

P4 Report: dgp34

In this project, a second joint was added to the minimal robot and both joints were commanded to move at unique, hard-coded frequencies. Due to gravity, the effect on the robot is not as one might expect, creating chaotic motion. This motion would be highly stressful on joints, arms, motors, etc. if the model were real and this code were actually implemented.

The motion can be edited by going to `sin_commander.cpp` and editing the defined `FREQ1` and `FREQ2` values. Different values would produce different motions. The current values chosen are arbitrary, and are therefore as valid as any other combination. Feel free to change in order to satisfy a desire for idle entertainment.