**Homework – Trajectory Planning**

In lab and lecture, trajectory planning for the 2-DOF planar manipulator was derived and demonstrated.

1. In **xl320-line1\_0.nxc** change the value of numberOfWayPoints using the table below. Compile, execute and fill your observations

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| numberOfWayPoints | $t$ when $i=1$ | $$l(t|\_{i=1})$$[stud] value | What path does the end-effector make? How well does it “stay” on the desired line? | YouTube Video URL |
| 1 | 0.5 | 0 |  |  |
| 2 |  |  |  |  |
| 3 |  |  |  |  |
| 5 |  |  |  |  |
| 15 |  |  |  |  |
| 31 |  |  |  |  |

1. URL to your YouTube video demonstration for the above cases i.e. right-most column for the above table (20-points)
2. All files (e.g. NXC and Headers). Comment and make readable i.e. make good use of white space (10-points)