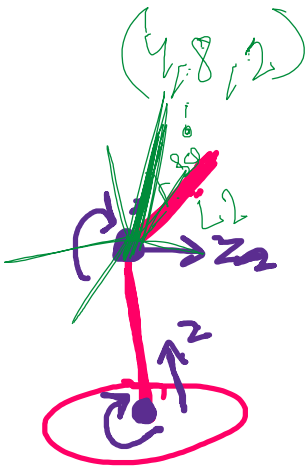


# Forward and Inverse Kinematics

Tuesday, 21 September 2021 10:50 AM

Joints space or Cartesian Space  
(x y z)



```
def robot_initialize(self):  
    self.kuka_robot = ikpy.chain.Chain.from_urdf_file("/home/luqman/r2_ra_ws/src/kuka_arm/urdf/kuka_model.urdf")
```

Forward Kinematics

Inverse Kinematics

