RobotLib Examples using the Pendulum
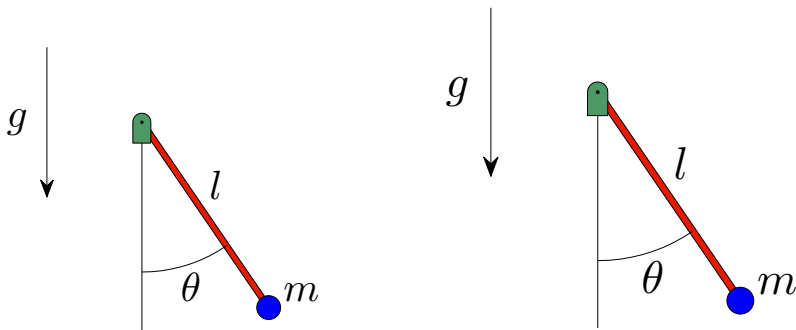
The Robot Locomotion Group

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Dynamics (PendulumPlant)

Equations of motion:

$$ml^2\ddot{\theta} + b\dot{\theta} + mgl\sin\theta = \tau$$

Note: The same dynamics are also available with
PlanarRigidBodyManipulator('Pendulum.urdf')