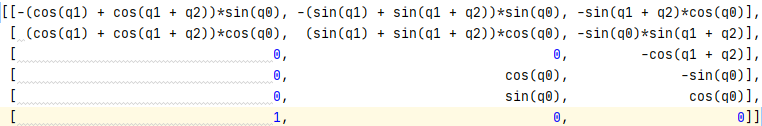
Task 1

For calculating Jacobian I choose skew theory method because in this method is hard to make mistake

Result:



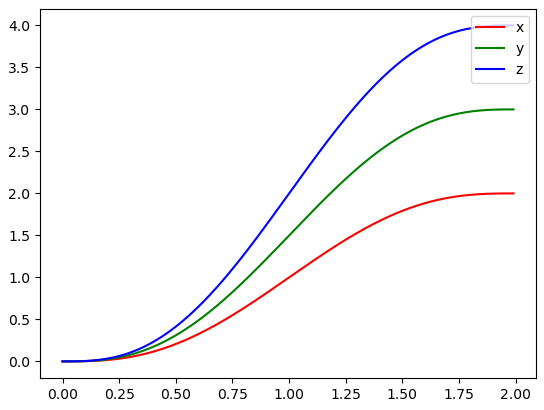
Task 2

Matrix A =

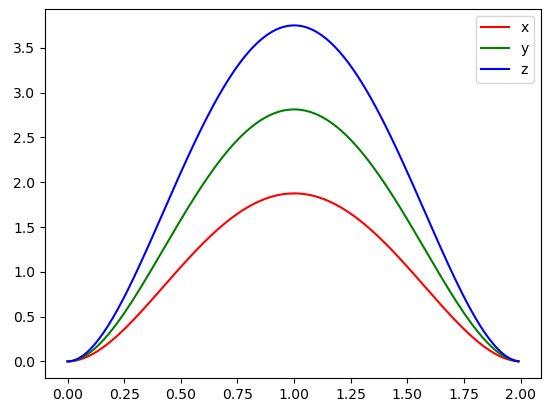
Matrix A-1 =

Coefficients = A-1\*Matrix()

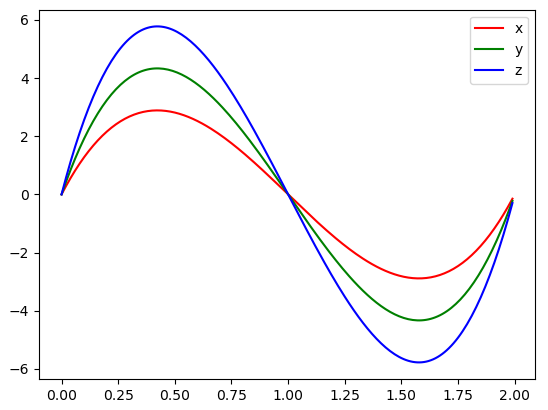
Endeffector position graphic



Endeffector velocity graphic



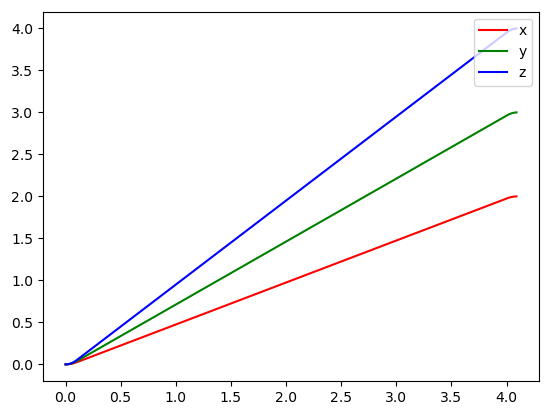
Endeffector acceleration graphics



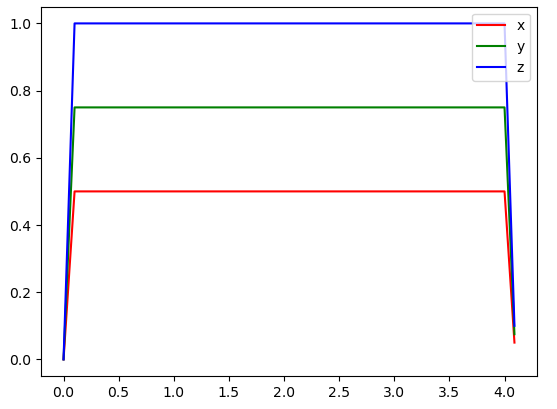
Task 3

q(t) =

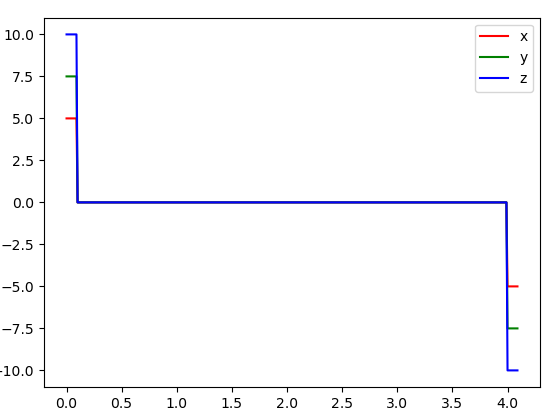
Endeffector position graphic



Endeffector velocity graphic

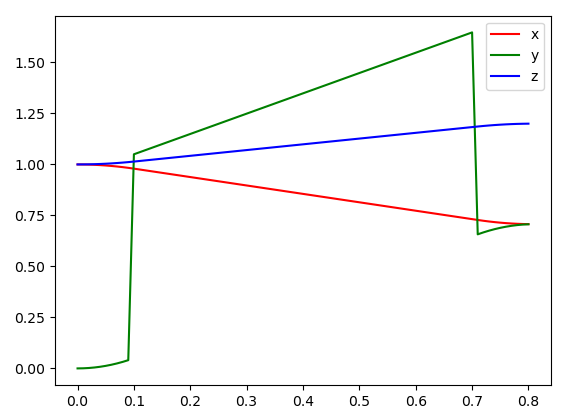


Endeffector acceleration graphics

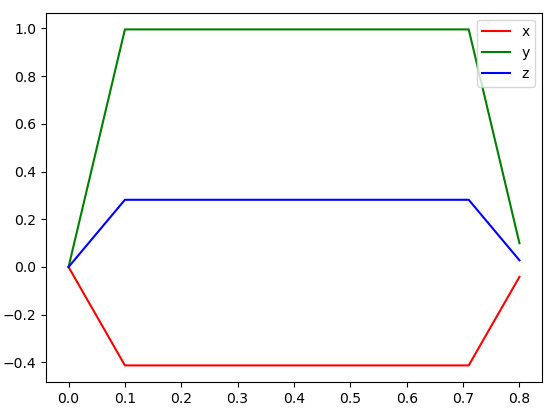


Task 4

Endeffector position graphic



Endeffector velocity graphic



Endeffector acceleration graphic

