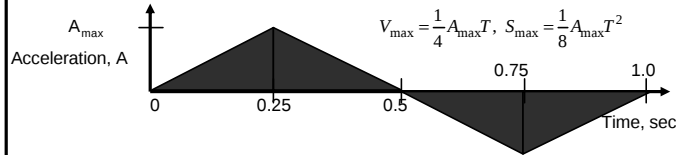


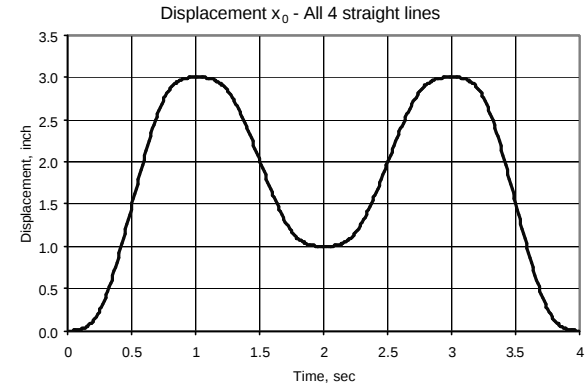
HW #9 – My Solution

- Found motion profile solution in Cartesian coordinates x_0, z_0

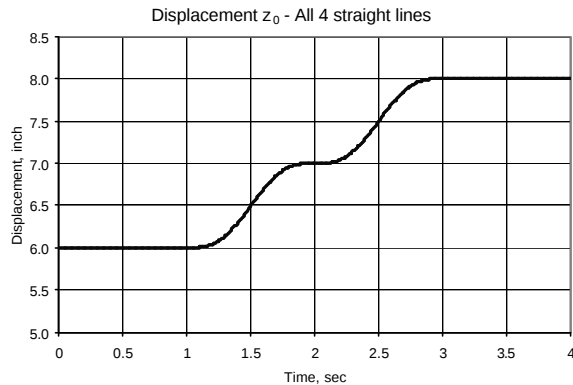


- Found inverse kinematic solution in joint coordinates d_1, θ_2 for each x_0, z_0

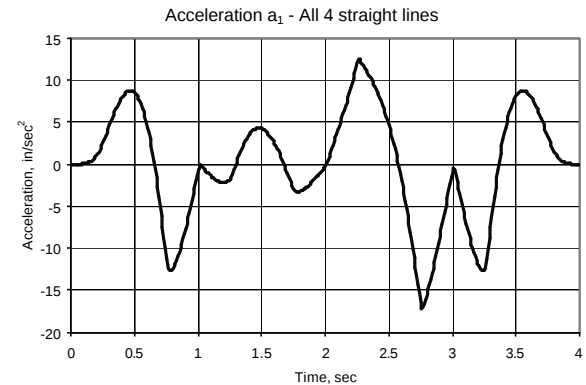
X displacement (0.01 sec increment)



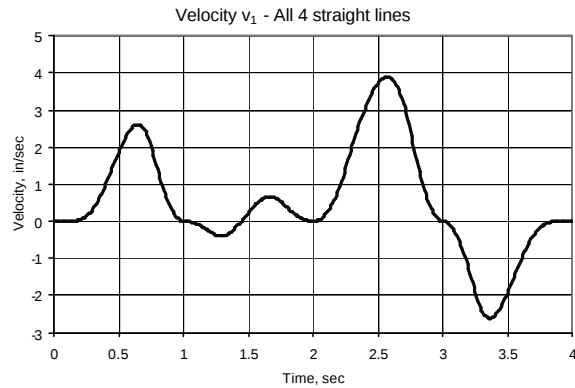
Z displacement (0.01 sec increment)



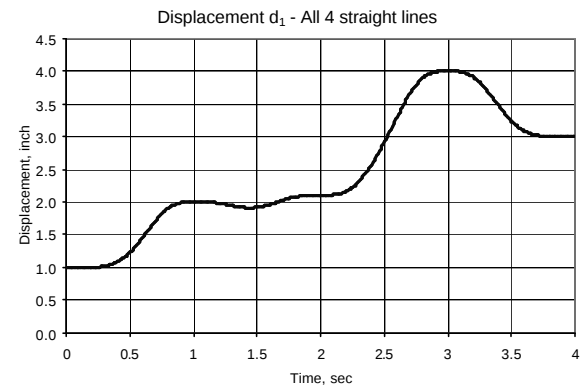
Joint 1 - Acceleration



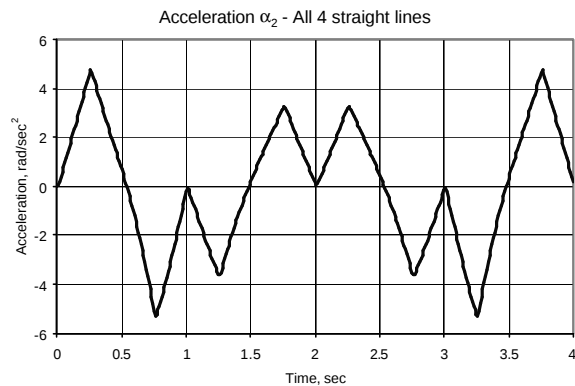
Joint 1 - Velocity



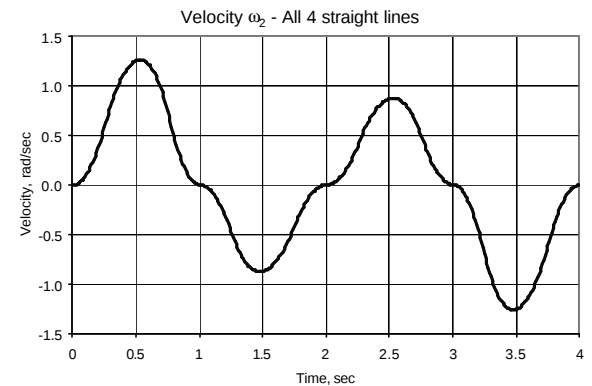
Joint 1 - Displacement



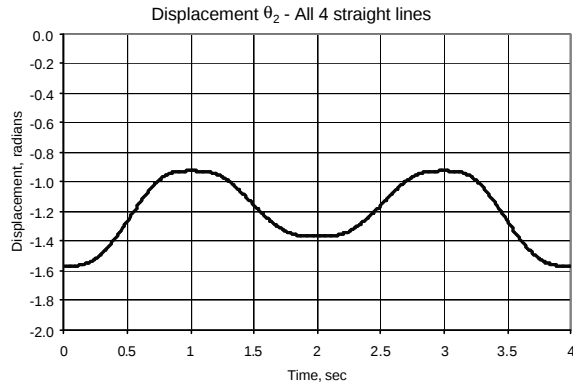
Joint 2 - Acceleration



Joint 2 - Velocity

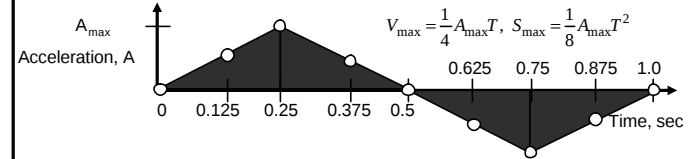


Joint 2 - Displacement



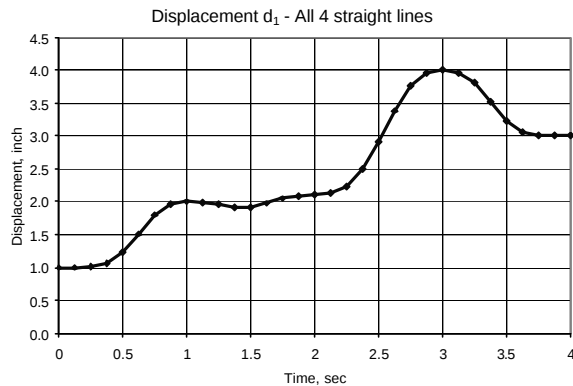
HW #9 – Practical Solution

- Found motion profile solution in Cartesian coordinates x_0, z_0 – 0.125 sec increments

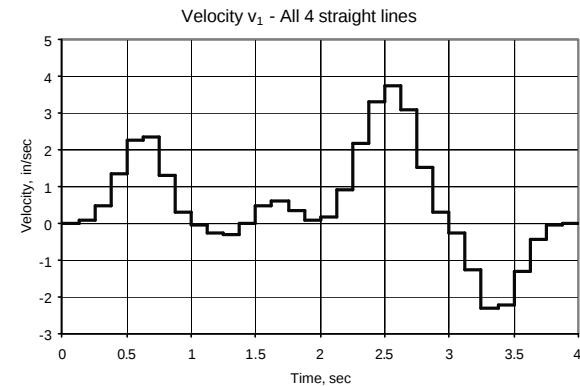


- Found inverse kinematic solution in joint coordinates d_1, θ_2 for each x_0, z_0
- Linearly interpolate during each 0.125 time increment

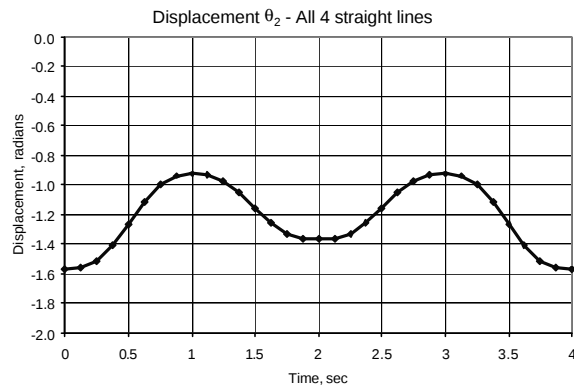
Joint 1 - Displacement



Joint 1 - Velocity



Joint 2 - Displacement



Joint 2 - Velocity

