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| Maths and computer graphics Coursework 2 |
| Approximation of Inverse Kinematics using Dual Quaternions |
| An implementation of a robot arm within Octet |
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| Juanmi Huertas Delgado, Sam Hayhurst and Sokol Murturi |
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# Introduction

# Dual-Quaternion Implementation

# Robot Arm and Inverse Kinematics approximation overview

# User Interaction

# What We Learnt

# Conclusions & Further Work

# References