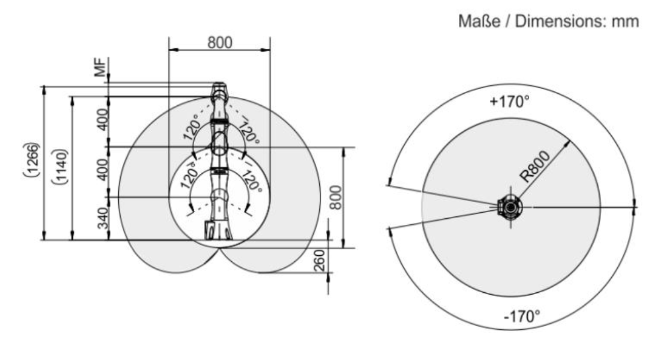
**Report**

1. Forward kinematics



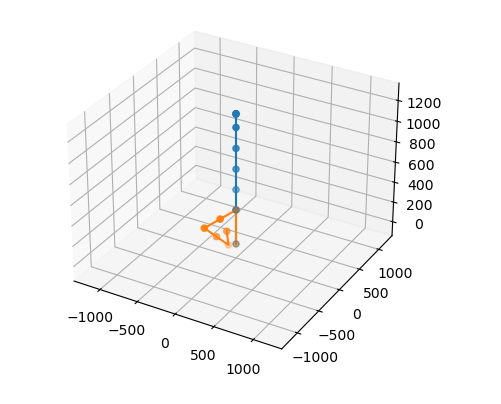
*Figure 1 – Manipulator structure*

Forward kinematics = Rz(q0)\*Tz(l1)\*Rx(q1)\*Tz(l2)\*Rz(q2)\*Tz(l3)\*Rx(q3)\*Tz(l4)\*Rz(q4)\*Tz(l5)\*Rx(q5)\*Tx(l6)\*Rz(q6)\*Tx(l7)

1. Weighted pseudoinverse



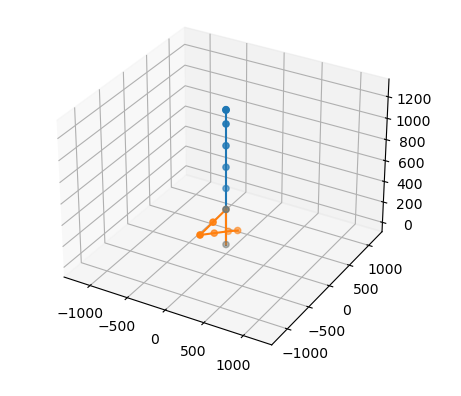
Where W = diag(weights)



*Figure 2 – weighted pseudoinverse result*

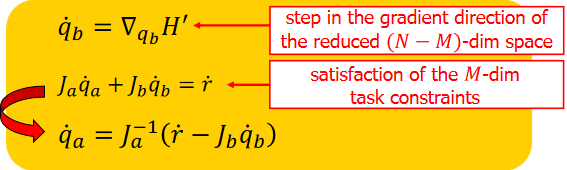
1. Damped least squares



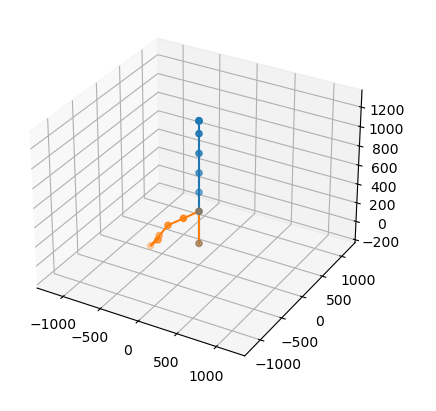


*Figure 3 – damped least squares result*

1. Null Space method







*Figure 4 –Null Space method result*

Git Hub: