

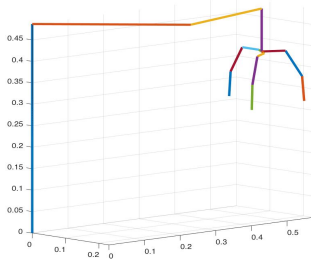
ROBOT INVERSE KINEMATICS USING SQP METHOD

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PROBLEM FORMULATION



A configuration of the system consists of the pair (p_{ab}, R_{ab}) , and the configuration of the system is the product space of \mathbb{R}^3 with $SO(3)$, which shall be denoted as $SE(3)$ (for special Euclidean group):

$$SE(3) = \mathbb{R}^3 \times SO(3)$$