**A6P1 –**

The following is the command line which runs a setup provided by me751.mdl.

[engine,engine2] = simEngine3D\_A6P1('me751');

The quantities of interest should be engine.myPhi, engine.myJac , engine2.myPhi, engine2.myJac.

**A6P2 -**

[engine] = simEngine3D\_A6P2('revJoint');

Quantities of interest will be displayed automatically

**A6P3 –**

[engine] = simEngine3D\_A6P3('revJoint');

Plots will be displayed automatically. To start off, I believe there is something wrong with my solver. Looking at my acceleration for the Z value of the point O’x’y’z’, I feel like it shouldn’t be strictly negative. I will have to double check with someone to make sure the mistake is real, then correct it for further implementations of the constraints.





As far as the graphs for point sQi, I believe they are correct. They are extremely close to 0 (which they should be, since the point is pinned), and the noise seen likely stems from the fact we are using a Newton-Raphson solver to try and drive the residual equations to zero. Since the residuals will never truly be equal to zero, this small noise in the position analysis will propagate and be amplified (by being multiplied by a Jacobian^-1) to the velocity and acceleration analysis as well.