7A. When we run the algorithm in a single iteration with height 0.5 meters, we observed that the robot arm moves a little away from the desired goal position. This is due to the Jacobian pseudo-inverse being taken for one time, where as when we take a smaller step size, the Jacobian changes in each iteration correcting the course and helping the hand move a lot closer to desired goal position. The reason Jacobian plays an important role is due to the fact that its derived from robot arm end-effector body node. And we know that

$$\Delta p = \alpha * J * \Delta q$$
$$\Delta p = p_d - p_{curr}$$
$$\Delta q = q - q_o$$

p_d and p_{curr} are desired and current positions,
q and q_o are the current and initial configuration states,
J is the Jacobian,
α is the step size.
Thus, making a single iteration and multiple iterations for same goal state with small step size result in two significantly different goal positions