

Output q Matrix

DRC Sim

INPUT

OUTPUT

cancel this for now

3D Plot

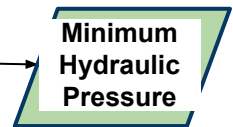
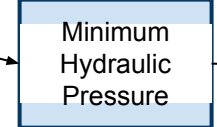
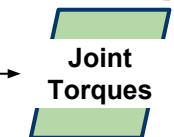
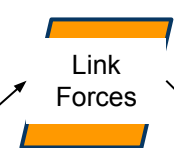
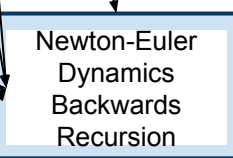
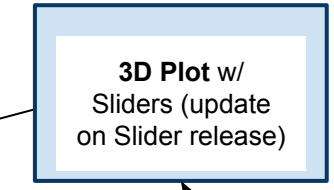
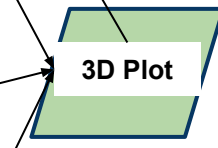
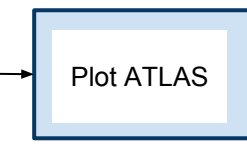
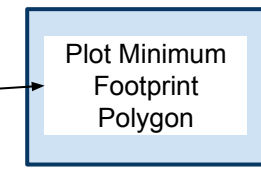
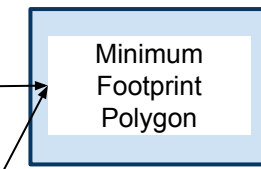
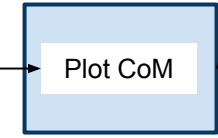
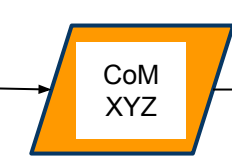
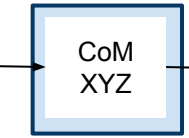
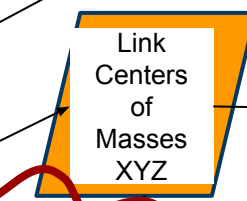
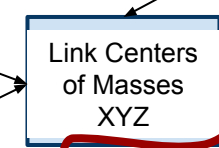
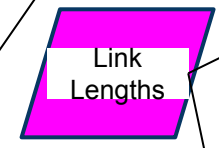
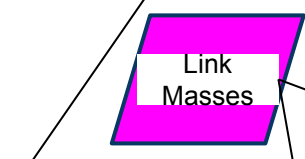
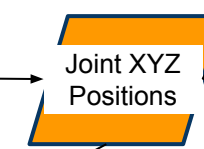
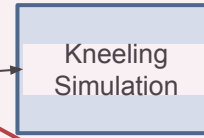
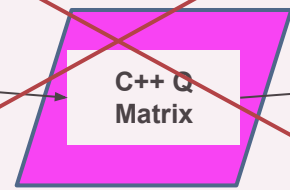
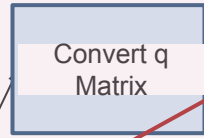
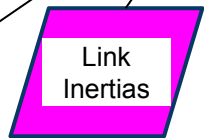
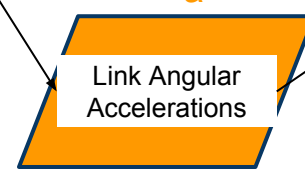
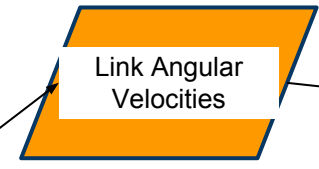
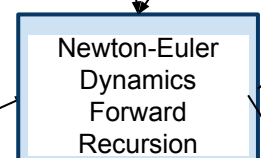
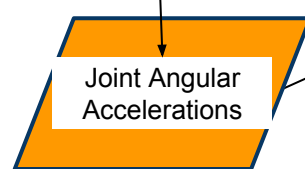
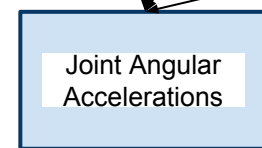
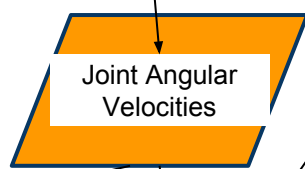
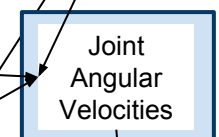
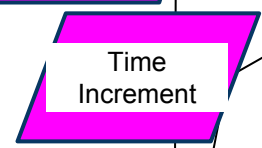
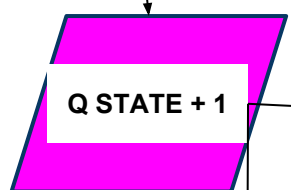
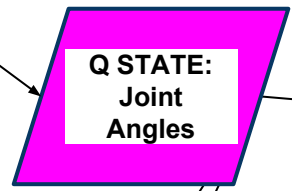
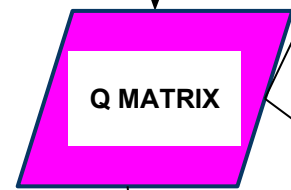
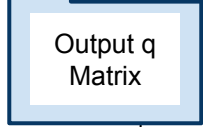
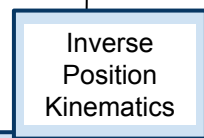
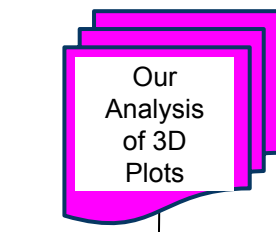
Kinematics

q

not sure about this arrow...

Dynamics

WE DON'T NEED JACOBIANS FOR NEWTON EULER??



$\tau_{ao}(q, q_{dot}, q_{dot_dot})$

Check that the pump can reach the required joint torques