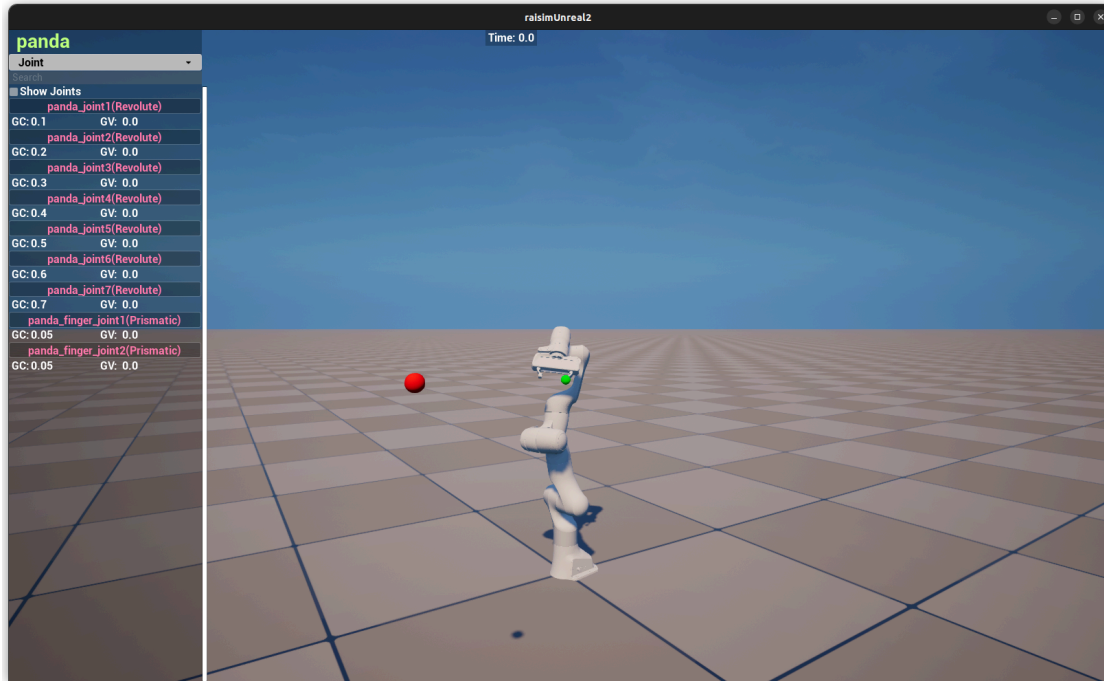


KAIST ME553 Robot Dynamics

Instructor: Jemin Hwangbo, Mechanical Engineering

Exercise 1

You will be using the Panda model for this exercise. You should download or clone the exercise repo here: https://github.com/jhwangbo/ME553_2025. When you run raisimUnreal2.exe and exercise1.exe, you should see this screen.



On the left 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 “panda_finger_joint3” in the list. Check it to display it on the screen. You can also see that a green ball is placed at the joint position (joint frame’s origin).

Your goal is to write a function that computes the position of the “panda_finger_joint3” **given any joint angles**. You can find the description of the robot in “resource/Panda/panda.urdf”. You can find about the URDF convention here: <http://wiki.ros.org/urdf/XML>

Deliverable: A single header file named “exercise_1_STUDENTID.hpp”. Use the provided template. You should replace “STUDENTID” with your real student id number. Submit it on KLMS.

Deadline: by the end of 2nd of April, 2025