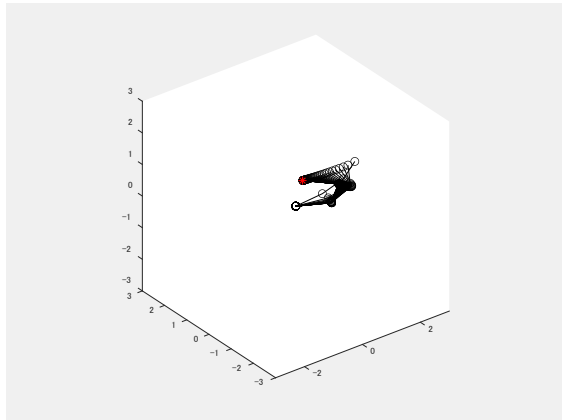
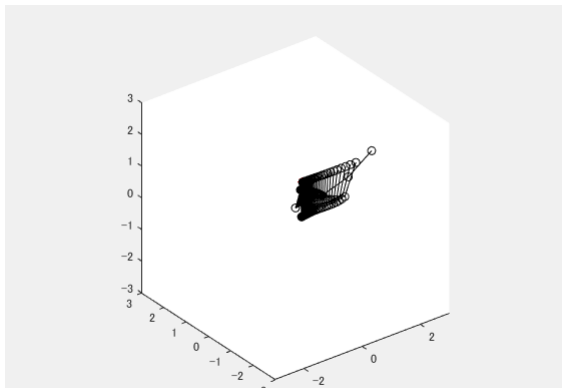


Quiz #5: Three-Link Robot Arm Inverse Kinematics



Robot arm of the sample codes



Robot arm of the modified parameters

- Modify the sample code to the following DH parameters
- % Link lengths
 - $L1 = 1$; $L2 = 1$; $L3 = 1$;
- % Homogeneous transformation matrices for given angles
 - $T01 = \text{DH}(0, 0, 0, Q(1))$;
 - $T12 = \text{DH}(\pi/2, L1, 0, Q(2))$;
 - $T23 = \text{DH}(0, L2, 0, Q(3))$;
 - $T34 = \text{DH}(0, L3, 0, 0)$;
- Solve the inverse kinematics for $pD = [1; 1; 0]$;