

Report #2: Deadline 1/28 Mon.

Jacobian exercise:

Exercise 1 (3-link 3-joint Manipulator in 3D): Calculate “Jacobian” for this manipulator and complete a python script ([Velocity_Jacobian_3Links_3D.py](#))

Exercise 2 (Trajectory tracking for a redundant manipulate, cf. [Trajectory_Tracking_Jacobian_5Links.py](#)): Change the target trajectory from the example, nonlinear path ($y=a*x*x+...$) would be better!!!

Please send it me by e-mail (owaki@tohoku.ac.jp), or put printed one in a report box @ A15 503 (5F): **If you need a few feedback, please (correctly) write your email address!!!**