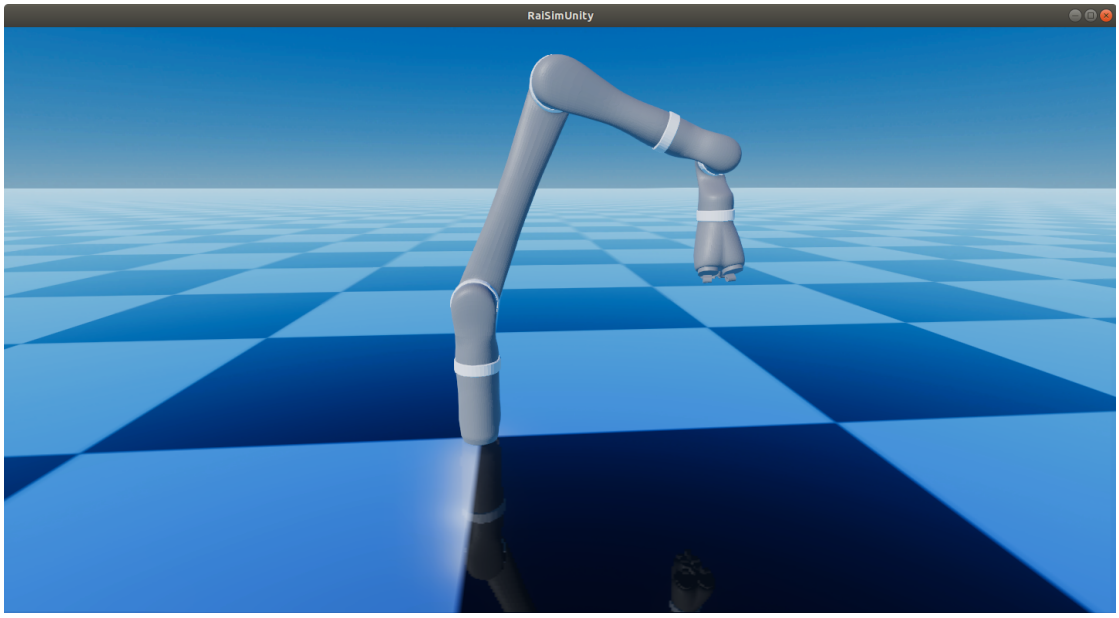
KAIST ME553 Robot Dynamics

Instructor: Jemin Hwangbo, Mechanical Engineering

Exercise 4

You will be again using the fingerless Kinova 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_4.exe after compilation, you should see this screen.



The goal of this project is to write a function to compute the mass matrix and the nonlinear term of the system. You will be using the Projected Newton Euler method to do so.

Use the provided template “exercise_4_STUDENTID.HPP” to write your functions. You can test your function using “exercise_4.cpp”. You should not use any external libraries other than Eigen.

Deliverable: A single header file named “exercise_4_STUDENTID.hpp”. Use the provided template. You should replace “STUDENTID” with your real student id number. Submit it on KLMS.

Deadline: 5pm, 16th of April