

Graduation Project (ME4918) Weekly Report(X)

赵四维

Institute of Robotics,
School of Mechanical Engineering, SJTU

November 29, 2024

Table of Contents

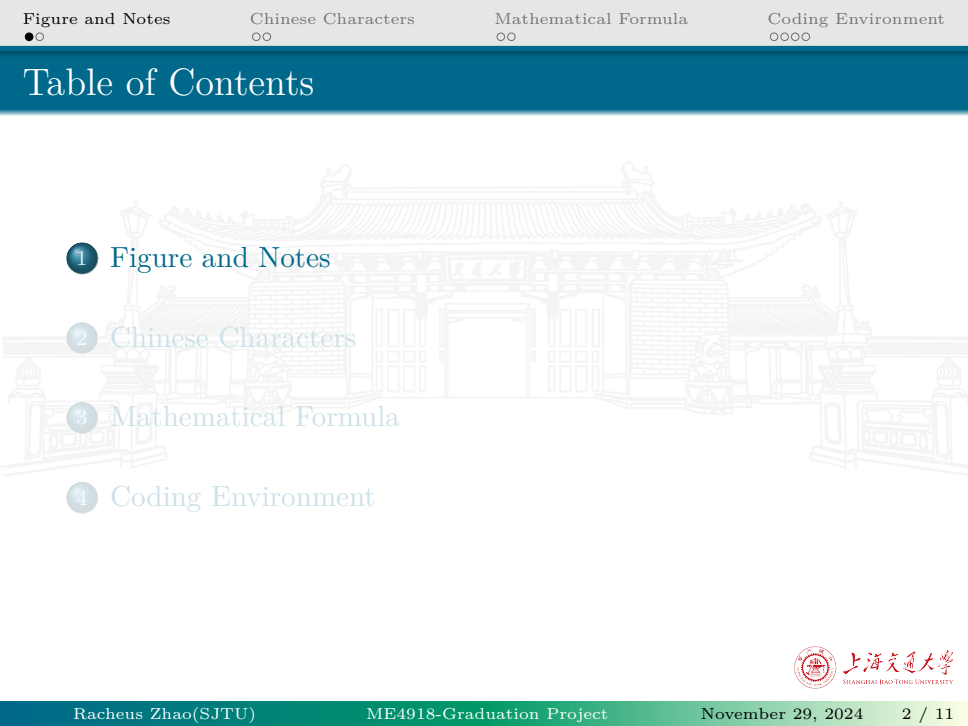
- 
- 1 Figure and Notes
 - 2 Chinese Characters
 - 3 Mathematical Formula
 - 4 Coding Environment


Figure and Notes

In Simulink, you can import models from other modeling environments, such as Solidworks.



Save the modeling file in XML format or URDF format, set a reasonable rotation coordinate system, and import it into Simulink for simulation.

Table of Contents

- 
- 1 Figure and Notes
 - 2 Chinese Characters
 - 3 Mathematical Formula
 - 4 Coding Environment

中文测试

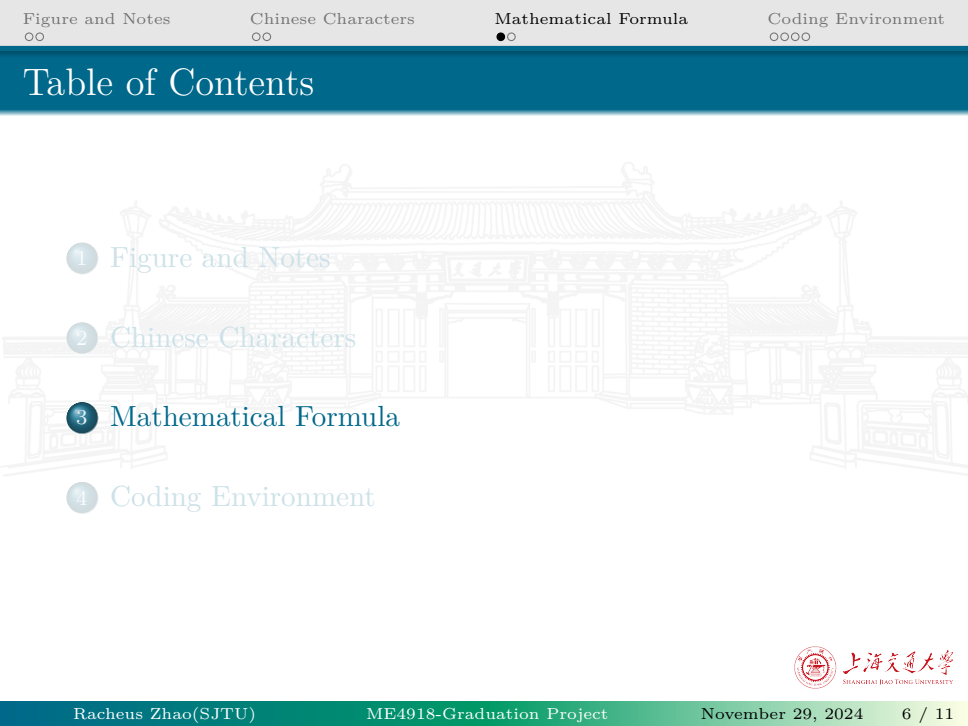
- 邓紫棋
- 林俊杰

手心的蔷薇 (加粗)
刺伤而不自觉 (楷书)
你值得被疼爱 (黑体)
你懂我的期待 (仿宋)

代表作展示

- 邓紫棋: 《倒数》, 《多远都要在一起》
- 林俊杰: 《修炼爱情》, 《可惜没如果》

Table of Contents

- 
- 1 Figure and Notes
 - 2 Chinese Characters
 - 3 Mathematical Formula
 - 4 Coding Environment

Mathematical Formula

Mathematical Formula

$$\begin{aligned}\dot{x} &= Ax + Bu \\ y &= Cx + Du\end{aligned}\tag{1}$$


对于机械臂的拉格朗日动力学方程，可以写成如下形式：

$$\frac{d}{dt}\left(\frac{\partial L}{\partial \dot{q}_i}\right) - \frac{\partial L}{\partial q_i} = Q_i\tag{2}$$

Where Lagrangian L is defined as:

$$L = T - V\tag{3}$$

Table of Contents

- 
- 1 Figure and Notes
 - 2 Chinese Characters
 - 3 Mathematical Formula
 - 4 Coding Environment

Coding Environment

import numpy as np



CodeSnap + Figure 清晰度不太高

lstlisting Environment

Here is a sample C++ code snippet:

Listing 1: Sample C++ Code

```
1  #include <iostream>
2
3  int main() {
4      std::cout << "Hello, Beamer!" << std::endl;
5      return 0; //test
6  }
```

Thanks for listening!

