

Homework3
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I didn't really write down much of the work here, all the preliminary math I did to derive my solutions is already in matlab grader.

To solve the inverse kinematics I just used the basic Newton-Raphson method, I didn't need damped least squares so I didn't over complicate it.

I can imagine that if a robot had a spherical wrist the analytic jacobian would have a tough time with the singularity where the two axes of the wrist that can line up do, just because in that case I'm not sure it would handle those two joints being able to spin.