

1. Modern Robotics: Exercise 3.20
2. Modern Robotics: Exercise 3.23
3. Modern Robotics: Exercise 3.26
4. Modern Robotics: Exercise 3.28
5. ~~Modern Robotics: Exercise 5.5~~
6. Modern Robotics: Exercise 5.6 (Note: part-(a) is modified to compute the twist of frame $\{b\}$ expressed in frame $\{b\}$, i.e., the ${}^b\mathcal{V}_b$)