1. Do trajectory planning with linear functions with parabolic blends for the two

joints of the manipulator:

Deriving

A piece of paper with math equations

Description automatically generated

Compute for joint 1:

A piece of paper with math equations and graphs

Description automatically generated

A piece of paper with math equations and graphs

Description automatically generated

Compute for joint 2:

A piece of paper with math equations and graphs

Description automatically generated

A piece of paper with a graph and numbers on it

Description automatically generated

2. Find the required

A piece of paper with writing on it

Description automatically generated