UR5

Inverse Kinematics wrt Fixed:
[[8.07467485e-06 9.99999996e-01 -8.65490759e-05 -5.99875823e-01]
 [1.66020512e-04 -8.65504152e-05 -9.99999982e-01 9.99806576e-02]
 [-9.99999986e-01 8.06030578e-06 -1.66021210e-04 9.99052455e-02]
 [0.00000000e+00 0.00000000e+00 0.00000000e+00 1.00000000e+00]]
[[0.   1.   0. -0.6]
 [0.   0. -1.   0.1]
 [-1.   0.   0.   0.1]
 [0.   0.   0.   1.]]
Iterations:
26
Final Configuration:
[3.02064715 -223.56720969 441.24477561 -161.12752113   9.30391889
   54.97924648] // this is later passed through modulos to be in [-pi,pi]

WAM

Initial Joint Angles:
[0.04378288 0.01963448 -0.17513453 0.03776945 -0.18636636 -0.04424871
  0.02341173]
Inverse Kinematics wrt Fixed:
[[9.99999780e-01 1.83976047e-04 -6.37367498e-04 3.99869043e-01]
 [-1.84536018e-04 9.99999597e-01 -8.78620720e-04 -4.59371704e-04]
 [6.37205596e-04 8.78738144e-04 9.99999411e-01 4.00096386e-01]
 [0.00000000e+00 0.00000000e+00 0.00000000e+00 1.00000000e+00]]
[[1.   0.   0.   0.4]
 [0.   1.   0.   0.]
 [0.   0.   1.   0.4]
 [0.   0.   0.   1.]]
Iterations:
12
Final Configuration:
[-27.39013371 5.81571918 8.0848724 -16.67859502 -33.9822407
   2.20079269 54.2008066]//this is later passed through modulos to be in [-pi,pi]