Project 1 instruction

All programs have to run under the Robotic System Toolbox folder.

To run my program, first run **startup\_rvc.m** under 569Project folder.

>>startup\_rvc.m

**kin\_verify.m** implemented kinematics and also verified forward and inverse kinematics.

**jacob\_verify.m** implemented Jacobian by cross-product and differential translation and rotation method.

**q4.m** is draw circle by using inverse kinematics.

**q4\_jacob.m** is draw circle by using Jacobian.

**q5.m** is draw line by using inverse kinematics.

**q5\_jacob.m** is draw line by using Jacobian.

To check my program, just simply run them:

>>kin\_verify

>>jacob\_verify

>>q4

>>q4\_jacob

>>q5

Input a:(recommend a=1)

Input b:(recommend b=0.5)

>>q5\_jacob

Input a:(recommend a=1)

Input b:(recommend b=0.5)







