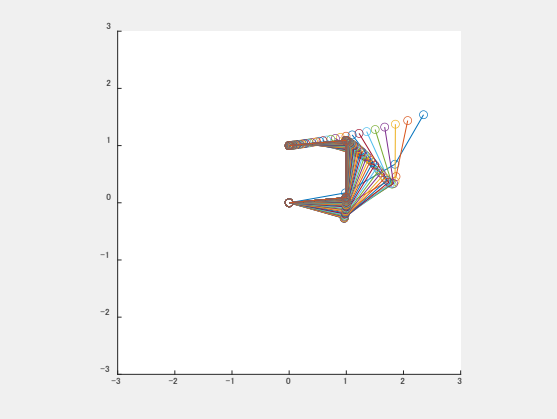
Quiz #4b: Three-Link Robot Arm Inverse Kinematics



- Modify the sample code as L1 = L2 = L3 = 0.5.
- Solve the inverse kinematics of the target position of [0, 0.5] with the two different initial joint angles of [10 deg, 10 deg, 10 deg] and [0 deg, 0 deg, 0 deg]
- If the inverse kinematics cannot be solved, put comments to your code explaining what has happened.