The functionality of my work.

- I implemented one simple inverse kinematics system using Jacobian matrix by showing three joints that the end one of them would reach or getting close to the target smoothly
- We control the position of target(cursor) by arrow keys and press "i" to force the end joint to get close to the target

Problems and solutions.

- I tried to use the pseudoinverse as J+ =(JTJ)^-1*JT, however, the results did not perform well. So I used the JTxV to compute theta directly and updated theta after every movement
- At the first I used while loop by mistake. Then, I used a bool variable as a reaching marker to stop rotation of the joints when have gotten closest