Maths Task 2: Forward Kinematics

Objective

1. Write code for the forward kinematics of the robot arm described below.
2. You can code either in python or C++
3. The visualization of results is optional.

Details

1. Input will be the joint angles j1, j2, j3, j4.
2. Output should be the 3d coordinates of the end-effector (end-of-arm)
3. The lengths of the links should be a parameter.

Here is the description of the robot -

a. The robot has four links, each connected using a revolute pair (like a door hinge)
b. The axis of each joint is perpendicular to the previous joint.
c. The lengths of the links -' L' is 1m each.
d. Please check the diagram below for more information.