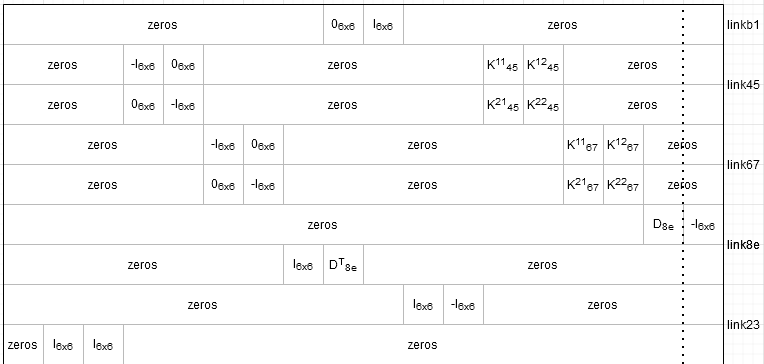
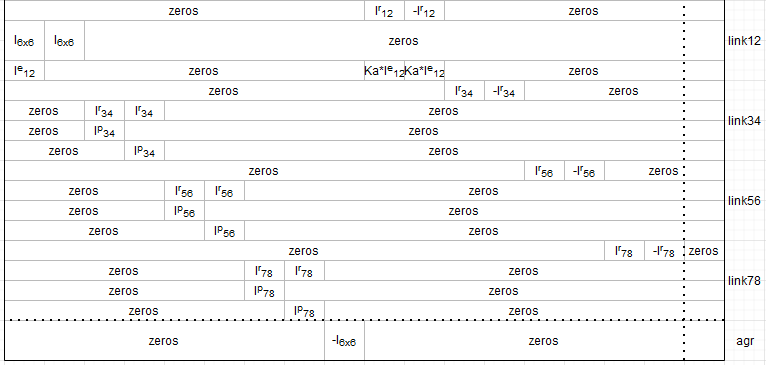
Report

Authors: Erik Krasilnikov, Alexey Astahov

Inverce kinematic of robot

Stiffness model





Kc=D-CA-1B

Wagr = Kc\*F

Result of analysis

Variance of results was too big to visualize so I use log of data

