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```
function x = hw4_fwd_kin_pl(a1, a2, d4, q)
% forward kinematics for SCARA robot
t1 = q(1);
t2 = q(2);
d3 = q(3);
t4 = q(4);

x = [ a2*cos(t1 + t2) + a1*cos(t1);
      a2*sin(t1 + t2) + a1*sin(t1);
      - d3 - d4;
      t1 + t2 + t4 ];

end
```

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