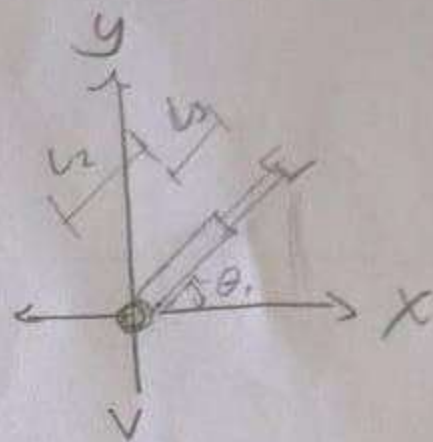
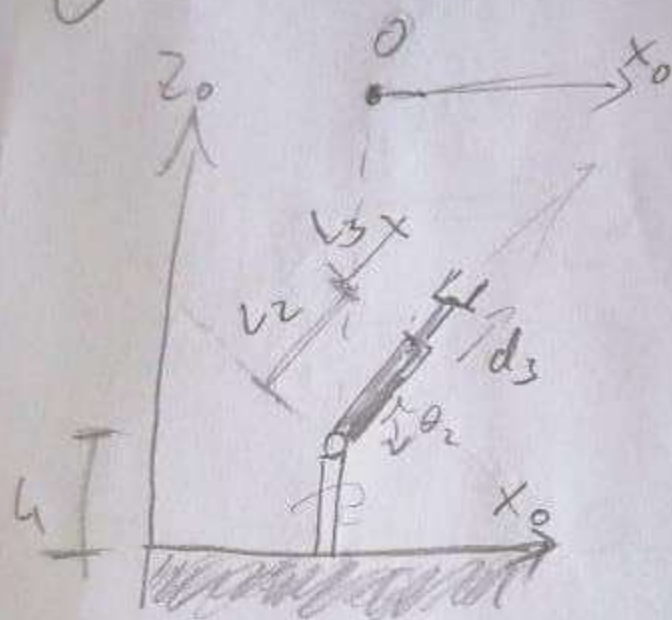
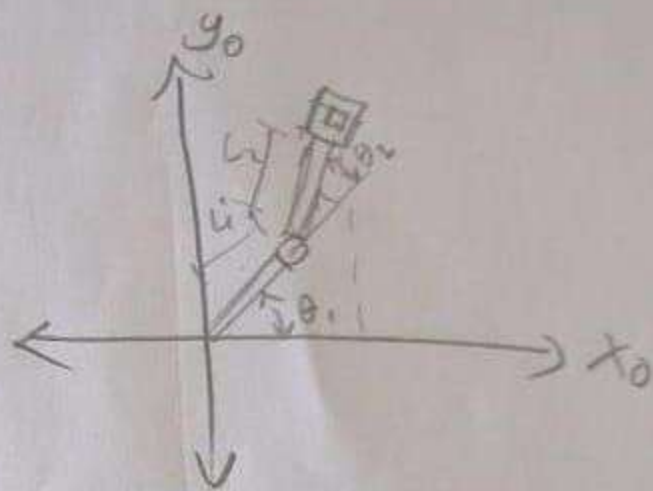
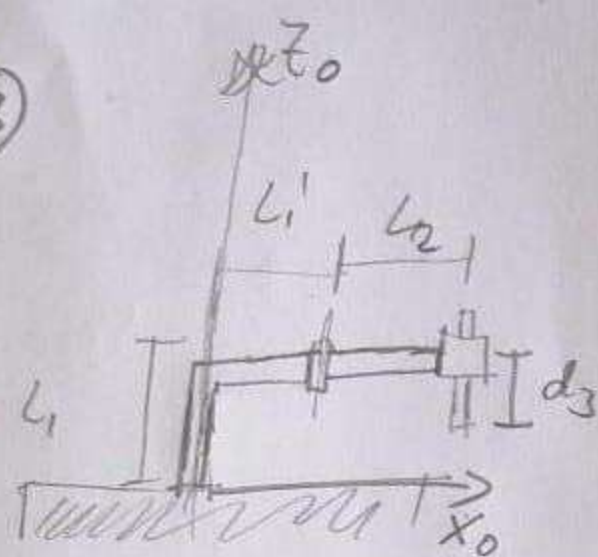


②



$$\begin{aligned}
 x &= (L_2 + d_3) \cos \theta_2 \cos \theta_1 = (L_2 + d_3) C \theta_2 C \theta_1 \\
 y &= (L_2 + d_3) \cos \theta_2 \sin \theta_1 = (L_2 + d_3) C \theta_2 S \theta_1 \\
 z &= L_1 + (L_2 + d_3) \sin \theta_2 = L_1 + (L_2 + d_3) S \theta_2
 \end{aligned}$$

③

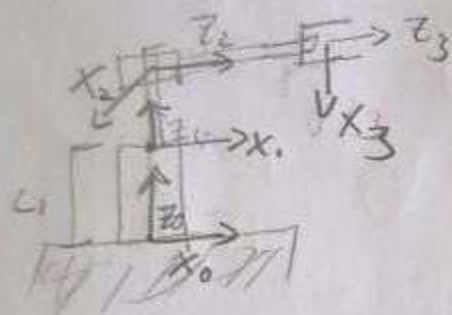


$$x = L_1 \cos \theta_1 + L_2 \cos(\theta_1 + \theta_2) = L_1 \cos \theta_1 + L_2 \cos(\theta_1 + \theta_2)$$

$$y = L_1 \sin \theta_1 + L_2 \sin(\theta_1 + \theta_2)$$

$$z = L_1 - d_3$$

⑦



Δ	θ_i	d_i	a_i	α_i
1	q_1	L_1	0	0
2	-90	q_2	0	-90
3	90	q_3	0	0

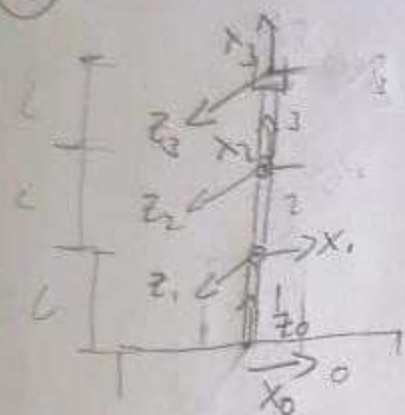
$$A_i = \begin{pmatrix} c\theta & -c\alpha s\theta & s\alpha s\theta & a c\theta \\ s\theta & c\alpha c\theta & -s\alpha c\theta & a s\theta \\ 0 & s\alpha & c\alpha & d_i \\ 0 & 0 & 0 & 1 \end{pmatrix} \quad T = {}^0A_3 = {}^0A_1 {}^1A_2 {}^2A_3$$

$${}^0A_1 = \begin{pmatrix} c\theta_1 & -s\theta_1 & 0 & 0 \\ s\theta_1 & c\theta_1 & 0 & 0 \\ 0 & 0 & 1 & L_1 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

$${}^1A_2 = \begin{pmatrix} 0 & 0 & 1 & 0 \\ -1 & 0 & 0 & 0 \\ 0 & -1 & 0 & q_2 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

$${}^2A_3 = \begin{pmatrix} 0 & -1 & 0 & 0 \\ 1 & 0 & 0 & 0 \\ 0 & 0 & 1 & q_3 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

4)



A	θ_i	d_i	a_i	d_i
1	θ_1	L_1	0	90
2	θ_2	0	L_2	0
3	θ_3	0	L_3	0

$${}^i A_i = \begin{pmatrix} c\theta & -c\alpha s\theta & s\alpha s\theta & a c\theta \\ s\theta & c\alpha c\theta & -s\alpha c\theta & a s\theta \\ 0 & s\alpha & c\alpha & d_i \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

$$T = {}^0 A_3 = {}^0 A_1 {}^1 A_2 {}^2 A_3$$

$${}^0 A_1 = \begin{pmatrix} c\theta_1 & 0 & s\theta_1 & 0 \\ s\theta_1 & 0 & -c\theta_1 & 0 \\ 0 & 1 & 0 & L_1 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

$${}^1 A_2 = \begin{pmatrix} c\theta_2 & -s\theta_2 & 0 & L_2 c\theta_2 \\ s\theta_2 & c\theta_2 & 0 & L_2 s\theta_2 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

$${}^2 A_3 = \begin{pmatrix} c\theta_3 & -s\theta_3 & 0 & L_3 c\theta_3 \\ s\theta_3 & c\theta_3 & 0 & L_3 s\theta_3 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$

```

clear, clc
syms q1 q2 q3 px py pz

L1 = 12
L2 = L1

EqX = px == (L2+q3)*cos(q2)*cos(q1)
EqY = py == (L2+q3)*cos(q2)*sin(q1)
EqZ = pz == L1 + (L2 + q3)*sin(q2)

[Sol_q1, Sol_q2, Sol_q3] = solve([EqX EqY EqZ], [q1 q2 q3]), param, cond] ,
    "ReturnConditions",true);
%disp(Sol_q3)

Sol_q1 = simplify(Sol_q1)
Sol_q2 = simplify(Sol_q2)
Sol_q3 = simplify(Sol_q3)

L1 =

    12

L2 =

    12

EqX =

px == cos(q1)*cos(q2)*(q3 + 12)

EqY =

py == cos(q2)*sin(q1)*(q3 + 12)

EqZ =

pz == sin(q2)*(q3 + 12) + 12

Warning: Solutions are only valid under certain conditions. To include
parameters and conditions in the solution, specify the 'ReturnConditions'
value
as 'true'.

Sol_q1 =

-2*atan((px - (12*(((px^2 + py^2 + pz^2 - 24*pz + 144)^(1/2) - pz + 12)*(pz +
(px^2 + py^2 + pz^2 - 24*pz + 144)^(1/2) - 12))^(1/2) + (px^2 + py^2 + pz^2

```

$$\begin{aligned}
& - 24*px + 144)^{(1/2)})/(pz - 12) - (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} \\
& + (pz*((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + (px^2 + \\
& py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} + (px^2 + py^2 + pz^2 - 24*px + \\
& 144)^{(1/2)}))/((pz - 12))/py) \\
& - 2*atan((px + (12*((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + \\
& (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} + (px^2 + py^2 + pz^2 - \\
& 24*px + 144)^{(1/2)}))/((pz - 12) + (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} \\
& - (pz*((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + (px^2 + \\
& py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} + (px^2 + py^2 + pz^2 - 24*px + \\
& 144)^{(1/2)}))/((pz - 12))/py) \\
& - 2*atan((px - (12*((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + \\
& (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} - (px^2 + py^2 + pz^2 - \\
& 24*px + 144)^{(1/2)}))/((pz - 12) + (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} \\
& + (pz*((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + (px^2 + \\
& py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} - (px^2 + py^2 + pz^2 - 24*px + \\
& 144)^{(1/2)}))/((pz - 12))/py) \\
& - 2*atan((px + (12*((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + \\
& (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} - (px^2 + py^2 + pz^2 - \\
& 24*px + 144)^{(1/2)}))/((pz - 12) - (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} \\
& - (pz*((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + (px^2 + \\
& py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} - (px^2 + py^2 + pz^2 - 24*px + \\
& 144)^{(1/2)}))/((pz - 12))/py)
\end{aligned}$$

Sol_q2 =

$$\begin{aligned}
& 2*atan((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + (px^2 + \\
& py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} + (px^2 + py^2 + pz^2 - 24*px + \\
& 144)^{(1/2)}))/((pz - 12)) \\
& - 2*atan((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + (px^2 + \\
& py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} + (px^2 + py^2 + pz^2 - 24*px + \\
& 144)^{(1/2)}))/((pz - 12)) \\
& 2*atan((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + (px^2 + \\
& py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} - (px^2 + py^2 + pz^2 - 24*px + \\
& 144)^{(1/2)}))/((pz - 12)) \\
& - 2*atan((((px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - pz + 12)*(pz + (px^2 + \\
& py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12))^{(1/2)} - (px^2 + py^2 + pz^2 - 24*px + \\
& 144)^{(1/2)}))/((pz - 12))
\end{aligned}$$

Sol_q3 =

$$\begin{aligned}
& (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12 \\
& - (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12 \\
& - (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12 \\
& (px^2 + py^2 + pz^2 - 24*px + 144)^{(1/2)} - 12
\end{aligned}$$

Sol_q1 =

$$\begin{aligned}
& - 2*atan((px + (px^2 + py^2)^{(1/2)}))/py) \\
& - 2*atan((px - (px^2 + py^2)^{(1/2)}))/py) \\
& - 2*atan((px + (px^2 + py^2)^{(1/2)}))/py) \\
& - 2*atan((px - (px^2 + py^2)^{(1/2)}))/py)
\end{aligned}$$

Sol_q2 =

$$\begin{aligned} & 2*\operatorname{atan}((px^2 + py^2)^{(1/2)} + (px^2 + py^2 + pz^2 - 24*pz + 144)^{(1/2)})/(pz - 12)) \\ & -2*\operatorname{atan}((px^2 + py^2)^{(1/2)} + (px^2 + py^2 + pz^2 - 24*pz + 144)^{(1/2)})/(pz - 12)) \\ & 2*\operatorname{atan}((px^2 + py^2)^{(1/2)} - (px^2 + py^2 + pz^2 - 24*pz + 144)^{(1/2)})/(pz - 12)) \\ & -2*\operatorname{atan}((px^2 + py^2)^{(1/2)} - (px^2 + py^2 + pz^2 - 24*pz + 144)^{(1/2)})/(pz - 12)) \end{aligned}$$

Sol_q3 =

$$\begin{aligned} & (px^2 + py^2 + pz^2 - 24*pz + 144)^{(1/2)} - 12 \\ & - (px^2 + py^2 + pz^2 - 24*pz + 144)^{(1/2)} - 12 \\ & - (px^2 + py^2 + pz^2 - 24*pz + 144)^{(1/2)} - 12 \\ & (px^2 + py^2 + pz^2 - 24*pz + 144)^{(1/2)} - 12 \end{aligned}$$

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```
syms q1 q2 q3 px py pz
```

```
L1 = 12
```

```
L2 = L1
```

```
EqX = px == L1*cos(q1) + L2*cos(q1+q2)
```

```
EqY = py == L1*sin(q1) + L2*sin(q1+q2)
```

```
EqZ = pz == L1 - q3
```

```
[Sol_q1 Sol_q2 Sol_q3] = solve([EqX EqY EqZ], [q1 q2 q3]);
```

```
Sol_q1 = simplify(Sol_q1)
```

```
Sol_q2 = simplify(Sol_q2)
```

```
Sol_q3 = simplify(Sol_q3)
```

```
L1 =
```

```
12
```

```
L2 =
```

```
12
```

```
EqX =
```

```
px == 12*cos(q1 + q2) + 12*cos(q1)
```

```
EqY =
```

```
py == 12*sin(q1 + q2) + 12*sin(q1)
```

```
EqZ =
```

```
pz == 12 - q3
```

```
Sol_q1 =
```

```
2*atan((24*py + (- px^4 - 2*px^2*py^2 + 576*px^2 - py^4 + 576*py^2)^(1/2))/  
(px^2 + 24*px + py^2))
```

```
2*atan((24*py - (- px^4 - 2*px^2*py^2 + 576*px^2 - py^4 + 576*py^2)^(1/2))/  
(px^2 + 24*px + py^2))
```

```
Sol_q2 =
```

```
-2*atan((- (px^2 + py^2)*(px^2 + py^2 - 576))^(1/2)/(px^2 + py^2))
```

$$2*\text{atan}((-(px^2 + py^2)*(px^2 + py^2 - 576))^{1/2}/(px^2 + py^2))$$

Sol_q3 =

12 - pz

12 - pz

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```

clear, clc

syms px py pz az ax ay
syms q1 q2 q3

L1 = 12
L2 = L1
L3 = L1

DHPParam = [q1 L1 0 0; -pi/2 q2 0 -pi/2; pi/2 q3 0 0];

[A, T, Q, Rot, Tra] = DH(DHPParam, px, py, pz, az);

EqX = px == (Tra(1));
EqY = py == (Tra(2));
EqZ = pz == (Tra(3));

Eqs = [EqX; EqY; EqZ];
% n, s, a
%EqAux = az == Rot(2,3);
%EqAux = az == Rot(3,3);

EqAux = az == Rot(3,1);

jointVar = symvar(T);

Q = solve([EqX EqY EqZ], jointVar, "Real",true)%, "PrincipalValue",false)

%%%%%%%%5

L1 =

    12

L2 =

    12

L3 =

    12

     3

[q1, 12, 0, 0]

[-pi/2, q2, 0, -pi/2]

[pi/2, q3, 0, 0]

```

`(:,:,1) =`

```
[cos(q1), -sin(q1), 0, 0]
[sin(q1), cos(q1), 0, 0]
[ 0, 0, 1, 12]
[ 0, 0, 0, 1]
```

`(:,:,2) =`

```
[ 0, 0, 1, 0]
[-1, 0, 0, 0]
[ 0, -1, 0, q2]
[ 0, 0, 0, 1]
```

`(:,:,3) =`

```
[ 0, -1, 0, 0]
[ 1, 0, 0, 0]
[ 0, 0, 1, q3]
[ 0, 0, 0, 1]
```

```
[ 0, -sin(q1), cos(q1), q3*cos(q1)]
[ 0, cos(q1), sin(q1), q3*sin(q1)]
[-1, 0, 0, q2 + 12]
[ 0, 0, 0, 1]
```

Warning: Solutions are only valid under certain conditions. To include parameters and conditions in the solution, specify the 'ReturnConditions' value as 'true'.

`Q =`

struct with fields:

```
q1: [2×1 sym]
q2: [2×1 sym]
q3: [2×1 sym]
```

`assume(q1>-pi & q1<pi & q2>0 & q3>0)`

```
EqX = px == expand(Tra(1));
EqY = py == expand(Tra(2));
EqZ = pz == expand(Tra(3));
```

```
EqAux = az == Rot(3,1);
EqAux2 = ay == Rot(2,1);
EqAux3 = ax == Rot(1,1);
```

```
jointVar = symvar(T);
```

```
%Q = solve([EqX EqY EqZ EqAux1 EqAux1b EqAux2 EqAux2b EqAux3 EqAux3b], jointVar, "Real")
```

```

Q = solve([EqX EqY EqZ EqAux EqAux2 EqAux3], jointVar(2:end), "Real",true) % Se puede j
Q2 = solve([EqX EqY EqZ EqAux EqAux2 EqAux3], jointVar, "Real",true) % Se puede jugar c

%Q.q1 = solve

%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%55

% A es el arreglo conteniendo las matrices de transformación de i = 1 a i =
% n. T es la matriz de transformación simplificada, la matriz de cinemática
% directa. Q es un vector conteniendo los resultados para las variables de
% q1 a qn. Rot es la matriz de rotación extraída de T. Y Tra es el vector
% posición extraído de T.

% syms n_x s_x a_x p_x n_y s_y a_y p_y n_z s_z a_z p_z
% T_syms = [n_x s_x a_x p_x;n_y s_y a_y p_y;n_z s_z a_z p_z;0 0 0 1];
%
% T1 = (A(:, :, 1))\T_syms == A(:, :, 2)*A(:, :, 3)

%inverseKinematics()

%   ia = inv(A(:, :, 1));
%   ter2 = A(:, :, 2) * A(:, :, 3);
%   eq1 = ter2(3,4) == ia (3,1)*px + ia(3,2) *py;
%   %q1 = solve(eq1,q1, 'real',true);
%
%   ib = inv(A(:, :, 2))*ia;
%   ter1 = A(:, :, 3);
%
%   eq2 = ter1(2,4) == ib(2,1)*px + ib(2,2)*py + ib(2,3)*pz + ib(2,4)*1;
%   eq3 = ter1(1,4) == ib(1,1)*px + ib(1,2)*py + ib(1,3)*pz + ib(1,4)*1;
%
%   [q2,q3] = solve([eq2,eq3],[q2 q3], 'real', true);
%
%   q1 = atan2(py,px);
%
%   q2 = eval(q2(1));
%   q3 = eval(q3(1));
%
%
%   th = [q1,q2,q3];
%   th2 = rad2deg(th);
%
%   th2(1)
%   th2(2)
%   th2(3)

```

```

clear, clc

syms px py pz az ax ay
syms q1 q2 q3

L1 = 12
L2 = L1
L3 = L1

DHParm = [q1 L1 0 pi/2; q2 0 L2 0; q3 0 L3 0];

[A, T, Q, Rot, Tra] = DH(DHParm, px, py, pz, az);

%assume(q1>-pi & q1<pi & q2>-pi & q2<pi & q3>-pi & q3<pi)
assume(pz>0 & q1<0 & q1 > -pi)% & q2>0 & q3>0)

EqX = px == simplify(Tra(1));
EqY = py == simplify(Tra(2));
EqZ = pz == simplify(Tra(3));

jointVar = symvar(T);

% Q3 = solve([EqZ], jointVar(3), 'real',true) % Se puede jugar con las
variables a resolver y a partir de ahí sacar la última solución. Usando la
primera variable como parámetro. Dado el caso de que las ecuaciones no son
linealmente independientes entre sí
% Q3b = Q3(1) %== q3
% %q3 = Q3(1)
% EqX = simplify(subs(EqX, q3, Q3b))
% EqY = simplify(subs(EqY, q3, Q3b))
% Q12 = solve([EqX EqY], jointVar(1:2)) % Se puede jugar con las
variables a resolver y a partir de ahí sacar la última solución. Usando la
primera variable como parámetro. Dado el caso de que las ecuaciones no son
linealmente independientes entre sí
% Q1 = solve([EqX], jointVar(1), 'real',true) % Se puede jugar con las
variables a resolver y a partir de ahí sacar la última solución. Usando la
primera variable como parámetro. Dado el caso de que las ecuaciones no son
linealmente independientes entre sí
% Q1b = Q1(2) %== q3
% %q3 = Q3(1)
% EqY = simplify(subs(EqY, jointVar(1), Q1b))
% EqZ = simplify(subs(EqZ, jointVar(1), Q1b))
% Q23 = solve([EqX EqY], jointVar(2:3)) % Se puede jugar con las
variables a resolver y a partir de ahí sacar la última solución. Usando la
primera variable como parámetro. Dado el caso de que las ecuaciones no son
linealmente independientes entre sí

%%%%%%%%%%55

% A es el arreglo conteniendo las matrices de transformación de i = 1 a i =

```

```
% n. T es la matriz de transformación simplificada, la matriz de cinemática
% directa. Q es un vector conteniendo los resultados para las variables de
% q1 a qn. Rot es la matriz de rotación extraída de T. Y Tra es el vector
% posición extraído de T.
```

```
% syms n_x s_x a_x p_x n_y s_y a_y p_y n_z s_z a_z p_z
% T_syms = [n_x s_x a_x p_x;n_y s_y a_y p_y;n_z s_z a_z p_z;0 0 0 1];
%
% T1 = (A(:, :, 1))\T_syms == A(:, :, 2)*A(:, :, 3)
```

```
%inverseKinematics()
```

```
ia = inv(A(:, :, 1));
ter2 = A(:, :, 2) * A(:, :, 3);
eq1 = ter2(3,4) == ia (3,1)*px + ia(3,2) *py;
%q1 = solve(eq1,q1, 'real',true);

ib = inv(A(:, :, 2))*ia;
ter1 = A(:, :, 3);

eq2 = ter1(2,4) == ib(2,1)*px + ib(2,2)*py + ib(2,3)*pz + ib(2,4)*1;
eq3 = ter1(1,4) == ib(1,1)*px + ib(1,2)*py + ib(1,3)*pz + ib(1,4)*1;

[q2,q3] = solve([eq2,eq3],[q2 q3], 'real', true);

q1 = atan2(py,px);

q2 = eval(q2(1));
q3 = eval(q3(1));

th = [q1,q2,q3];
th2 = rad2deg(th);

th2(1);
th2(2);
th2(3);
```

```
% fun = @(q) norm([Tra(1);Tra(2);Tra(3)]);
```

```
L1 =
```

```
12
```

```
L2 =
```

```
12
```

$L3 =$

12

3

$[q1, 12, 0, \pi/2]$

$[q2, 0, 12, 0]$

$[q3, 0, 12, 0]$

$(:,:,1) =$

```
[cos(q1),      0,  sin(q1),      0]
[sin(q1),      0, -cos(q1),      0]
[      0,      1,      0,      12]
[      0,      0,      0,      1]
```

$(:,:,2) =$

```
[cos(q2), -sin(q2),      0, 12*cos(q2)]
[sin(q2),  cos(q2),      0, 12*sin(q2)]
[      0,      0,      1,      0]
[      0,      0,      0,      1]
```

$(:,:,3) =$

```
[cos(q3), -sin(q3),      0, 12*cos(q3)]
[sin(q3),  cos(q3),      0, 12*sin(q3)]
[      0,      0,      1,      0]
[      0,      0,      0,      1]
```

```
[cos(q2 + q3)*cos(q1), -sin(q2 + q3)*cos(q1),  sin(q1), 12*cos(q1)*(cos(q2 +
q3) + cos(q2)))]
[cos(q2 + q3)*sin(q1), -sin(q2 + q3)*sin(q1), -cos(q1), 12*sin(q1)*(cos(q2 +
q3) + cos(q2)))]
[      sin(q2 + q3),      cos(q2 + q3),      0, 12*sin(q2 + q3) +
12*sin(q2) + 12]
[      0,      0,      0,
1]
```

Warning: Solutions are only valid under certain conditions. To include parameters and conditions in the solution, specify the 'ReturnConditions' value as 'true'.

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```

clear, clc
tic
syms px py pz az ax ay
syms q1 q2 q3

L1 = 13.5
L2 = 15
L3 = 20

DHPParam = [q1 L1 0 pi/2; (pi/2+q2) 0 L2 0; q3 0 L3 0];

[A, T, Q, Rot, Tra] = DH(DHPParam, px, py, pz, az);

%assume(q1>-pi & q1<pi & q2>-pi & q2<pi & q3>-pi & q3<pi)
assume(pz>0 & q1<0 & q1 > -pi)% & q2>0 & q3>0)

EqX = px == simplify(Tra(1));
EqY = py == simplify(Tra(2));
EqZ = pz == simplify(Tra(3));

jointVar = symvar(T);

%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%55

% A es el arreglo conteniendo las matrices de transformación de i = 1 a i =
% n. T es la matriz de transformación simplificada, la matriz de cinemática
% directa. Q es un vector conteniendo los resultados para las variables de
% q1 a qn. Rot es la matriz de rotación extraída de T. Y Tra es el vector
% posición extraído de T.

% syms n_x s_x a_x p_x n_y s_y a_y p_y n_z s_z a_z p_z
% T_syms = [n_x s_x a_x p_x;n_y s_y a_y p_y;n_z s_z a_z p_z;0 0 0 1];
%
% T1 = (A(:, :, 1))\T_syms == A(:, :, 2)*A(:, :, 3)

ia = inv(A(:, :, 1));
ter2 = A(:, :, 2) * A(:, :, 3);
eq1 = ter2(3,4) == ia(3,1)*px + ia(3,2) *py;
%q1 = solve(eq1,q1, 'real',true);

ib = inv(A(:, :, 2))*ia;
ter1 = A(:, :, 3);

eq2 = ter1(2,4) == ib(2,1)*px + ib(2,2)*py + ib(2,3)*pz + ib(2,4)*1;
eq3 = ter1(1,4) == ib(1,1)*px + ib(1,2)*py + ib(1,3)*pz + ib(1,4)*1;

%assume(q2>0 & q3>0)
[q2,q3] = solve([eq2,eq3],[q2 q3], 'real', true);

```

```

    q1 = atan2(-py,-px); %ajustado a mano para dar órdenes de valores
negativos

    q2a = eval(q2(1));
    q3a = eval(q3(1));

    q2b = eval(q2(2));
    q3b = eval(q3(2));

    toc

%     th = [q1,q2,q3];
%     th2 = rad2deg(th);
%
%     th2(1);
%     th2(2);
%     th2(3);

% fun = @(q) norm([Tra(1);Tra(2);Tra(3)]);

L1 =

    13.5000

L2 =

    15

L3 =

    20

    3

[q1, 27/2, 0, pi/2]

[q2 + pi/2, 0, 15, 0]

[q3, 0, 20, 0]

(:, :, 1) =

[      cos(q1),      0,  sin(q1),      0]
[      sin(q1),      0, -cos(q1),      0]
[           0,      1,      0,    27/2]
[           0,      0,      0,      1]

(:, :, 2) =

```

```

[cos(q2 + pi/2), -sin(q2 + pi/2),      0, 15*cos(q2 + pi/2)]
[sin(q2 + pi/2),  cos(q2 + pi/2),      0, 15*sin(q2 + pi/2)]
[      0,      0,      1,      0]
[      0,      0,      0,      1]

(:, :, 3) =

[      cos(q3),      -sin(q3),      0,      20*cos(q3)]
[      sin(q3),      cos(q3),      0,      20*sin(q3)]
[      0,      0,      1,      0]
[      0,      0,      0,      1]

[-sin(q2 + q3)*cos(q1), -cos(q2 + q3)*cos(q1),  sin(q1), -5*cos(q1)*(4*sin(q2
+ q3) + 3*sin(q2))]
[-sin(q2 + q3)*sin(q1), -cos(q2 + q3)*sin(q1), -cos(q1), -5*sin(q1)*(4*sin(q2
+ q3) + 3*sin(q2))]
[      cos(q2 + q3),      -sin(q2 + q3),      0,      20*cos(q2 + q3) +
15*cos(q2) + 27/2]
[      0,      0,      0,
1]

```

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Elapsed time is 44.052097 seconds.

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