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% ECE 4560 - Homework 8.2
% Caitlyn Caggia
%part a: forward kinematics
syms a1 a2 a3 a4 10 11 12;
g1 = [SE3.RotZ(a1) [0; 0; 10]; 0 0 0 1];
q2 = [SE3.RotX(a2) [0; 0; 0]; 0 0 0 1];
g3 = [SE3.RotZ(a3) [0; 11; 0]; 0 0 0 1];
g4 = [eye(3) [0; 12; 0]; 0 0 0 1];
geparta = g1*g2*g3*g4
%part b: visualization
10 = 1; 11 = 0.75; 12 = 0.5;
alpha1 = (-90:5:90) * pi()/180;
alpha2 = (-45:5:60) * pi()/180;
alpha3 = (-90:5:90) * pi()/180;
alpha1Cnt = numel(alpha1);
alpha2Cnt = numel(alpha2);
alpha3Cnt = numel(alpha3);
total = alpha1Cnt*alpha2Cnt*alpha3Cnt;
x = zeros(1, total);
y = zeros(1,total);
z = zeros(1,total);
11 = 1;
for ii=1:alpha1Cnt
    for jj=1:alpha2Cnt
        for kk=1:alpha3Cnt
            x(11) =
 (11+12*cos(alpha3(kk)))*sin(alpha1(ii))*cos(alpha2(jj)) ...
                -12*cos(alpha1(ii))*sin(alpha3(kk));
            y(11) =
 (11+12*cos(alpha3(ii)))*cos(alpha1(ii))*cos(alpha2(jj)) ...
                -12*sin(alpha1(ii))*sin(alpha3(kk));
            z(11) = 10 + (11+12*cos(alpha3(kk)))*sin(alpha2(jj));
            11 = 11+1;
        end
    end
end
x = reshape(x, [alpha2Cnt*alpha3Cnt, alpha1Cnt]);
y = reshape(y, [alpha2Cnt*alpha3Cnt, alpha1Cnt]);
z = reshape(z, [alpha2Cnt*alpha3Cnt, alpha1Cnt]);
surf(x,y,z);
%part c: end-effector configuration
a = [pi/3; pi/3; -pi/4];
g1 = [SE3.RotZ(a(1)) [0; 0; 10]; 0 0 0 1];
g2 = [SE3.RotX(a(2)) [0; 0; 0]; 0 0 0 1];
q3 = [SE3.RotZ(a(3)) [0; 11; 0]; 0 0 0 1];
g4 = [eye(3) [0; 12; 0]; 0 0 0 1];
gepartc = g1*g2*g3*g4
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geparta =
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 [ \cos(a1)*\cos(a3) - \cos(a2)*\sin(a1)*\sin(a3), - \cos(a1)*\sin(a3) - \cos(a2)*\cos(a3)*\sin(a1), \sin(a1)*\sin(a2), - 12*(\cos(a1)*\sin(a3) + \cos(a2)*\cos(a3)*\sin(a1)) - 11*\cos(a2)*\sin(a1)] ] \\ [ \cos(a3)*\sin(a1) + \cos(a1)*\cos(a2)*\sin(a3), \cos(a1)*\cos(a2)*\cos(a3) - \sin(a1)*\sin(a3), -\cos(a1)*\sin(a2), 11*\cos(a1)*\cos(a2) - 12*(\sin(a1)*\sin(a3) - \cos(a1)*\cos(a2)*\cos(a3))] \\ [ & \sin(a2)*\sin(a3), & \cos(a3)*\sin(a2), & \cos(a3), & \cos(a3),
```

## gepartc =

-0.3011	0.7500	0.0474	0.6597
0.5821	-0.4330	0.7891	0.4356
1.9557	0.5000	0.6124	-0.6124
1.0000	0	0	0



