

Team:

Èric Ruiz Cuscó (eric.ruiz@enti.cat)



Roger Aguilar Emanuel (roger.aguilar@enti.cat)



Exercise 2 explanation:

The approach we made in exercise 2 consisted in individually lerping each rotation by using a global value which is increased on each iteration as it is being multiplied by a speed value so it is easily adjustable. This approach is really simple to implement since each joint only rotates in one axis.

Then, each joint rotation is being multiplied by the accumulated rotation in order to rotate in local space instead of global space.

Possibly there is a better approach but as we said it is easy to implement and works perfectly for what we need.