Lab Assignment 4

Q1) Justify the statement that "*Rotations are non-commutative in 3D*".

Instruction: Show the Matlab operations with example. You can put snapshots in your answer sheet and give relevant explanation.

Refer Text book Robotics Vison and Control by Peter Corke page 29-35

Q2) Describe twist in 2D.

Use matlab functions to show how to regenerate homogeneous transformations

Refer Text book Robotics Vison and Control by Peter Corke page 29-35

Q3) Demonstrate the Toolbox function tranimate which animates a rotation using Matlab.

Refer Text book Robotics Vison and Control by Peter Corke page 29-35