alphaf\_generated = jTraj.alpha(end, :);

alphaf\_generated = alphaf\_generated(1:5)

gf\_generated = double(subs(g, [l0 l1 l2 l3 l4 a1 a2 a3 a4 a5], [linklen(1:end) alphaf\_generated(1:end)]))

gerr = gf\_generated\gf

eps\_err = logm(gerr);

eps\_err = SE3.unhat(eps\_err)

eps\_err\_norm = norm(eps\_err(1:5))

posf\_gen = double(subs(ee\_pos, [l0 l1 l2 l3 l4 a1 a2 a3 a4 a5], [linklen(1:end) alphaf\_generated]))

Posf

rhosq = .05;

dampedPInv = Jb(1:3, :)' \* inv((Jb(1:3, :) \* Jb(1:3, :)' + rhosq \* eye(3)));

% aDot = pinv(Jb(1:3, :))\*speedbody(1:3);

aDot = dampedPInv \* speedbody(1:3);