```matlab
% Assignment 2 - Question 1, Forward Kinematics
clear all;
%lengths
l0 = 1;
l1 = 1;
l2 = 1;
%M
M = [1, 0, 0, 0;
     0, 1, 0, l1+l2;
     0, 0, 1, l0;
     0, 0, 0, 1];
%Screw Axes
S1 = [0,0,1,0,0,0];
S2 = [0,0,1,l1,0,0];
S3 = [0,0,1,l1+l2,0,0];
S4 = [0,0,0,0,0,1];
Slist = [S1', S2', S3', S4'];
%Body Axes
B1 = [0,0,1,-(l1+l2),0,0];
B2 = [0,0,1,-l2,0,0];
B3 = [0,0,1,0,0,0];
B4 = [0,0,0,0,0,1];
Blist = [B1', B2', B3', B4'];
%thetalist
thetalist = [0;pi/2;-pi/2;1];
%Configuration Space frame
Ts = FKinSpace(M,Slist,thetalist);
%Configuration Body Frame
Tb = FKinBody(M,Blist,thetalist);

% OUTPUT
% Ts =
%
%      1      0      0     -1
%      0      1      0      1
%      0      0      1      2
%      0      0      0      1
%
%
% Tb =
%
%      1      0      0     -1
%      0      1      0      1
%      0      0      1      2
%      0      0      0      1
```

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