The following is an aggregation of helpful resources for developing the inverse kinematics code for the robotic arm project. The existing code for the project is poorly documented, and doesn’t run, so it’s best to begin this part of the project from scratch.

There is also a brown hardcover book on robotics somewhere in the ideas clinic coop office that may be useful.

<https://automaticaddison.com/the-ultimate-guide-to-inverse-kinematics-for-6dof-robot-arms/>

<https://automaticaddison.com/how-to-assign-denavit-hartenberg-frames-to-robotic-arms/#Example_3_-_Articulated_Robot>

<https://automaticaddison.com/how-to-find-the-rotation-matrices-for-robotic-arms/>

<https://www.youtube.com/watch?v=DKDMrc69Snk>

<https://automaticaddison.com/homogeneous-transformation-matrices-using-denavit-hartenberg/>

<https://automaticaddison.com/how-to-find-denavit-hartenberg-parameter-tables/>