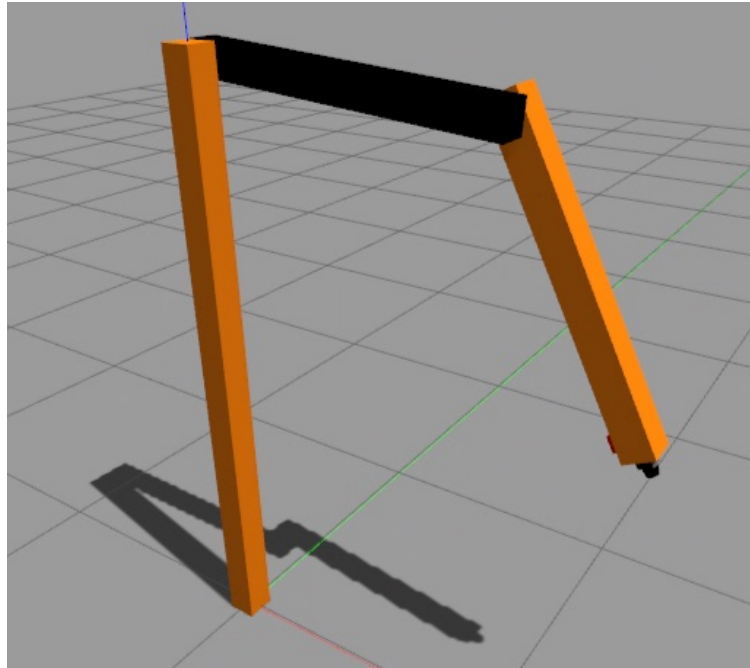


Inverse Kinematics of elbow manipulator



Link	a	α	d	θ
Base link	2	$\pi/2$	0.1	0
Link 1	1	0	0.1	θ_1
Link 2	1	0	0.1	θ_2