631811975513e−05
Joint 3	0.0	0.0	−1.3972052630606416e−09 t^5 +
			1.7465065788258018e−08 t^4 +
			−5.821688596086006e−08 t^3 +
			0.0 t^2 +
			0.0 t +
			7.277110745107507e−07
Joint 4	0.0	0.0	−1.8473350013437088e−09 t^5 +
			2.309168751679636e−08 t^4 +
			−7.697229172265452e−08 t^3 +
			0.0 t^2 +
			0.0 t +
			9.621536465331815e−07

Joint Angle	Start Configuration	End Configuration	Polynomial Function
Joint 1	0.0	−0.2	−0.0003835917375459085 t^5 +
			0.0047948967193238856 t^4 +
			−0.01598298906441285 t^3 +
			0.0 t^2 +
			0.0 t +
			−0.0002126366948393965
Joint 2	0.0	0.0	0.0007679392157171038 t^5 +
			−0.009599240196463797 t^4 +
			0.031997467321545986 t^3 +
			0.0 t^2 +
			0.0 t +
			3.165848067521182e−05
Joint 3	0.0	0.0	−1.849251700036803e−09 t^5 +
			2.3115646250460035e−08 t^4 +
			−7.705215416820011e−08 t^3 +
			0.0 t^2 +
			0.0 t +
			9.631519271025013e−07
Joint 4	0.0	0.0	−1.7358778956122483e−09 t^5 +
			2.16984736951153103e−08 t^4 +
			−7.232824565051033e−08 t^3 +
			0.0 t^2 +
			0.0 t +
			9.041030706313791e−07

Joint Angle	Start Configuration	End Configuration	Polynomial Function
Joint 1	0.0	−0.2	0.0003835910989393759 t^5 + −0.004794888736742199 t^4 + 0.015982962455807326 t^3 + 0.0 t^2 + 0.0 t + 0.00021296930240843892
Joint 2	0.0	0.0	−0.00038404748930971356 t^5 + 0.00480059361637142 t^4 + −0.016001978721238062 t^3 + 0.0 t^2 + 0.0 t + 2.4734015475758042e−05
Joint 3	0.0	0.0	−0.000768001239 8839343 t^5 + 0.009600015498549178 t^4 + −0.032000051661830585 t^3 + 0.0 t^2 + 0.0 t + 6.457728822795161e−07
Joint 4	0.0	0.0	−1.7071410780999945e−09 t^5 + 2.133926347624993e−08 t^4 + −7.113087825416642e−08 t^3 + 0.0 t^2 + 0.0 t + 8.891359781770802e−07