Universidad De Las Américas Puebla

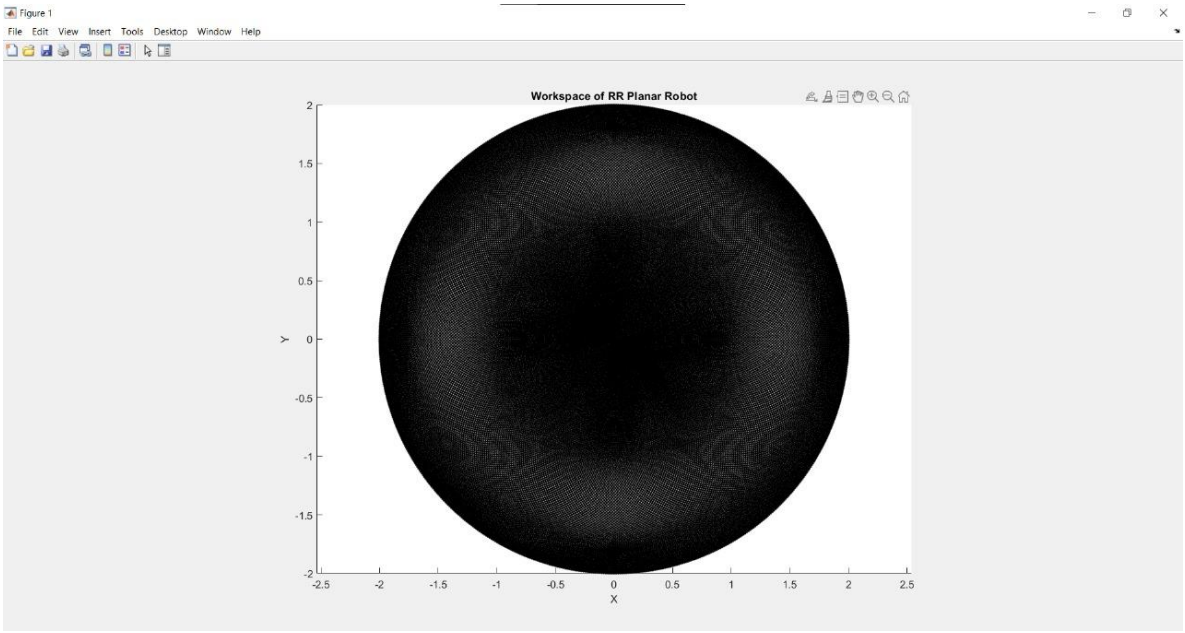
Ingeniería en Robótica y
Telecomunicaciones
Departamento de computación, electrónica y mecatrónica.

En el curso:
CINEMÁTICA Y DINÁMICA DE ROBOTS
P24-LRT3042-1

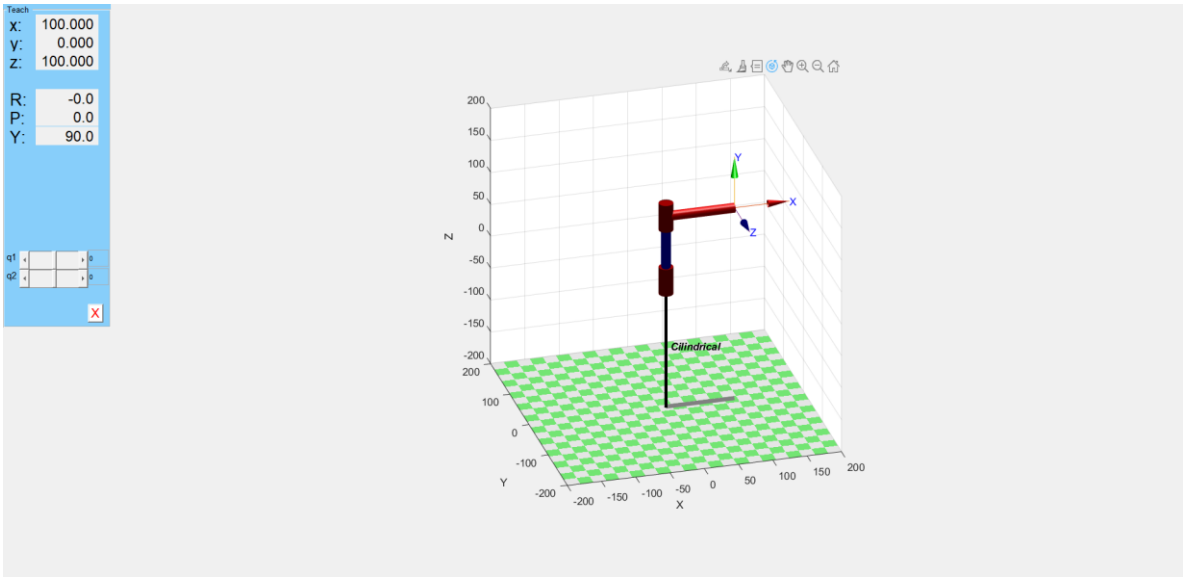
Impartido por:
Cesar Martínez Torres

Tarea 2.2:
RR Planar Robot
Estudiante:
Jonathan Eliasib Rosas Tlaczani - 168399

1.



Workspace of a RR planar Robot



RR Robot

In the provided code, I chose initial values of 100 mm for both L1 and L2 as a starting point.

The link lengths should be long enough to cover the required workspace while maintaining sufficient rigidity and avoiding collisions between links.

I chose an initial range of -90 to 90 degrees for both joints, which corresponds to a total range of 180 degrees.

This range allows the joints to cover a wide range of motion, from pointing downwards to upwards, and provides flexibility for various tasks.