

RBE 501 Week 1 Assignment

1st Arjan Gupta
Robotics Engineering
Worcester Polytechnic Institute
Worcester, MA, USA
agupta11@wpi.edu

Abstract—This document provides an in-depth solution for Problem 2–37 described in *Robot Modeling and Control*. This is the assignment for the first week in RBE 501 (Robot Dynamics), Spring 2023 at Worcester Polytechnic Institute.

Index Terms—robotics, homogeneous transformation, frames

I. INTRODUCTION

We are asked to solve Problem 2–37 of the main textbook [1]. Here, a robot is near a table, with a camera placed over the table to supervise the robot. A cube is also placed in the center of the table-top. The objective of the problem is to express all the frames in the environment (frame for the edge of the table, frame for the cube, and frame for the overhead camera) in terms of the homogeneous transformations with respect to the base frame, situated at the base link of the robot. An additional objective of the problem is to find the homogeneous transformation relating the center of the cube's frame to the camera's frame. The graphic below, given in the textbook, gives a pictorial representation of the problem.

II. MATERIALS AND METHODS

The IEEEtran class file is used to format your paper and style the text. All margins, column widths, line spaces, and text fonts are prescribed; please do not alter them. You may note peculiarities. For example, the head margin measures proportionately more than is customary. This measurement and others are deliberate, using specifications that anticipate your paper as one part of the entire proceedings, and not as an independent document. Please do not revise any of the current designations.

REFERENCES

- [1] M. W. Spong, S. Hutchinson, and M. Vidyasagar, “Robot modeling and control,” 2006.

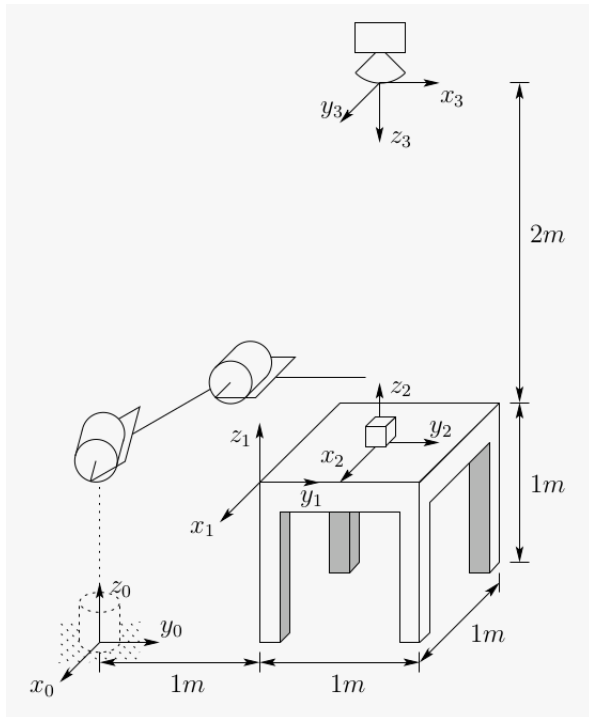


Fig. 1. Figure for 2–37