KAIST ME553 Robot Dynamics

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Exercise 7

Download the latest code here: https://github.com/jhwangbo/ME553_2022. If you already have the project, simply pull the changes (using git).

The goal of this Exercise is to find the generalized acceleration of a **simplified kinova robot (no fingers)**. You can find the robot description “resource/kinova/robot.urdf”. You must use the “**Articulated body algorithm**” to compute the generalized acceleration.

Deliverable:

1. A single header file named “exercise7_STUDENTID.hpp” which outputs the generalized acceleration term of the system given the generalized coordinate and the generalized velocity. Use the provided template. **You should replace “STUDENTID” with your real student id number**. Submit it on KLMS.

Deadline: 5pm, 10th of June