|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| f\_dyn\_nb2 | f\_dyn | **calc\_hh**  system inertia matrix  3.19-3.24 | **calc\_jt**  centroids transl Jac  3.25 |  |
|  |  |  | **calc\_jr**  centroids rotat Jac  3.26 |  |
|  |  | **calc\_je**  endpont transl/rotat Jac  3.25-3.26 | **calc\_jte**  endpoint transl Jac  3.25 | **f\_kin\_e**  endpoint pos/rot |
|  |  |  |  | **f\_kin\_j**  joints pos/rot up to endpoint |
|  |  |  | **calc\_jre**  endpoint rotat Jac  3.26 |  |
|  |  | **r\_ne**  inverse dynamics RNE  3.30-3.39 | **calc\_acc**  acc all links  R=3.10-3.11,P=3.14-3.15 |  |
|  |  |  | **calc\_vel**  vel all links  R=3.8-3.9, P=3.12-3.13 |  |
|  |  | **calc\_aa**  centroid/joint rot. matrix  int. eqs. R=3.8, P=3.12 |  |  |
|  |  | **calc\_pos**  pos all links  int. eqs. R=3.9, P=3.13 |  |  |
|  |  | **j\_num**  links sequence to endpoint |  |  |
|  | rotW |  |  |  |