* Do trajectory planning with linear functions with parabolic blends for the two

joints of the manipulator:

A piece of paper with writing on it

Description automatically generated

A piece of paper with writing on it

Description automatically generated

* Perform PD control simulation:

A graph of a graph

Description automatically generated with medium confidence

* Perform PD + gravity control simulation:

A graph of different angles

Description automatically generated with medium confidence

* Perform computed torque control simulation:

A graph of different colored lines

Description automatically generated with medium confidence

* Compare errors of 3 cases:
* The PD is not as good as the PD with gravity case.
* The computed torque performs much better than the PD with gravity case.