Saturday 29, 9:15 – 9:45 PM

*Start:*

Right now, I am working on creating a 2R optimization solver using an example code from the Crocoddyl library. Looking at .urdf files, the double pendulum is exactly the same as a 2R robot, with a world link, 2 robot joints, and 2 robot links. It looks like the geometry of 2R robot geometry is specified in .stl file created using Solid Works to Urdf [ROS](http://wiki.ros.org/sw_urdf_exporter) program.

Monday 31, 12:45 AM –

*Goal:*

There are two things needed to transform optimization of pendulum into optimization of 2R robot.

1. Add another actuator to the second joint
2. Rephrase terminal and running cost in terms of running cost

Let’s separate these tasks. First (1), then (2).