KAIST ME553 Robot Dynamics

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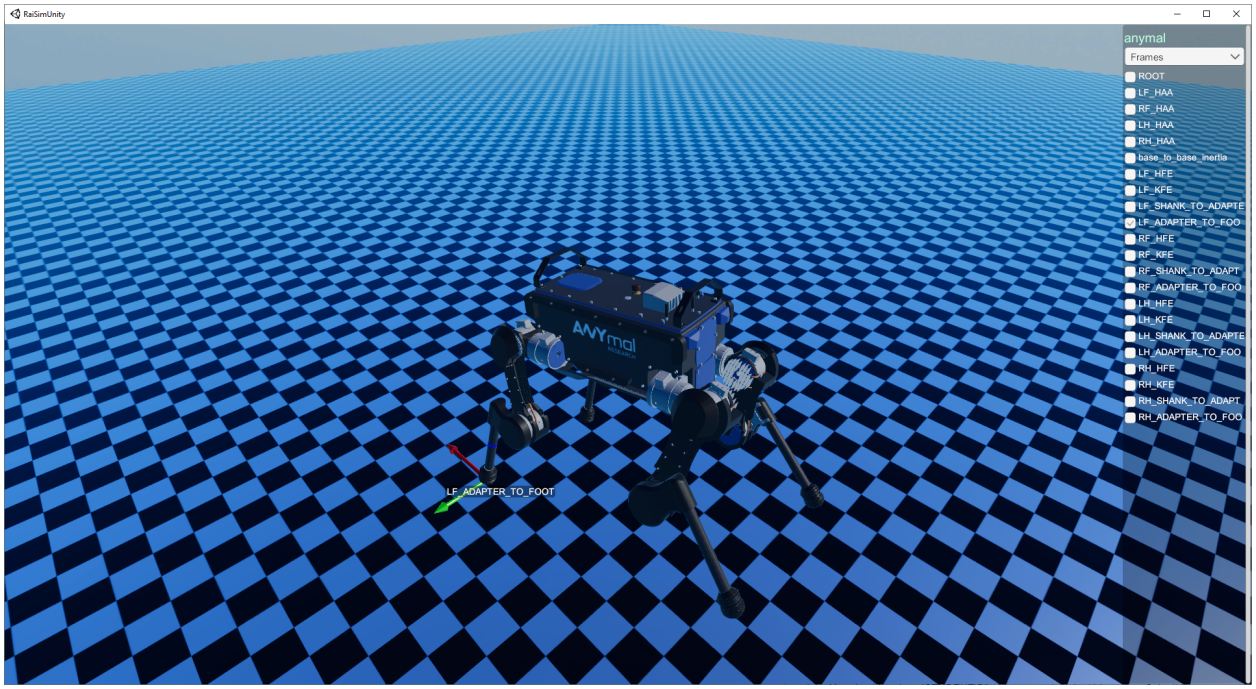
Exercise 2

You will be using the ANYmal robot model for this exercise. You should download or clone the exercise repo here: https://github.com/HuboLabKaist/KAIST_ME553. If you already have the project, pull (using git) or download it again. When you run RaiSimUnity.exe and exercise_2.exe, you should see this screen.



On the right side, you see the robot description panel. Use the dropdown and navigate to the “Frames” panel. You can check which frame you want to show in this panel. You should find “LF_ADAPTER_TO_FOOT” in the list. Check it to display it on the screen.

Your goal is to compute the linear and angular velocity of the “LF_ADAPTER_TO_FOOT”. You can find the description of the robot in “rsc/anymal/urdf/anymal.urdf”. You can find about the URDF convention here: http://wiki.ros.org/urdf/XML

Deliverable: A single header file named “exercise_2_STUDENTID.hpp”. Use the provided template. You should replace “STUDENTID” with your real student id number. Submit it on KLMS.

Deadline: 5pm, 25th of March