**COMPUTER PROJECT 2**

I was able to complete the entire project and generate the required joint angles. The top level matlab script is ‘Project2\_Final’. I wrote two separate functions, one to compute the actual position of the tooltip by forward kinematics, and the other to compute the jacobian of the tooltip. I incorporated these functions and implemented the Damped Least Squares equation to calculate the error in the joint angles.

I used (m+1) in the ‘for’ loop as the m given in the trajectory file is 31 but there are 32 desired points in the same file.

I also tried implementing it in RobotStudio but there seems to be linking problem. I will solve it after exams.