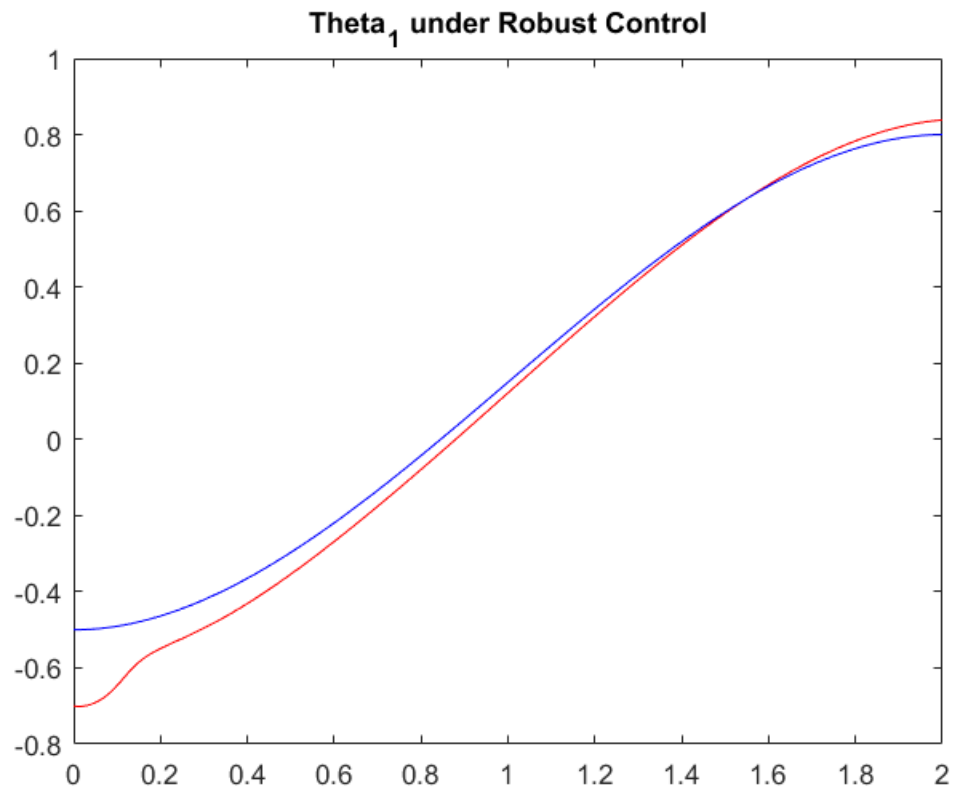
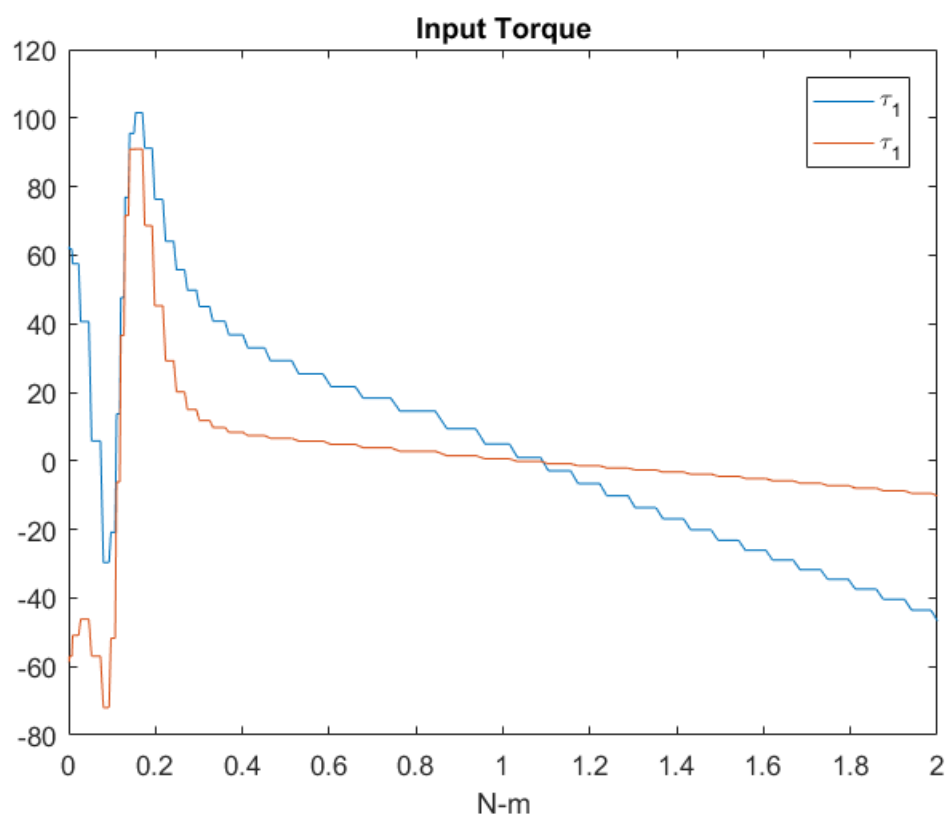
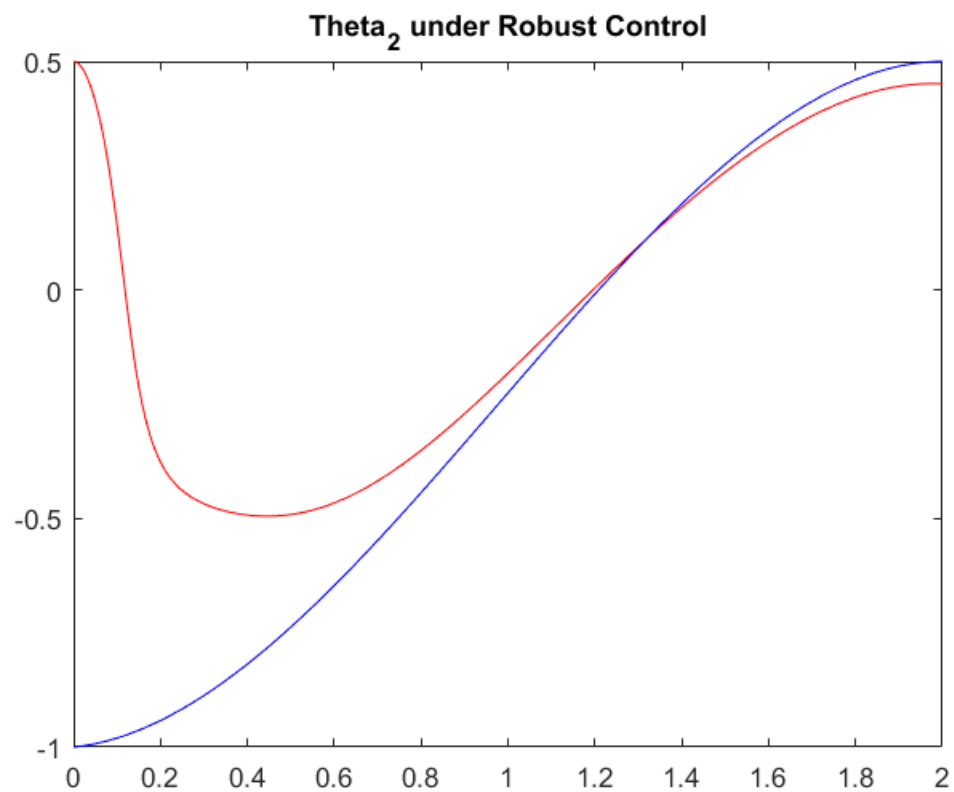

testing algorithm with a set of initial and final states.

```
clc
clear all
close all
%Example to demonstrate the robust control with planar 2d arm.
theta10=-0.5;
dtheta10 =0;
theta1f = 0.8;
dtheta1f=0;
tf=2;

% plan a trajectory to reach target position given by theta1f, dot
% theta1f, dot theta2f.
theta20=-1;
dtheta20= 0.1;
theta2f = 0.5;
dtheta2f=0;

robustControl(theta10,theta20,dtheta10, dtheta20,theta1f,
theta2f,dtheta1f,dtheta2f,tf)%plan_control(theta10,theta20,dtheta10,
dtheta20,theta1f, theta2f,dtheta1f,dtheta2f,tf)
```





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