

❖ Reaching task in the Neurorobotics Platform (NRP)

In this project, students will use a simulated humanoid robot arm in the Neurorobotics Platform to perform a basic reaching task. The role of the students is to use an inverse kinematic model to control the arm and guide it in the cartesian space.

Project main area	Additional knowledge	Hardware	Work @ Lab ¹	Tutor
Robotics	<ul style="list-style-type: none">• Inverse Kinematics model• NRP	<ul style="list-style-type: none">• No additional hardware required	<ul style="list-style-type: none">• One session for NRP installation• One session for embedding the inverse kinematic controller	Egidio Falotico e.falotico@santannapisa.it Alessandro Ambrosano a.ambrosano@santannapisa.it

Neurorobotics Platform link -> www.neurorobotics.net

