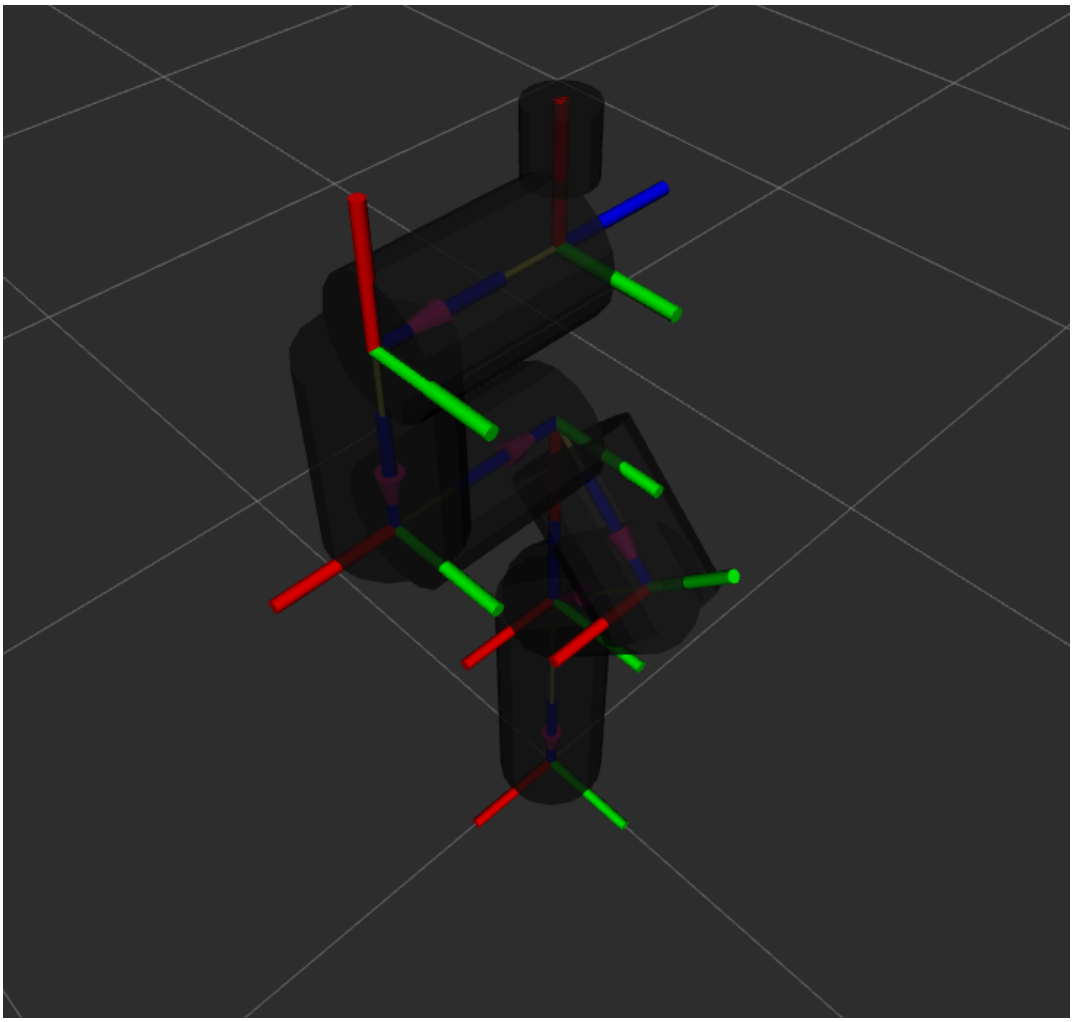
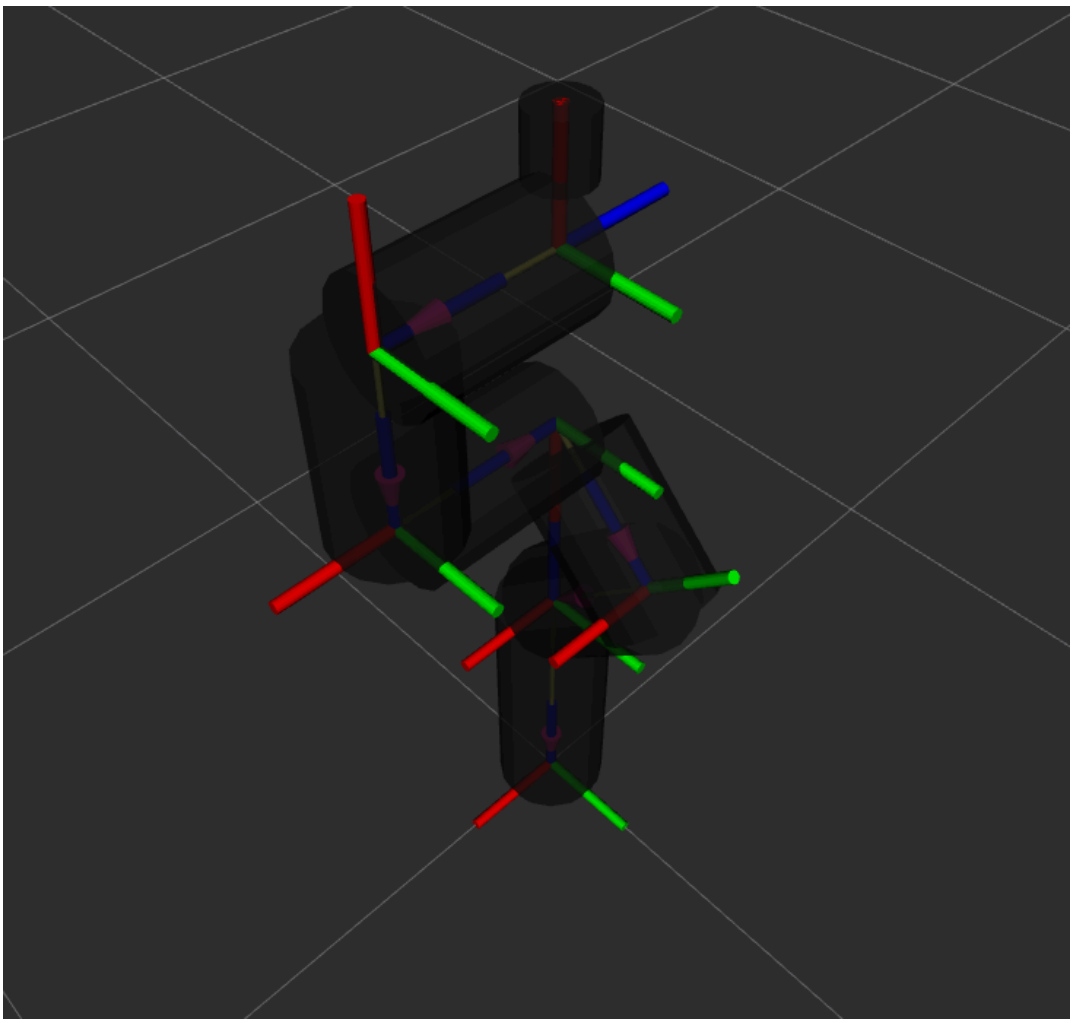
Report

1. Robot
   6-dof manipulator that I made for my bachelor thesis



2. Structure described in assignment_package/urdf/my_manipulator.urdf
3. The movement is described by the movement of each joint angle by the following law $\pi sin(\omega t)$