KAIST ME553 Robot Dynamics

Instructor: Jemin Hwangbo, Mechanical Engineering

We provide two different exercises: CRBA+RNE exercise; ABA exercise. Even though it is highly recommended that you try both, you will grade only on one of them. If you submit both, your grade will be based on the better one.

Clone your project file at https://github.com/HuboLabKaist/KAIST_ME553

Exercise 8

You are going to compute the mass matrix and nonlinear term for a floating-base system (ANYmal with one leg). Use CRBA and RNE. If you use other methods, you will not grade for the submission.

Deliverable: A single header file named “exercise_9_STUDENTID.hpp”. Use the provided template. You should replace “STUDENTID” with your real student id number. Submit it on KLMS.

Exercise 9

You are going to compute the generalized acceleration for a fingerless kinova model. Use the **articulated body algorithm.**

Deliverable: A single header file named “exercise_9_STUDENTID.hpp”. Use the provided template. You should replace “STUDENTID” with your real student id number. Submit it on KLMS.

Deadline: 10pm, 10th of June