1. execise

```
U_T_R 입력
0 0 -1 8
0 1 0 2
1 0 0 -1
0 0 0 1
U_T_H 입력

1 0 0 0
0 1 0 6
0 0 1 2
0 0 0 1
행렬 연산 전 과정에 대한 결과를 보기 위해서는 0번
최종 R_T_H만 보려면은 1번
0
==========================================================================================
U_T_R
0  0  -1  8
0  1  0  2
1  0  0  -1
0  0  0  1

U_T_H
1  0  0  0
0  1  0  6
0  0  1  2
0  0  0  1

Result_Matrix (HT_Multiply)
0 0 1 -6

0 1 0 -2

-1 0 0 -8

0 0 0 1

Inverse_Matrix (HT_Inverse)
0 0 1 -8

0 1 0 -8

-1 0 0 -8

0 0 0 1

Rot
Rot: 1 Rot: 1 Rot: 1 Rot: 8.30662

==========================================================================================
```

2. execise

```
POS 입력

1.5 1.0 0.5

RPY 입력

90 45 30


0:theta1 , theta234, +s3
================================================================================
POS

1.500 1.000 0.500
RPY

1.571 0.785 0.524
Matrix

0.000  -0.866  0.500  0.000

0.707  0.354  0.612  0.000

-0.707  0.354  0.612  0.000

0.000  0.000  0.000  1.000


R_T_H

0.000  -0.866  0.500  1.500

0.707  0.354  0.612  1.000

-0.707  0.354  0.612  0.500

0.000  0.000  0.000  1.000


Joint_Angle(rad)

0 0.588  -0.226  0.948  -0.041  1.805  -0.921



Joint_Angle(deg)

0 33.690  -12.936  54.306  -2.351  103.425  -52.780


================================================================================
```