

Report for HomeWork 5

To begin with, the robot in this homework has 2 joints. The first one is revolute, while the second one is prismatic. But on the picture the first one is number 2, while the second one is number 1. Forward kinematics matrix was created and after that every center of mass was founded. All Jacobians were created by using skew theory. The main equation is " $\tau = D \ddot{q} + C \dot{q} + G$ ". So, main goal is to find D, C and G matrices. Which were done in matlab "main" file.

Torques were taken with values 1 and 1 and after that position and velocity graphs were created. In this work revolute joint is q_1 , while s is a prismatic joint parameter.

Link to the project on github - <https://github.com/adilermek1/HomeWork5-DnRs.git>