Kinematics solution with Ikine-Py

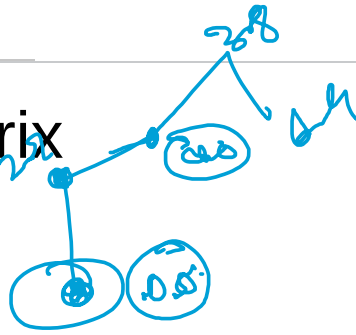- Urdf Read

- Transformation Matrix
- Kinematic Solutions
  - Delete Fixed Joints

```python
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")
```