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				

   A. URL to your YouTube video demonstration for the above cases i.e. right-most column for the above table (20-points)

   B. All files (e.g. NXC and Headers). Comment and make readable i.e. make good use of white space (10-points)