Robotic Systems
Practice: Trajectory generation

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Practice I

Trajectory generation with trapezoidal velocity profile
Write a function with input:

- initial position (vector $x \times 1$)
- final position
- final time
- cruise velocity
- current time instant

and output

- position at the current time instant
- velocity at the current time instant
- acceleration at the current time instant

A possible implementation is given in the file practice03.zip