

Centro Universitario de Ciencias Exactas e Ingenierías



INRO

Robótica Móvil

Actividad 6 - Robot Móvil

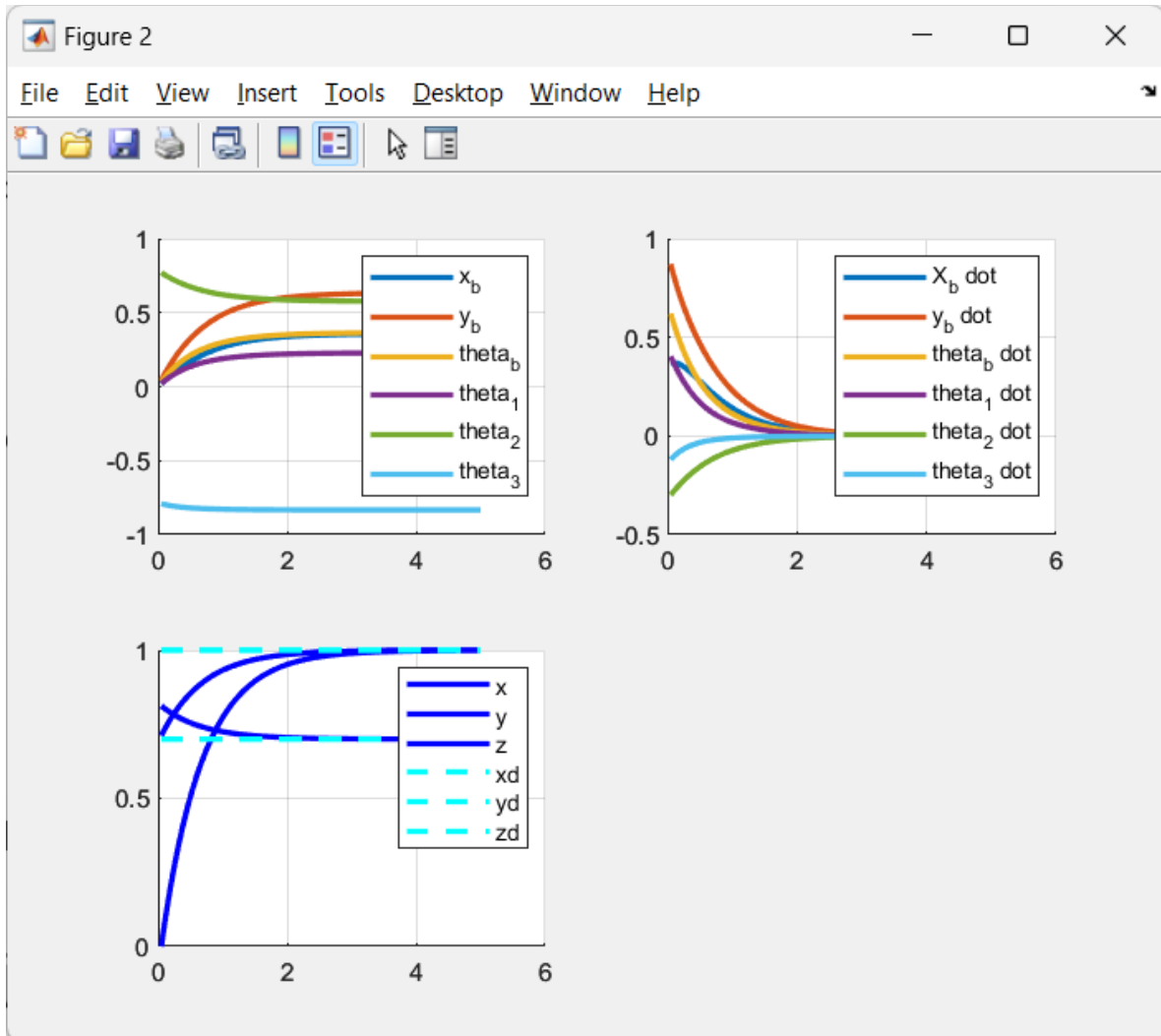
Julio Alexis González Villa

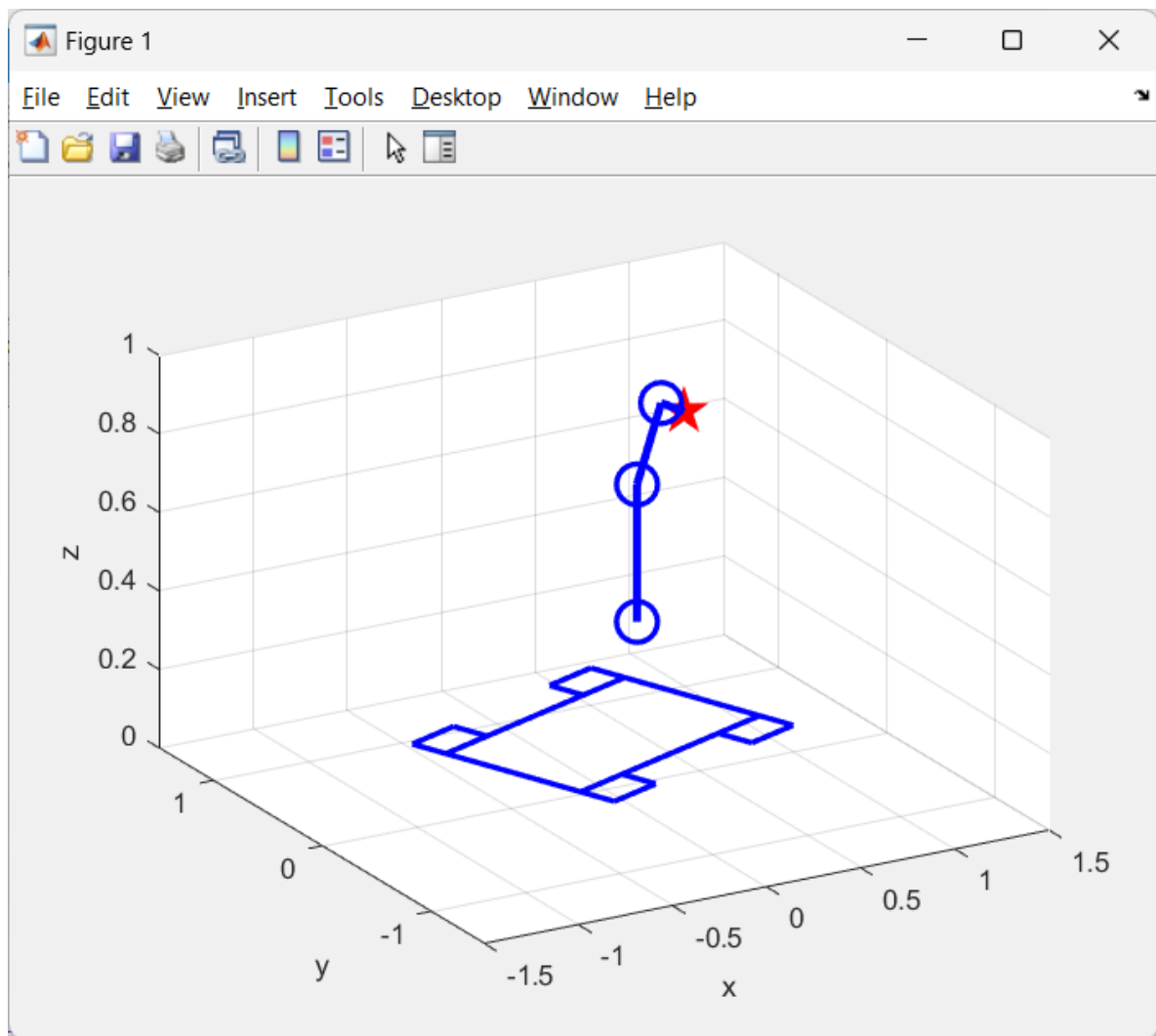
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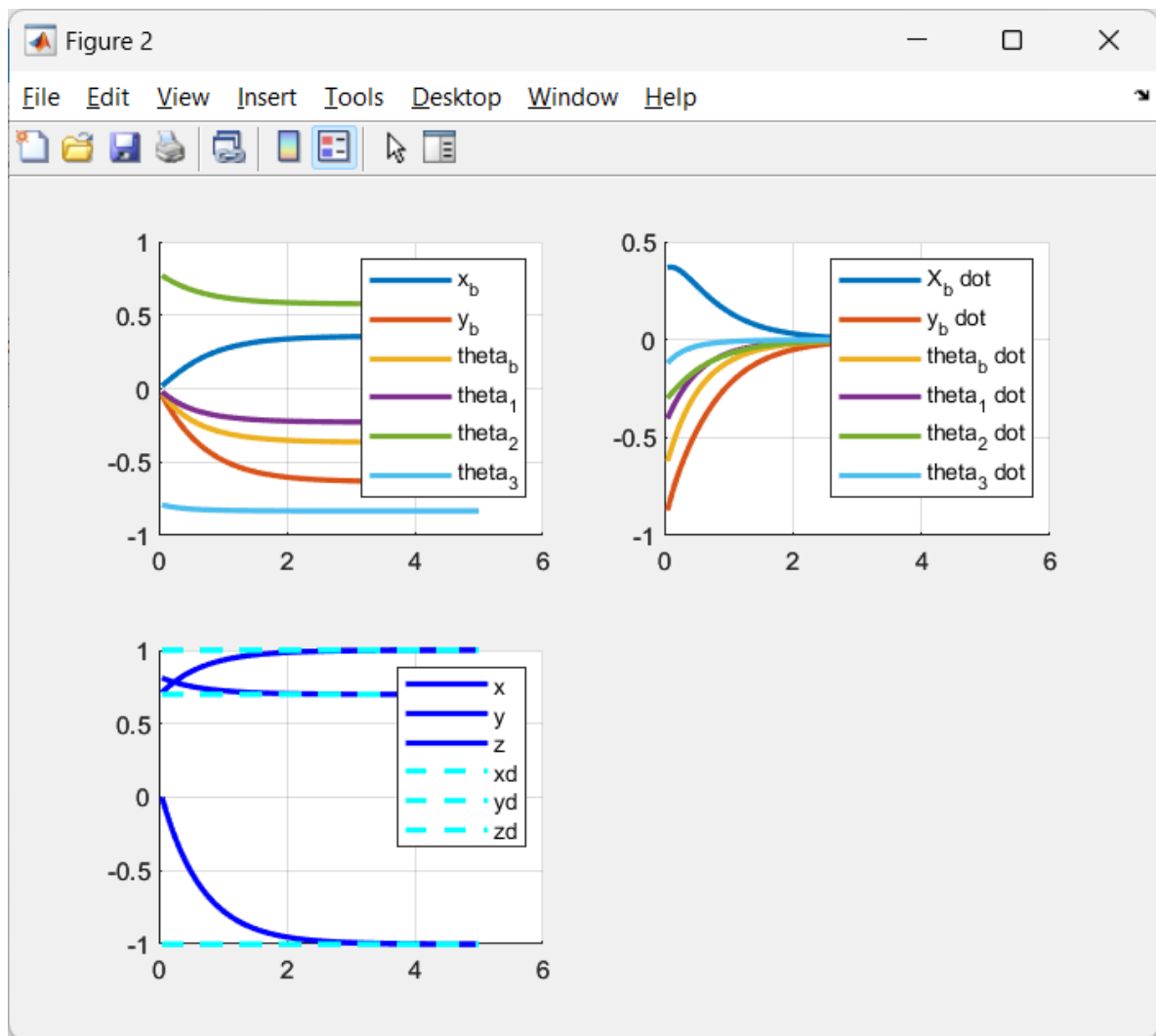
Objetivo: Implementa una simulación del modelo de un robot móvil manipulador en lazo abierto.

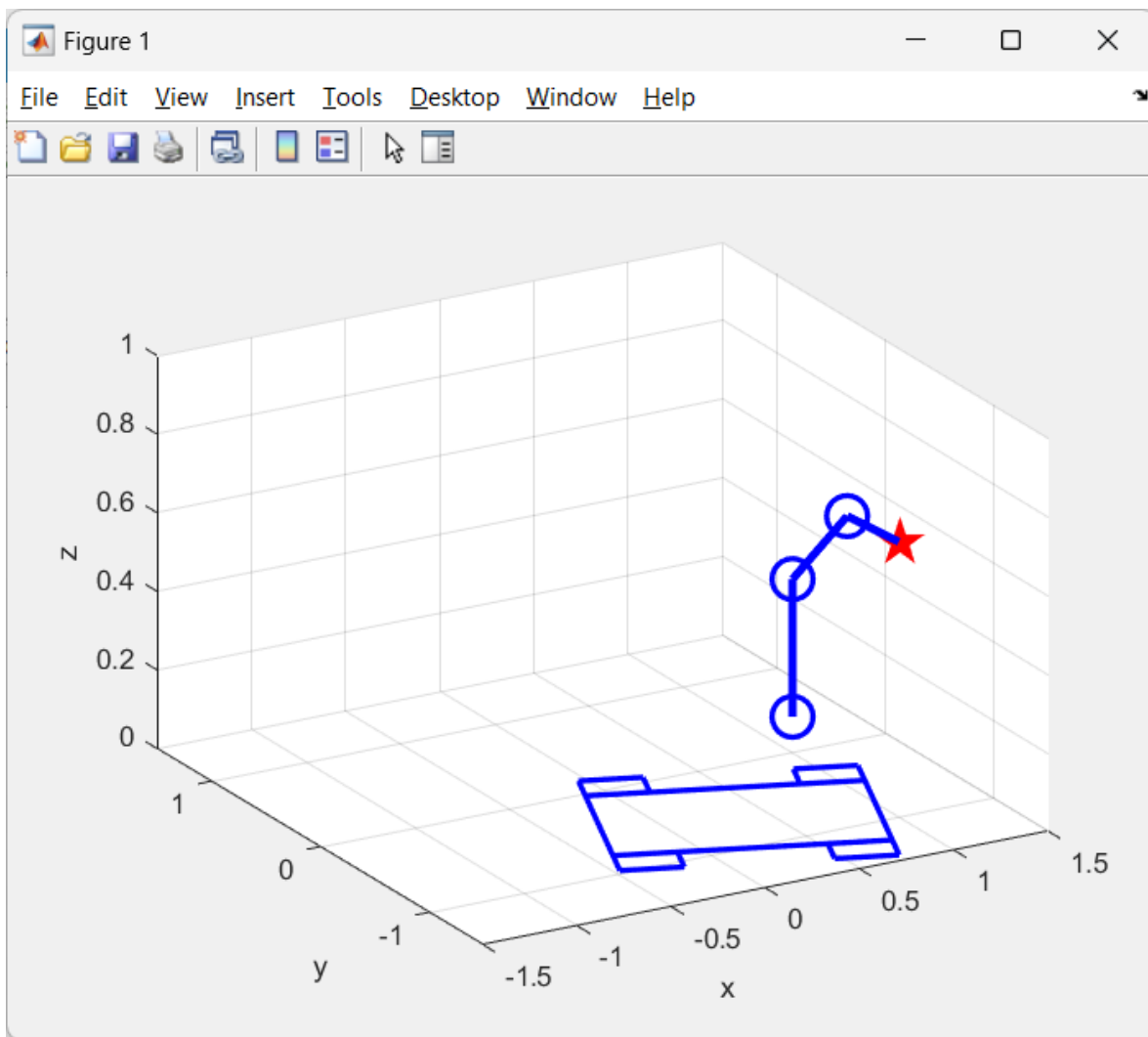
Resultados

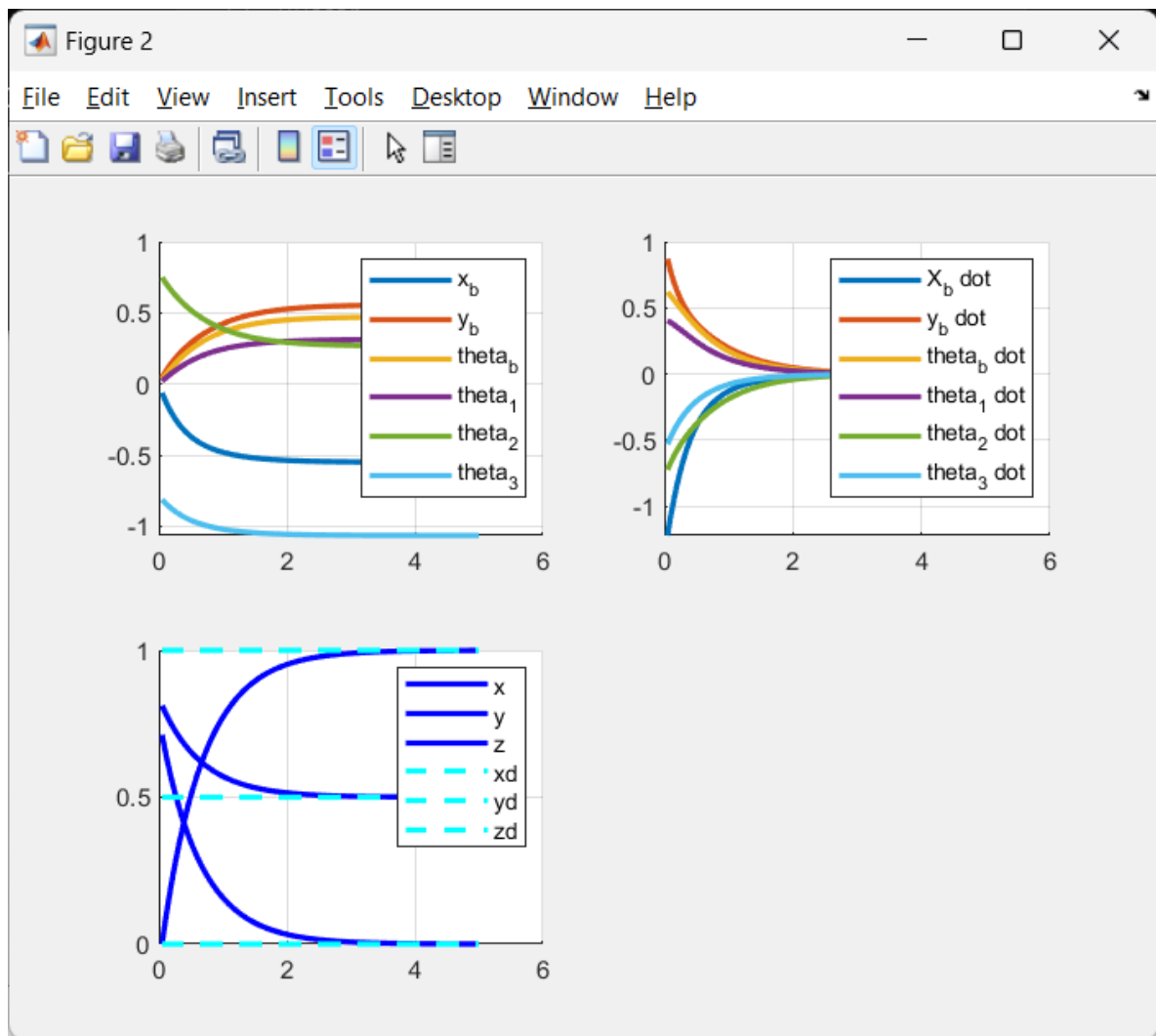
- Ejercicio 1

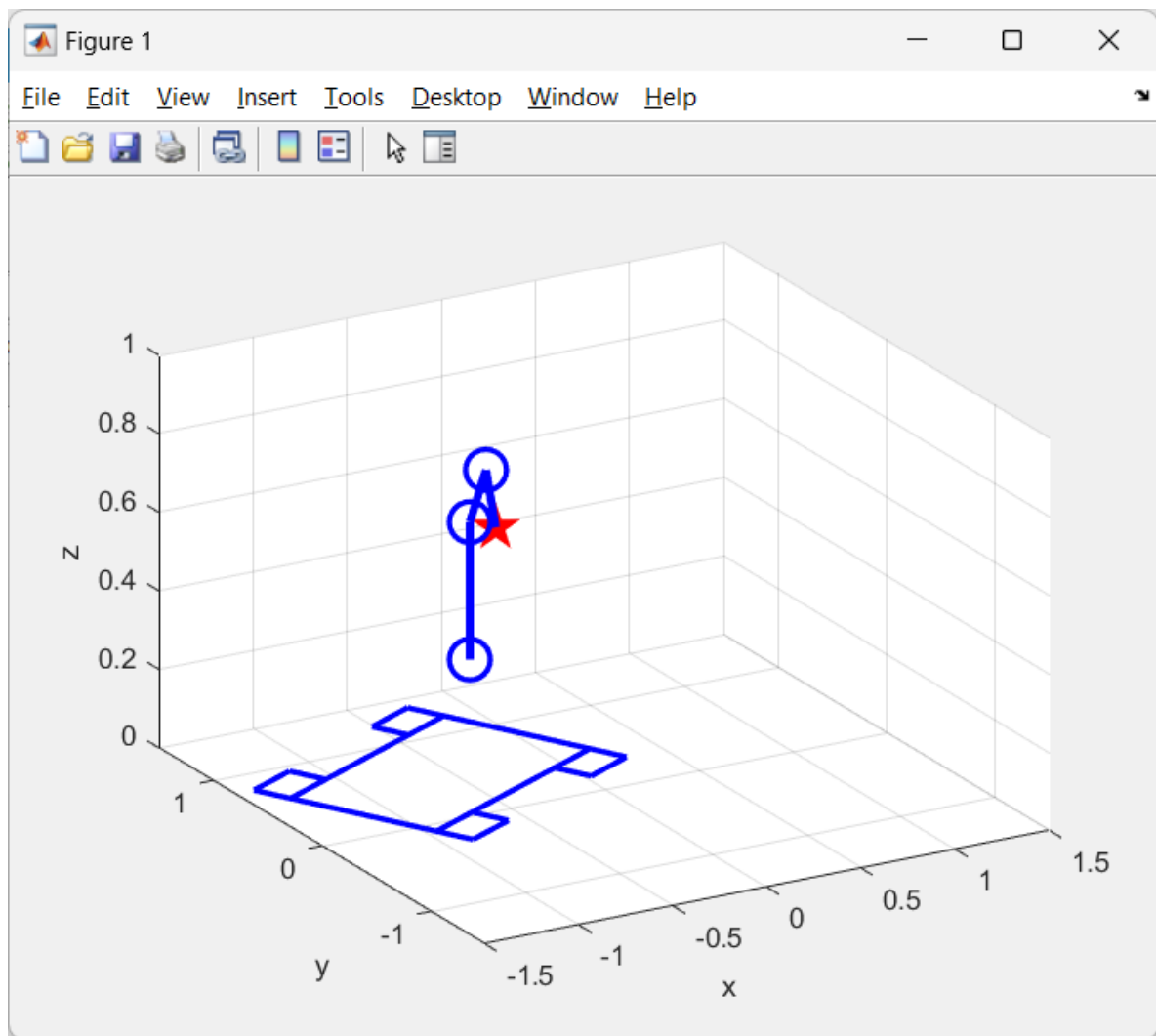


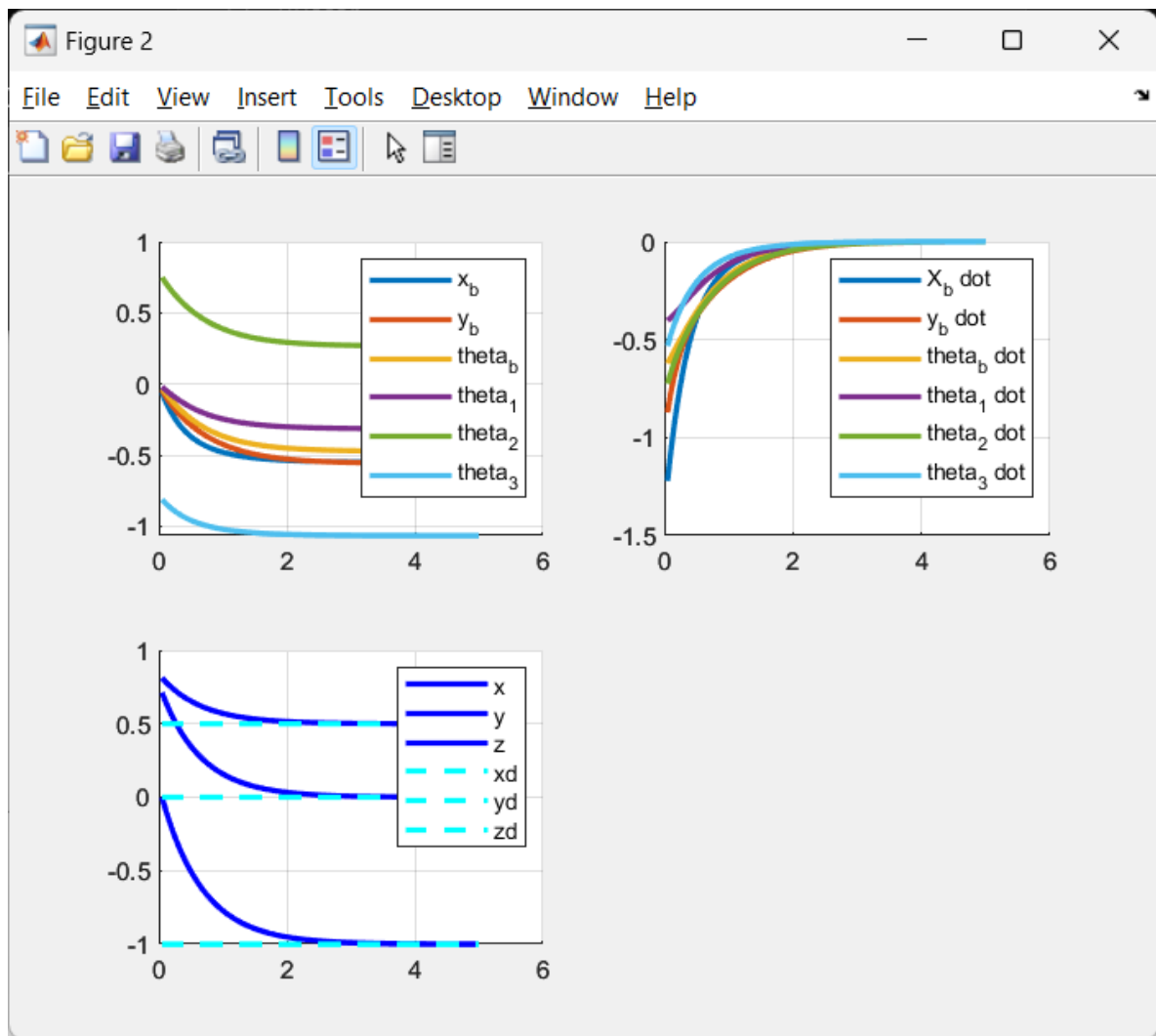


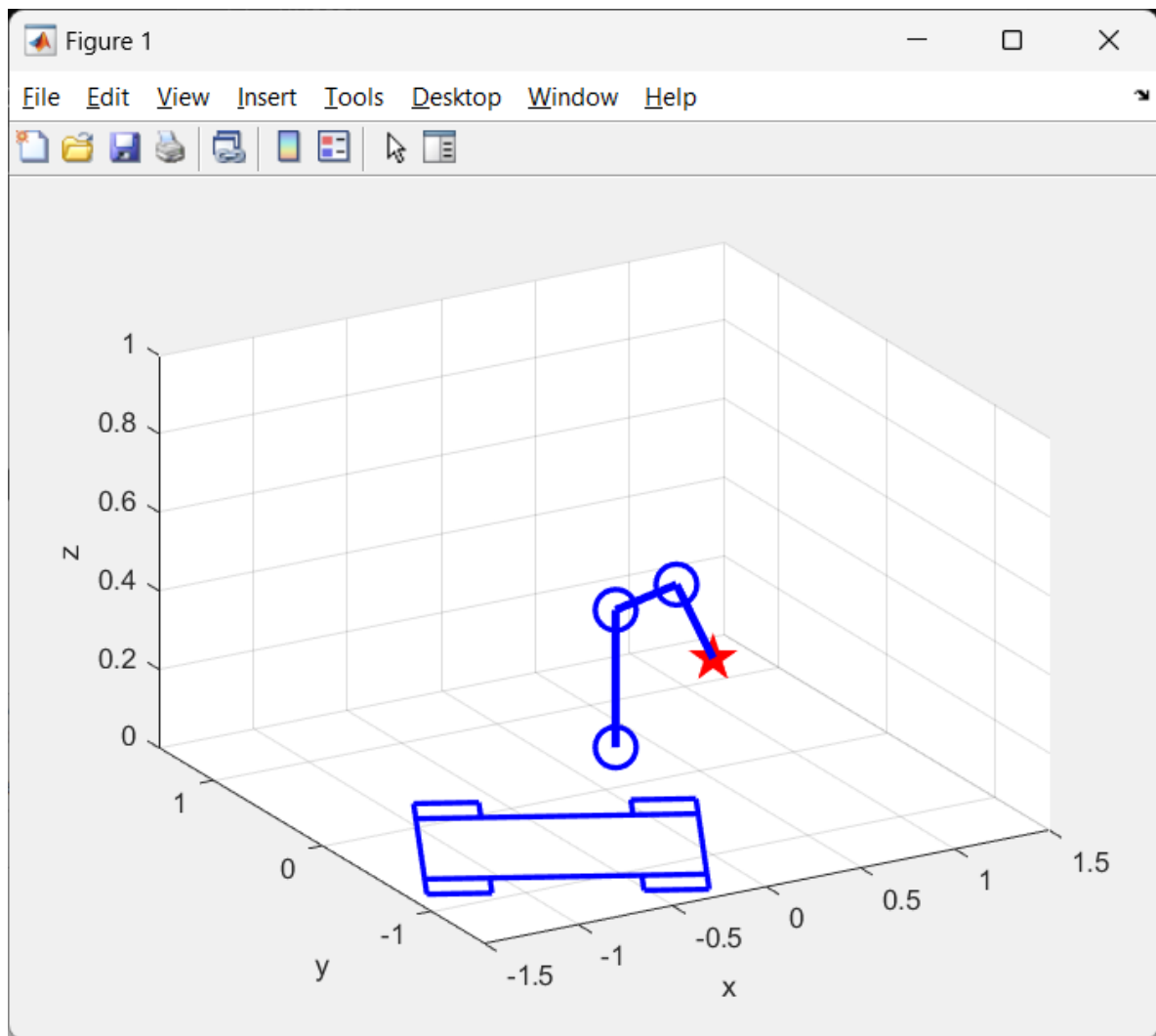


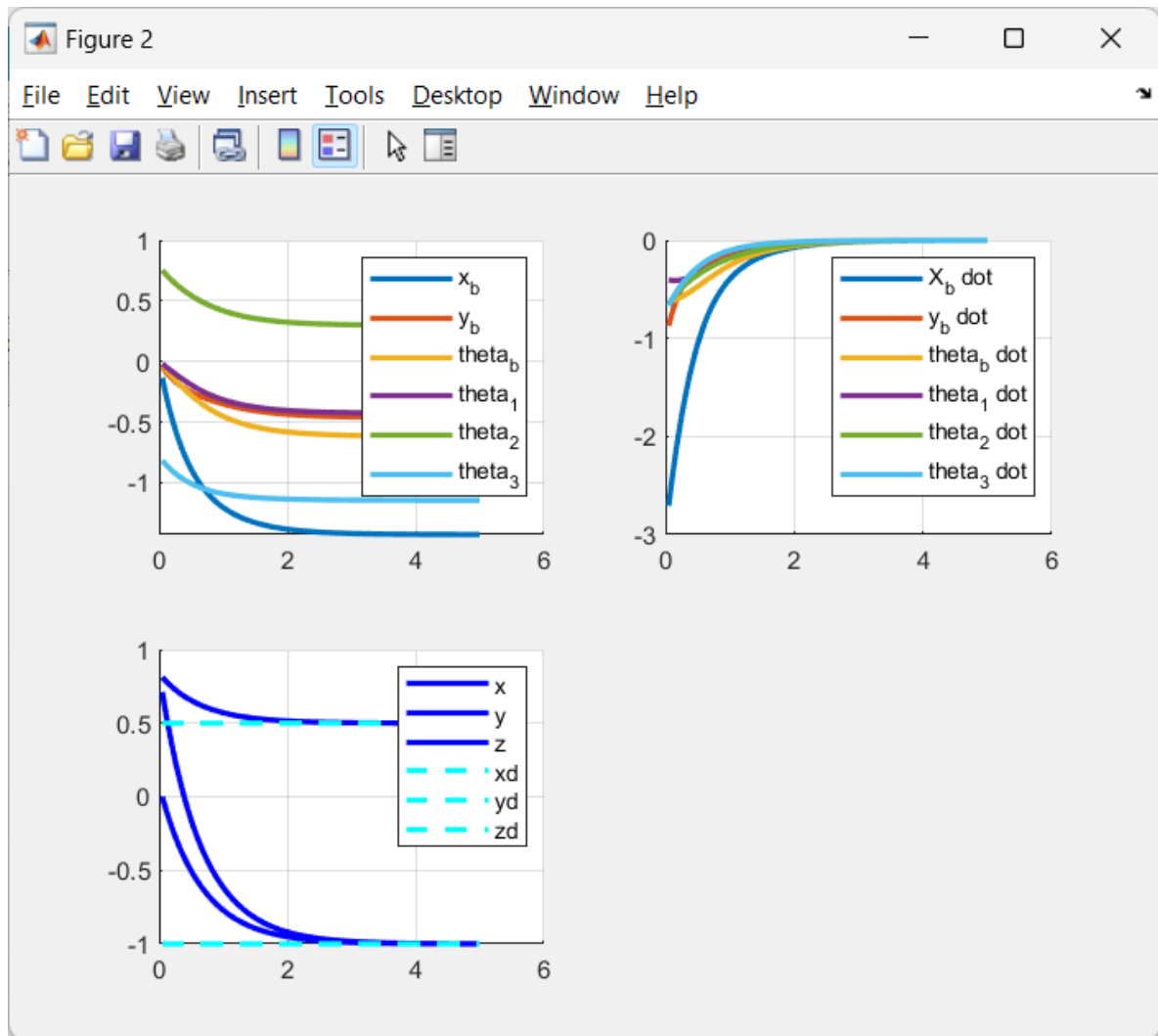


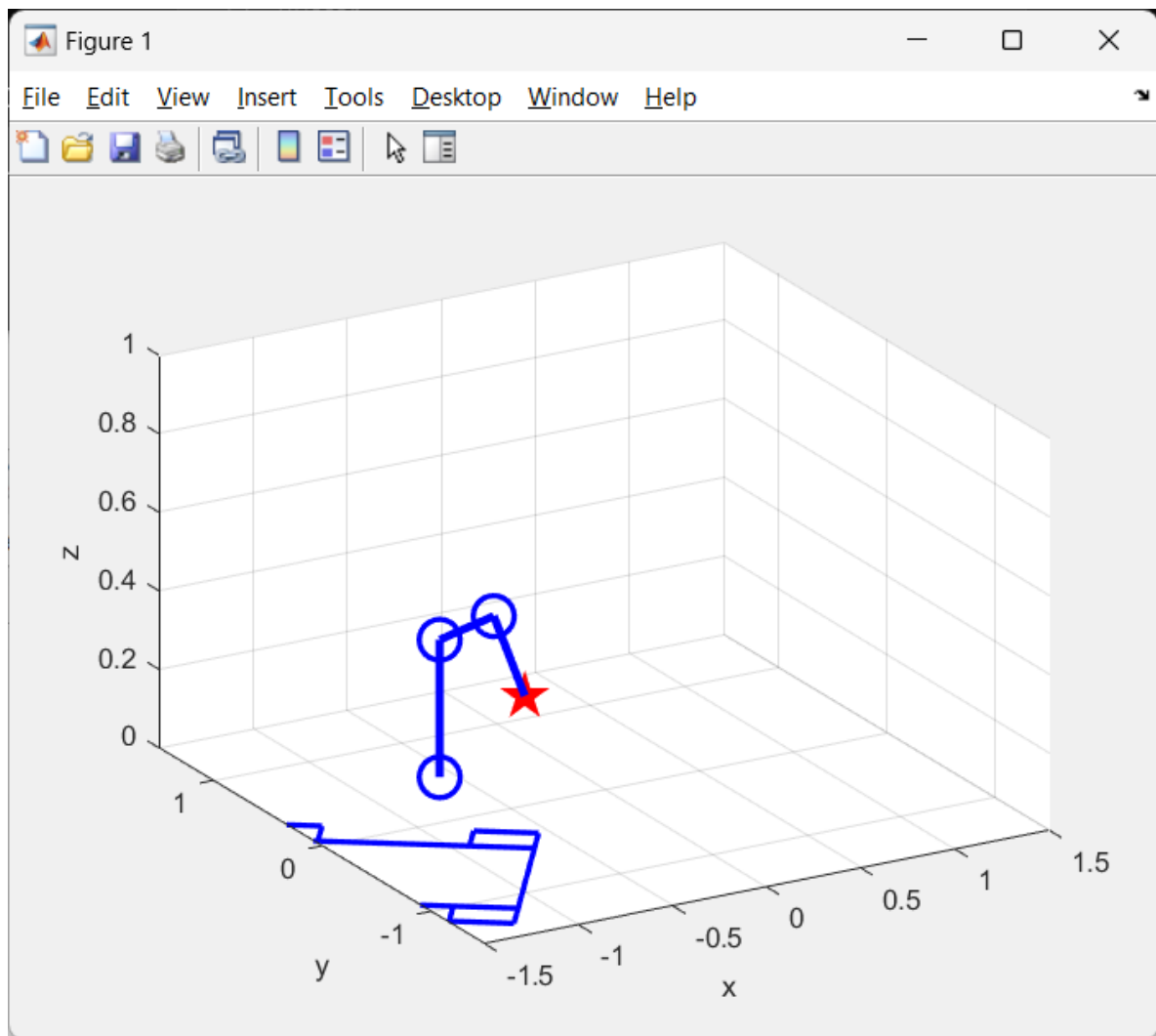


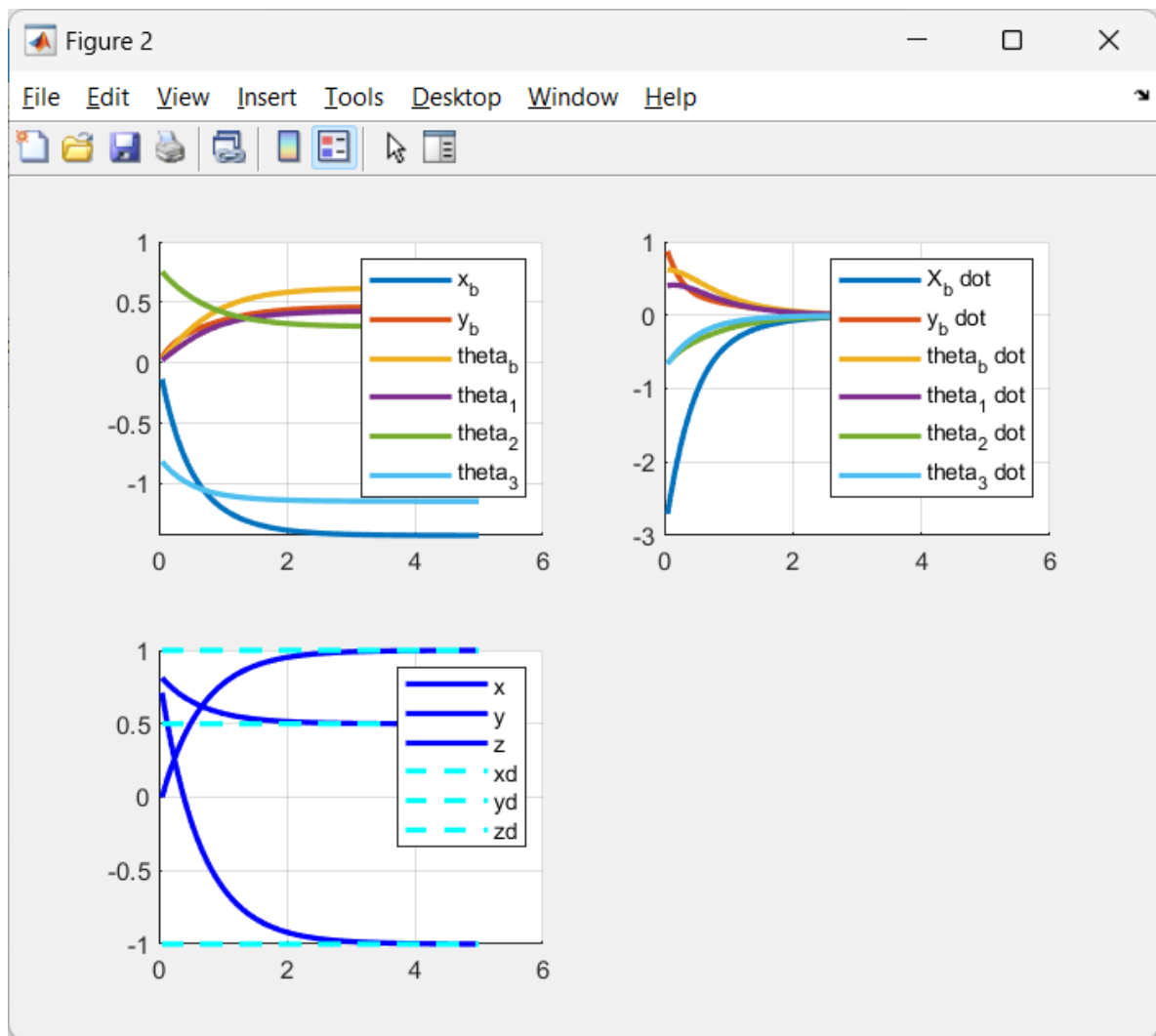


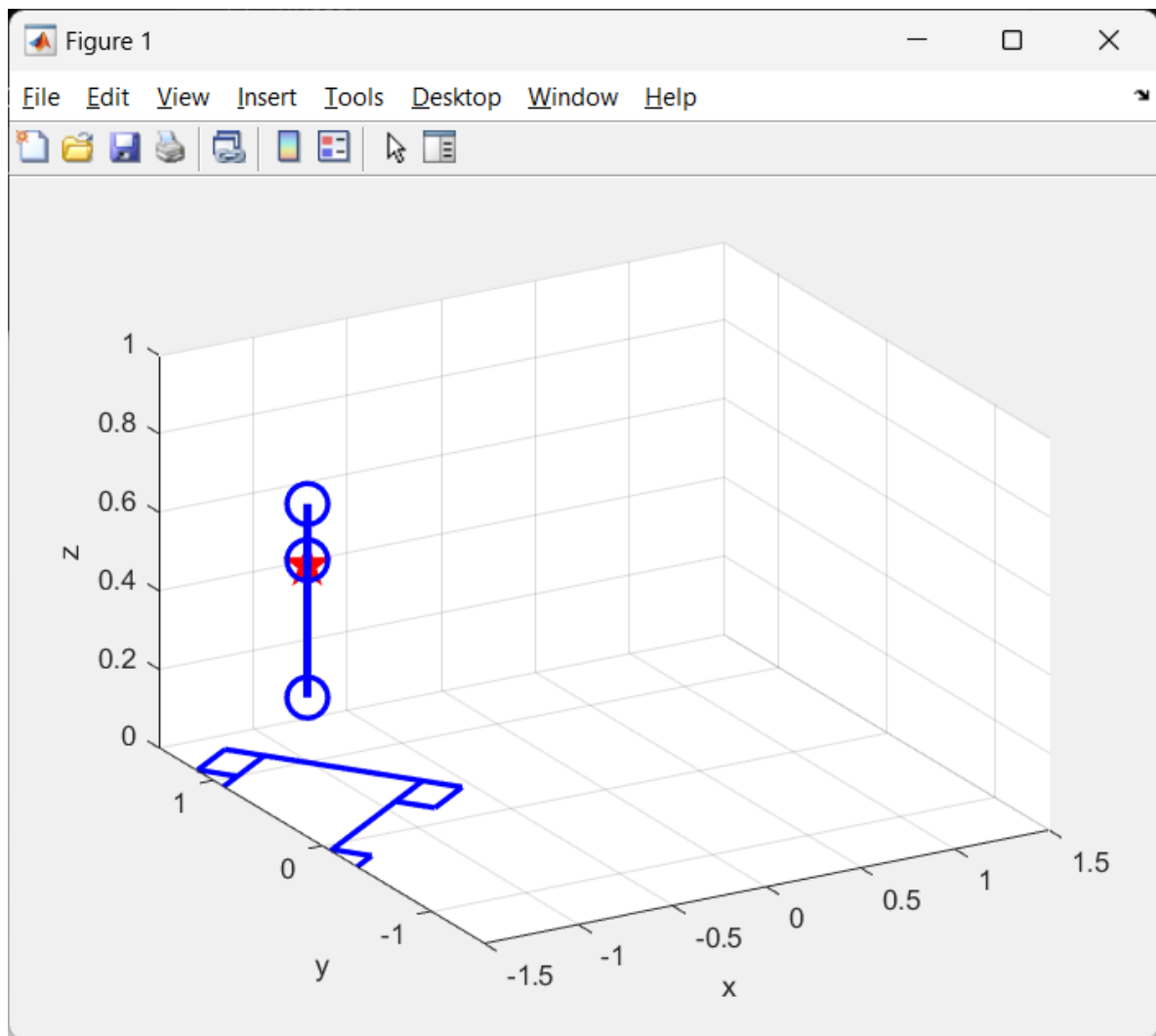




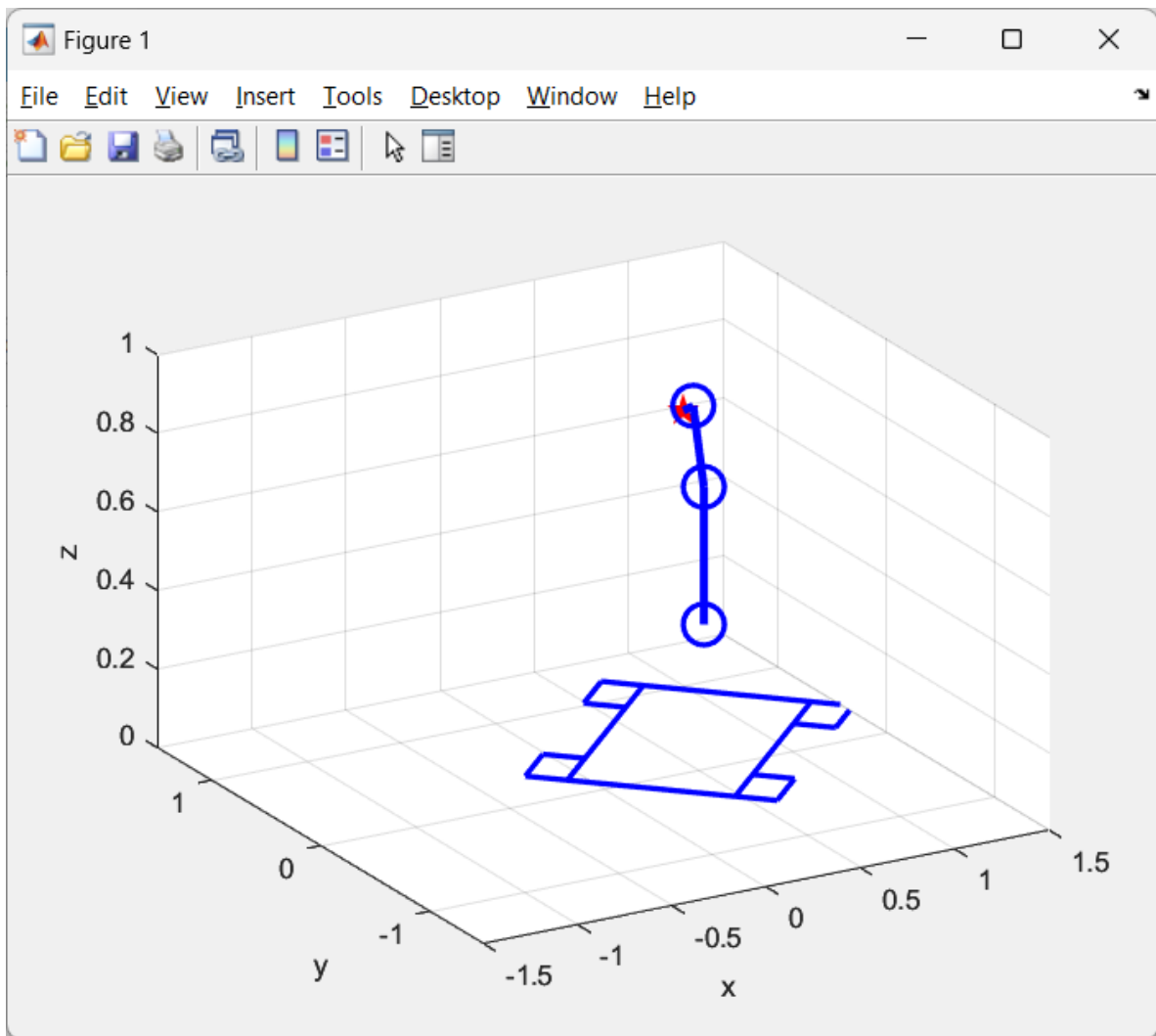


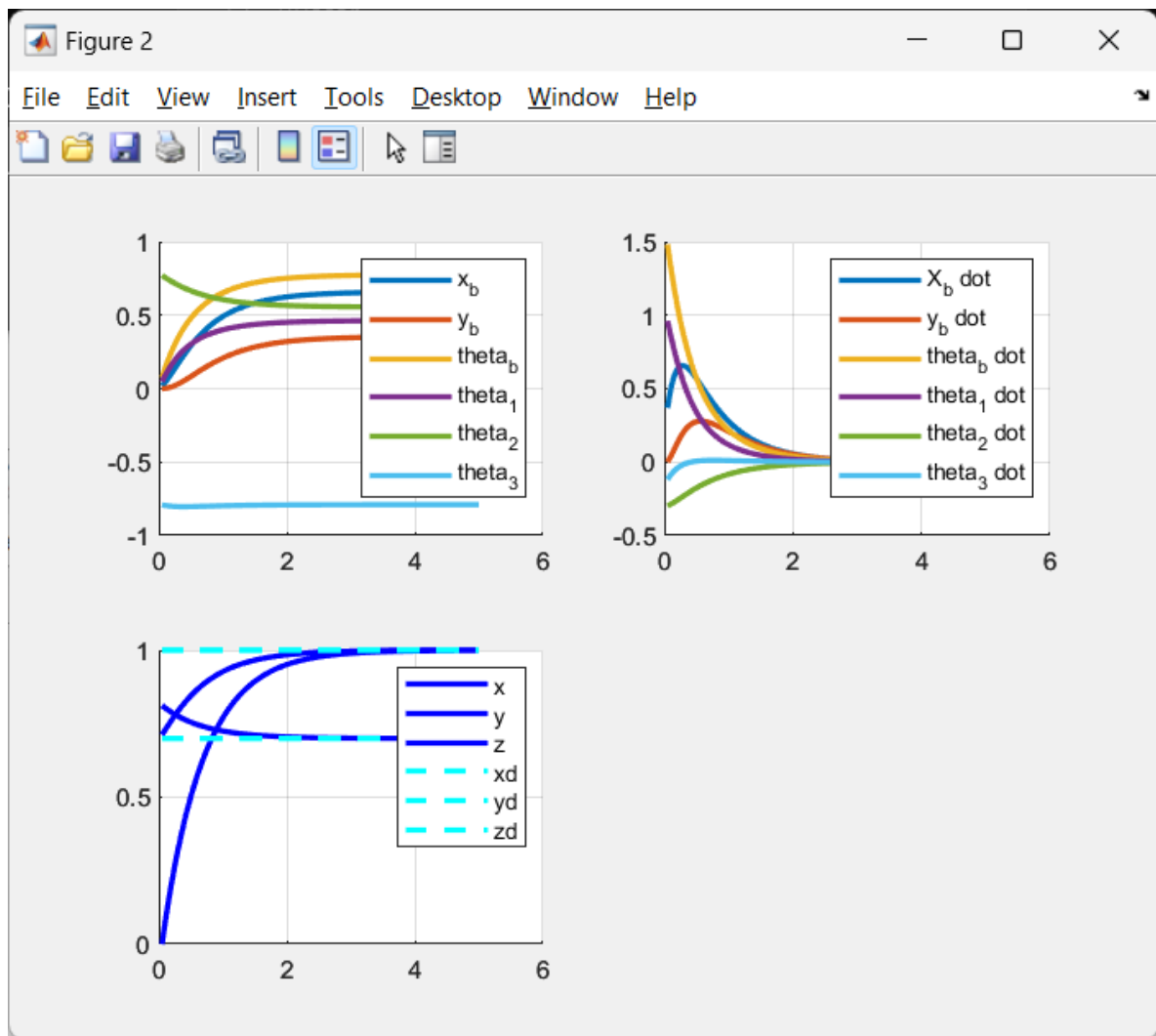


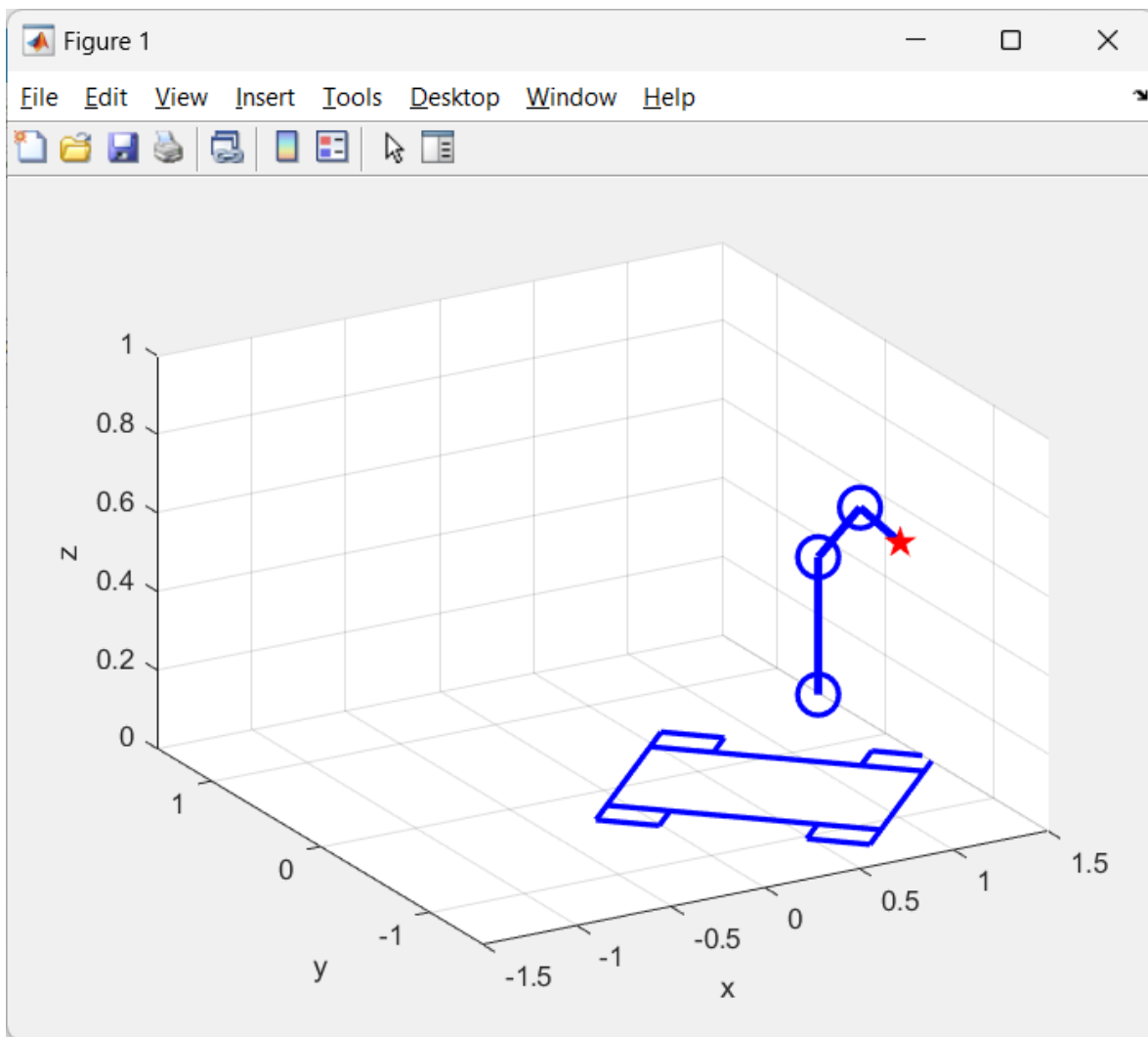


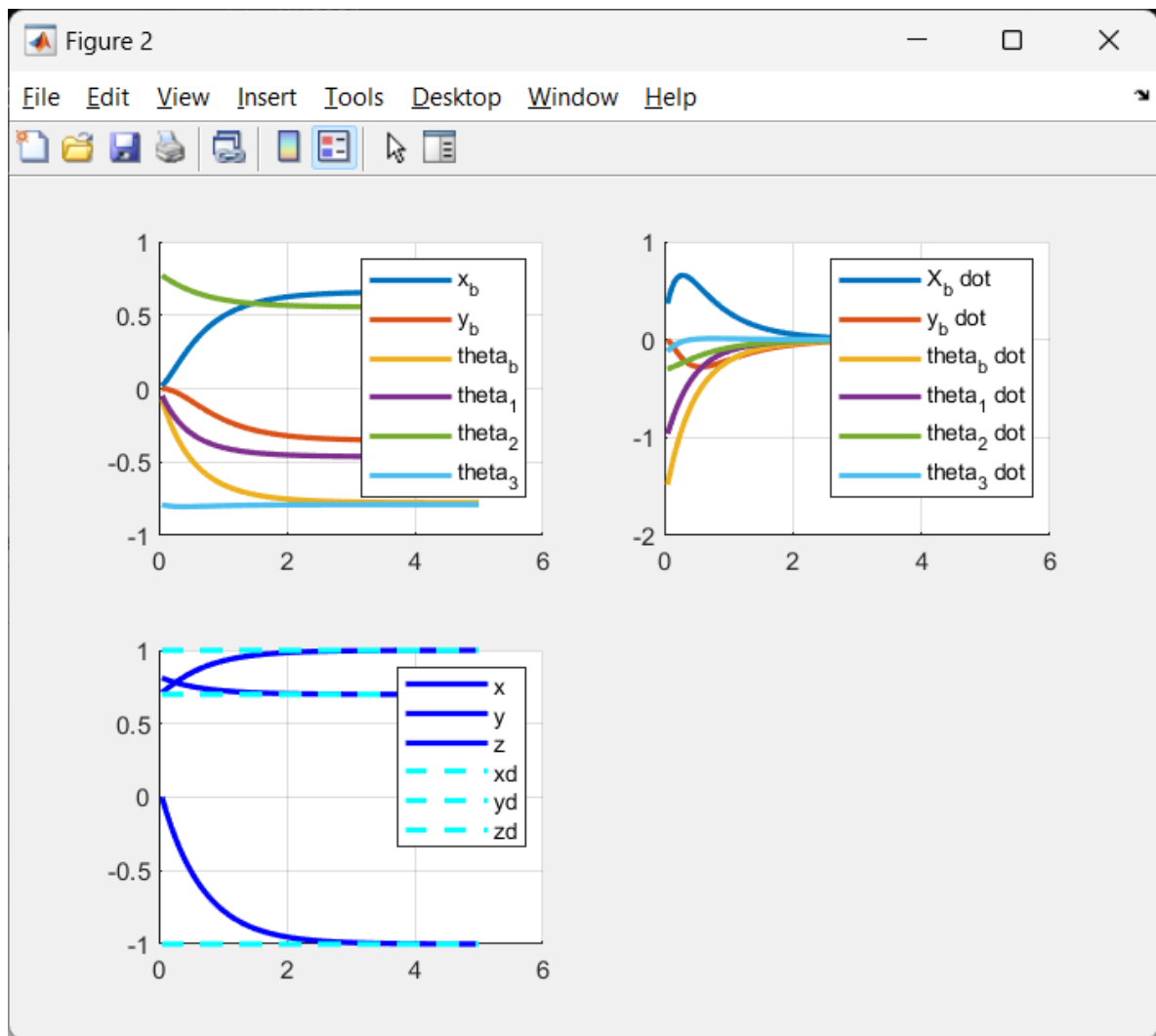


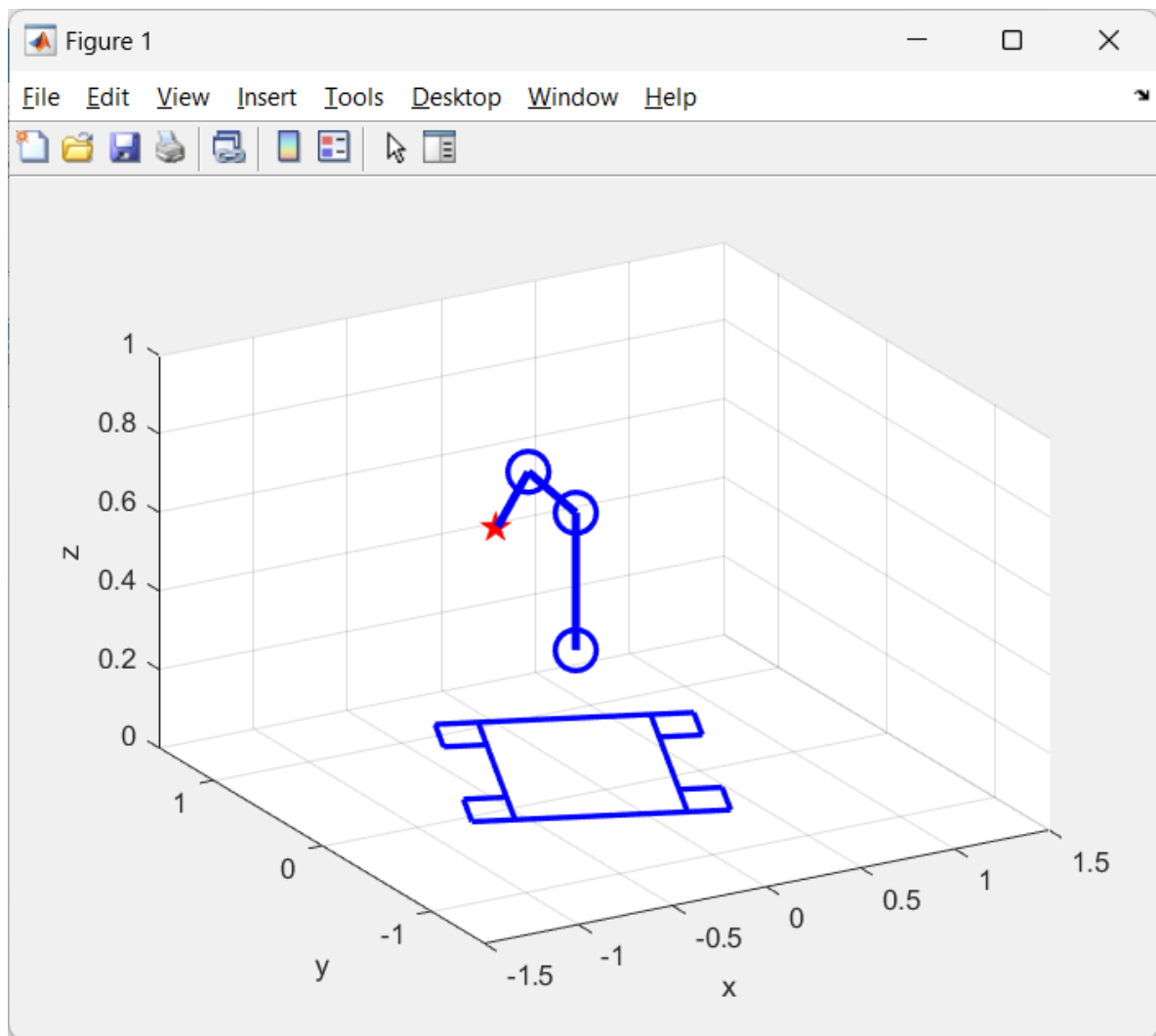
- **Ejercicio 2**

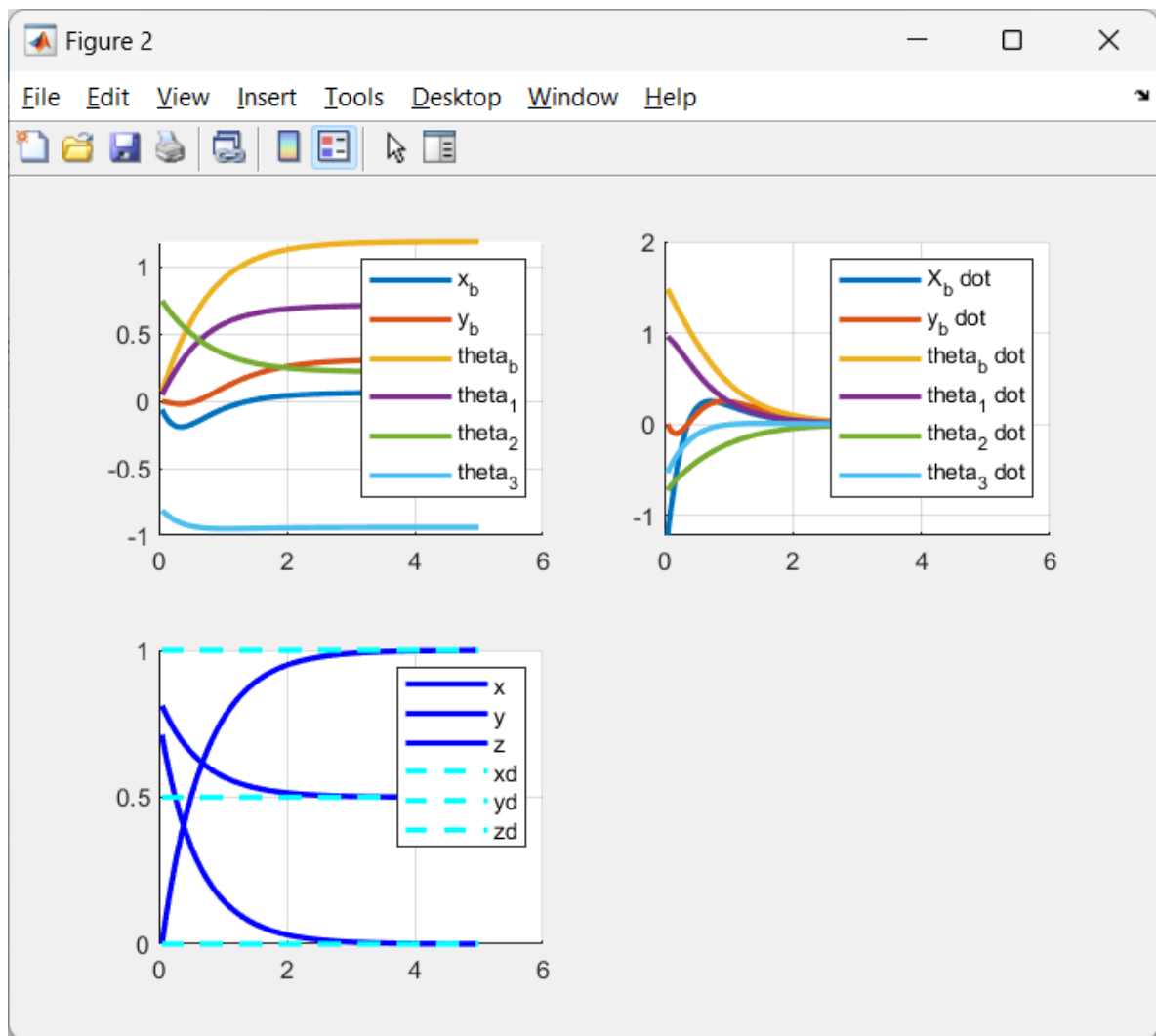


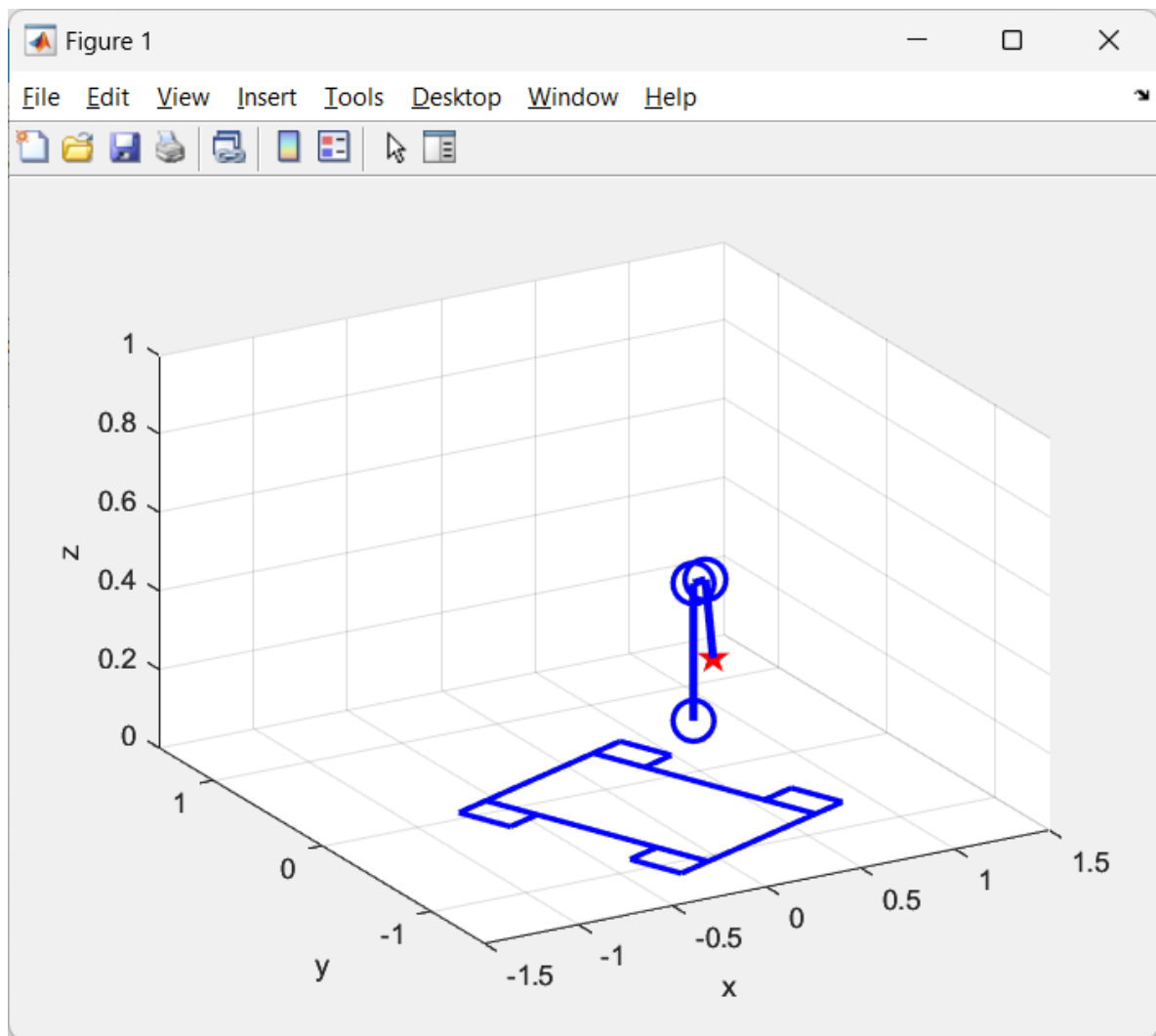


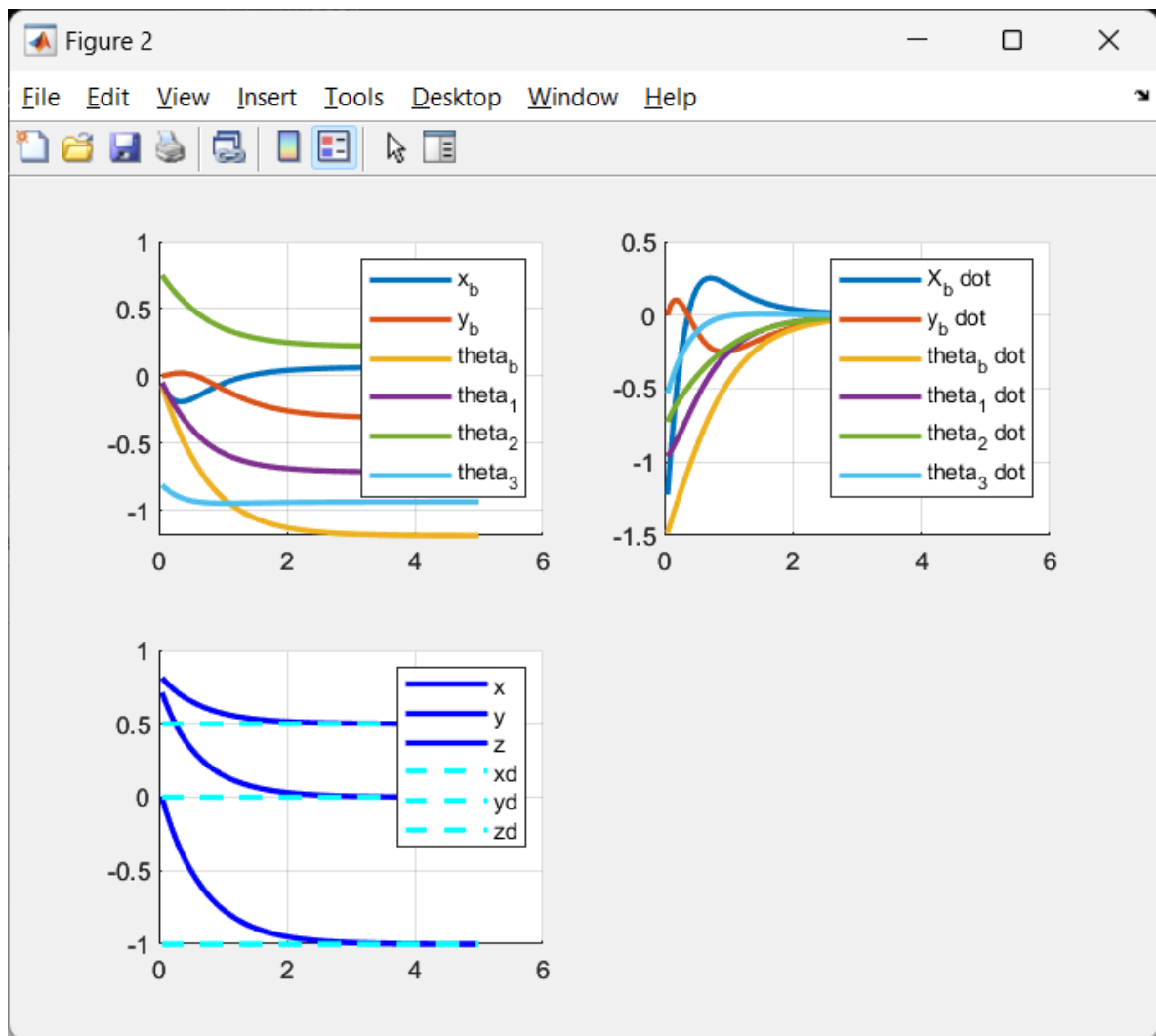


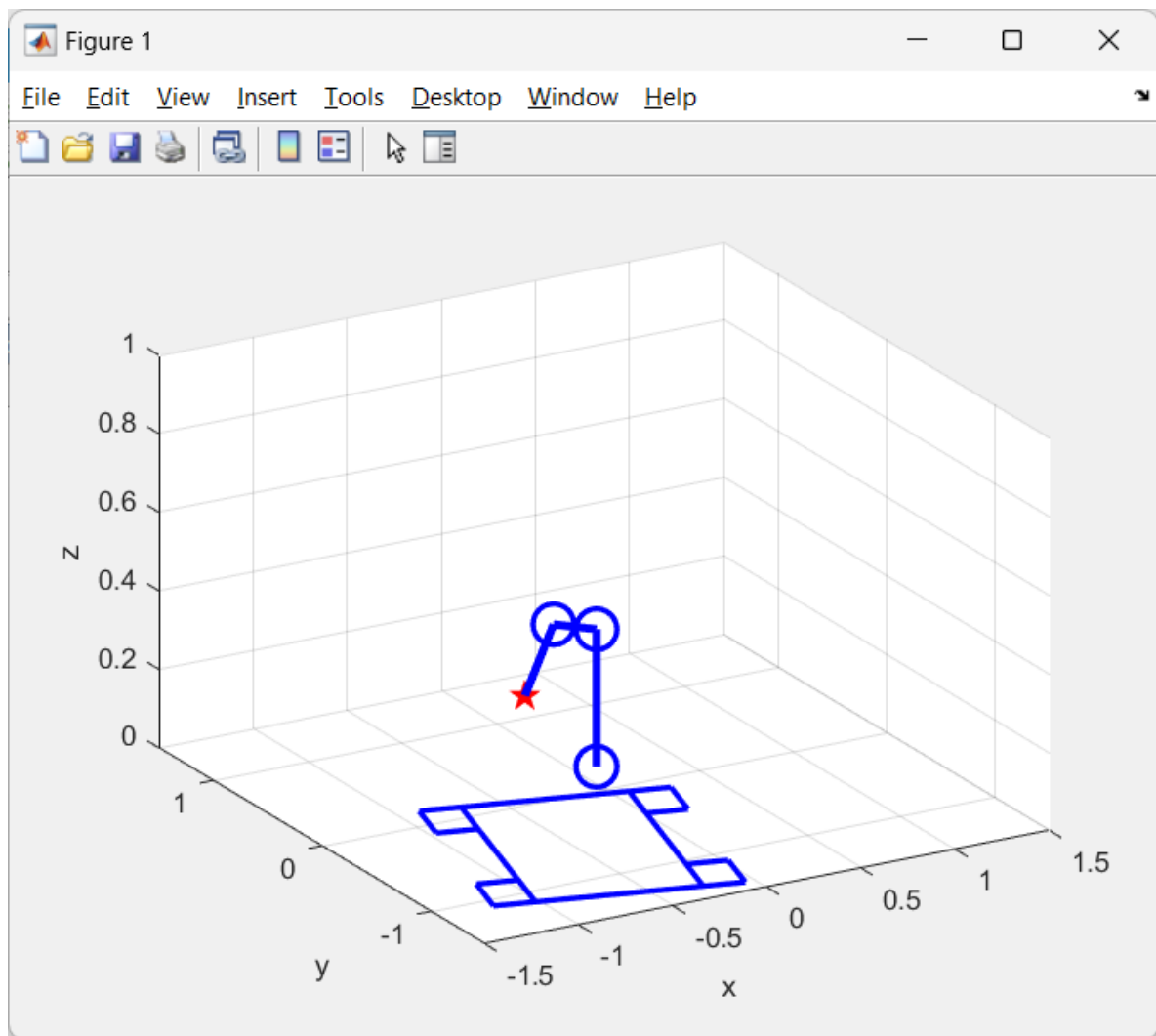


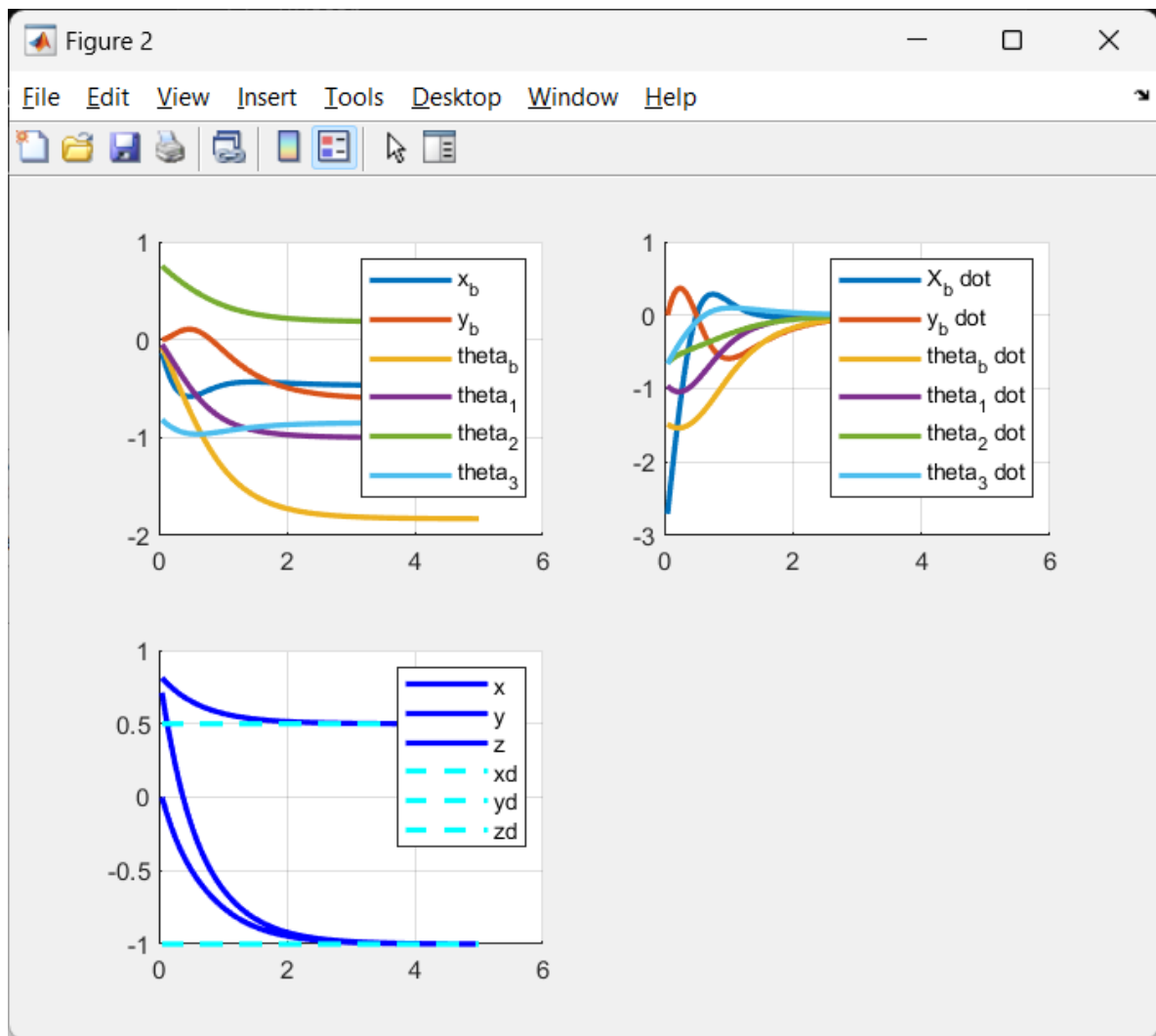


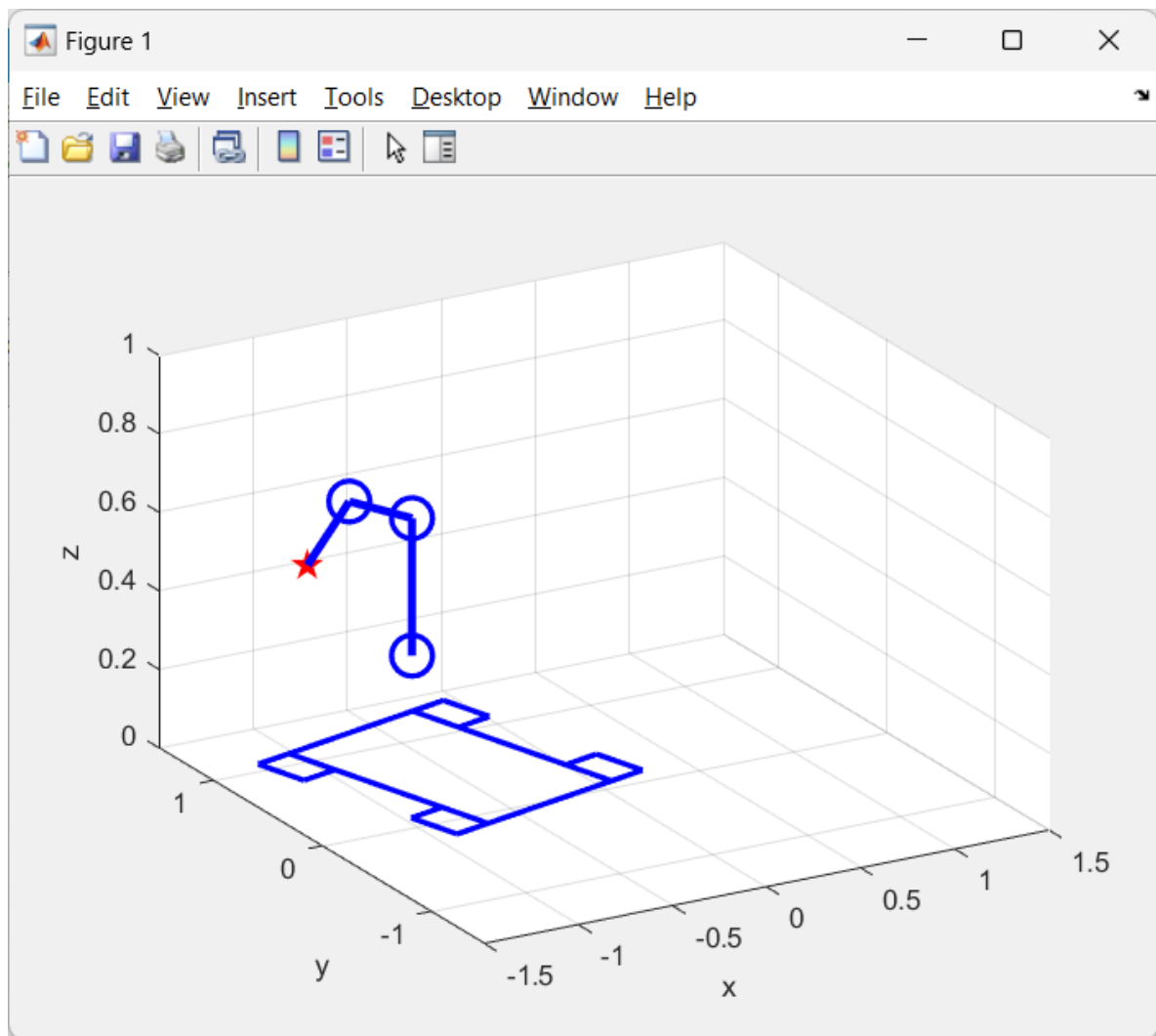














Conclusión

Estudiamos el comportamiento de un robot móvil con manipulador, gracias a las gráficas de posición y velocidad, obtenidas con ayuda de las ecuaciones del modelo cinemático inverso y también la manera de hacer su simulación usando cinemática directa .