Robot Motion Planning Assignment 1

Assume a two-arm manipulator with two revolute joints (refer to the example given in the class).

Write a code in language of your choice (Matlab can be easy though) to do the following.

1. Draw the robot world to display the robot and some polygonal obstacles.

2. Your code to generate the robot end effector workspace.

3. Your code should also generate the configuration space and display the configuration space obstacles.

For your reference, the output from your code should look somewhat like the below figure.
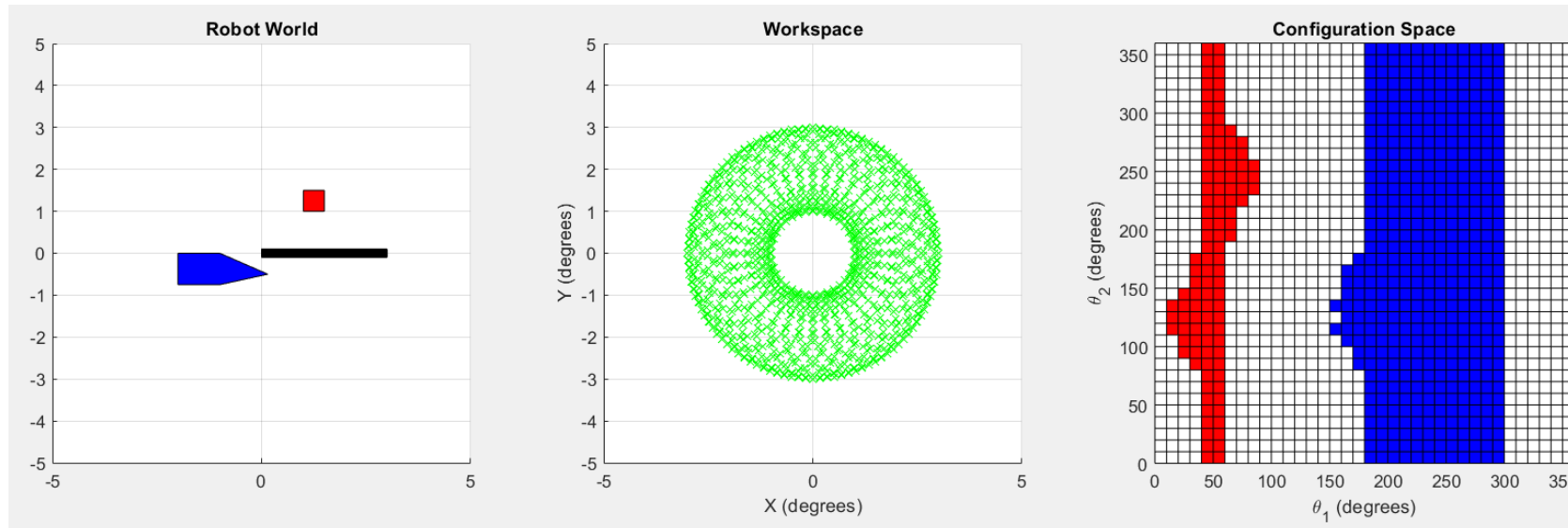
Submit your code and a brief report describing the output.