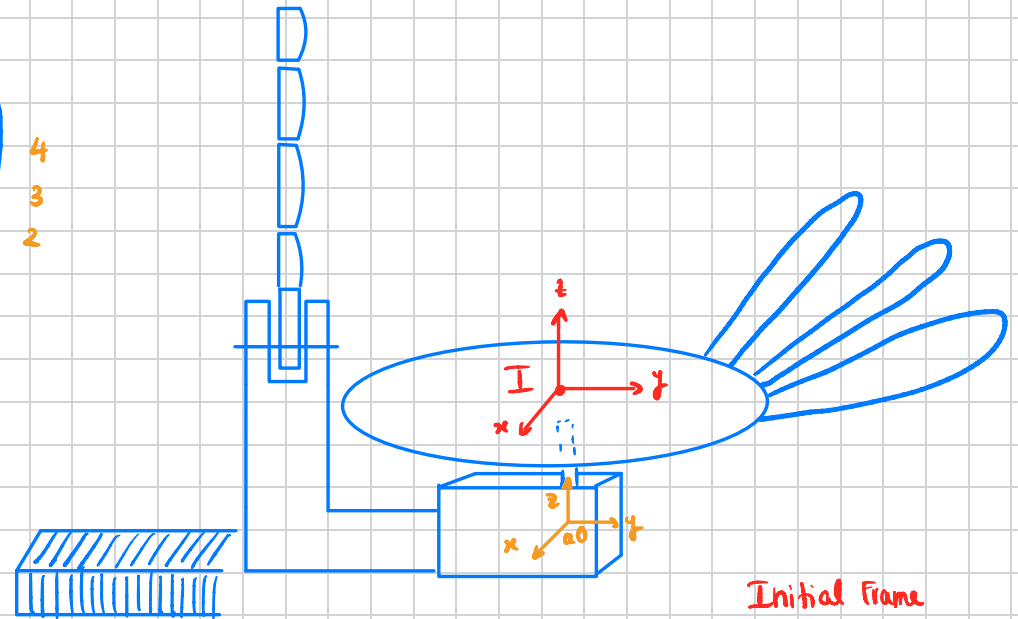
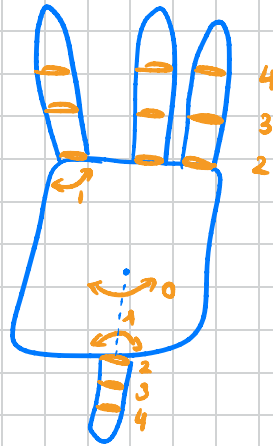


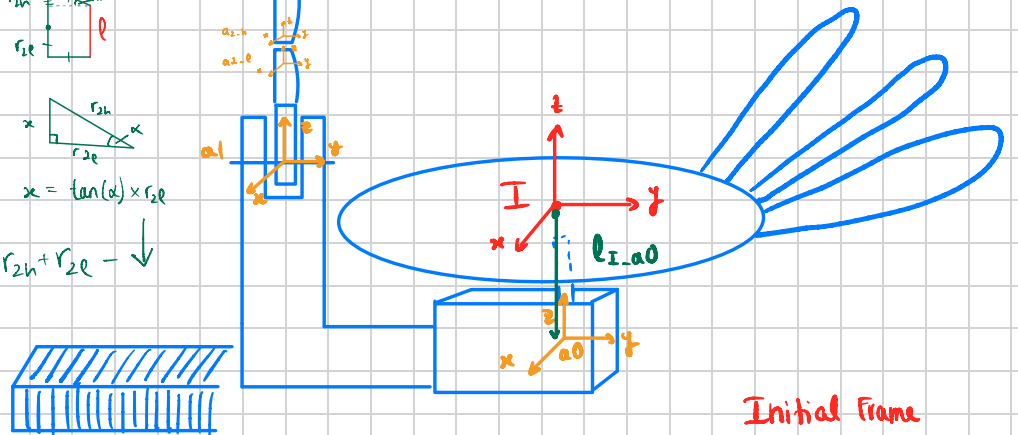
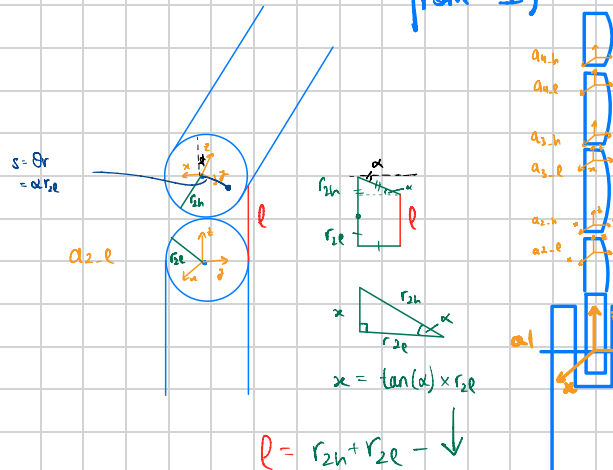
Coding Inverse Kinematics

	Finger	Joint
Thumb	O/A	[0, 1, 2, 3, 4]
Index	1/B	[2, 3, 4]
Middle	2/C	[2, 3, 4]
Pinky	3/D	[1, 2, 3, 4]

T_{0-12} = translation from joint 1 \rightarrow 2 in thumb



Arm
(-ve y-directed from I)



Arm
(-ve y-directed from I)