# [0]:(0\*(-(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*sin(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*cos(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta5))\*sin(theta6) + 1.0\*((0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*cos(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*sin(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*sin(theta5))\*cos(theta6) - 1.0\*(0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - 1.0\*((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*cos(theta2) + 0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*sin(theta6))\*cos(theta8) + 1.0\*(-0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) + 0\*((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*sin(theta5) - 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*cos(theta5) - 0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4) + 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta5) - 0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1)\*cos(theta3) + 0\*sin(theta1) – 0\*sin(theta2)\*cos(theta1))\*sin(theta8)

[1]:-(0\*(-(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*sin(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*cos(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta5))\*sin(theta6) + 1.0\*((0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*cos(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*sin(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*sin(theta5))\*cos(theta6) - 1.0\*(0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - 1.0\*((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*cos(theta2) + 0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*sin(theta6))\*sin(theta8) + 1.0\*(-0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) + 0\*((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*sin(theta5) - 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*cos(theta5) - 0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4) + 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta5) - 0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1)\*cos(theta3) + 0\*sin(theta1) – 0\*sin(theta2)\*cos(theta1))\*cos(theta8)

[2]:0\*(-(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*sin(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*cos(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta5))\*cos(theta6) - 1.0\*((0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*cos(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*sin(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*sin(theta5))\*sin(theta6) - 1.0\*(0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - 1.0\*((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*cos(theta2) + 0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta6)

[3]:theta7\*(0\*(-(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*sin(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*cos(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta5))\*cos(theta6) - ((0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*cos(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*sin(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*sin(theta5))\*sin(theta6) - 1.0\*(0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - 1.0\*((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*cos(theta2) + 0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta6)) + 0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0.04951\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + 0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - 0.36665\*((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 0.04951\*((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) - 0\*(-(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*sin(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*cos(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta5))\*sin(theta6) + 0\*(-(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*sin(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*cos(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta5))\*cos(theta6) - 0.39443\*((0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4)

+ 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*cos(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*sin(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*sin(theta5))\*sin(theta6) - 0.0405\*((0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*sin(theta4) + ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*cos(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4))\*cos(theta5) + 0\*(0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - ((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4))\*sin(theta5) - 1.0\*(1.0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*sin(theta1)\*cos(theta2) + 1.0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*sin(theta5))\*cos(theta6) + 0.04951\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*sin(theta4) + 0.36665\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4) + 0.0405\*(0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - 1.0\*((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*cos(theta2) + 0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*sin(theta6) - 0.39443\*(0\*(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) + 0\*(-(-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*sin(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*cos(theta3) - 1.0\*sin(theta1)\*cos(theta3))\*cos(theta4) - 1.0\*((-0\*sin(theta1)\*sin(theta2) + cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(-0\*sin(theta1)\*cos(theta2) - sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*sin(theta1)\*sin(theta3))\*sin(theta4) + 1.0\*(0\*sin(theta1)\*cos(theta2) - 0\*sin(theta1) + 1.0\*sin(theta2)\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*cos(theta2) + 0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0\*sin(theta2)\*cos(theta1))\*cos(theta6) + 0.04951\*sin(theta1)\*sin(theta3) + 0\*sin(theta1)\*cos(theta2) + 0\*sin(theta1)\*cos(theta3) - 0\*sin(theta1) + 0.3633\*sin(theta2)\*cos(theta1)

[4]:(1.0\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*sin(theta5) + ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*cos(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*sin(theta5))\*cos(theta6) + 0\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*cos(theta5) - ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*sin(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta5))\*sin(theta6) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*sin(theta6))\*cos(theta8) + 1.0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - 0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) - 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) - 0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*cos(theta5) + 1.0\*((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*sin(theta5) - 0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4) + 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta5) - 0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1)\*cos(theta3) – 0\*cos(theta1))\*sin(theta8)

[5]:-(1.0\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*sin(theta5) + ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*cos(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*sin(theta5))\*cos(theta6) + 0\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*cos(theta5) - ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*sin(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta5))\*sin(theta6) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*sin(theta6))\*sin(theta8) + 1.0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - 0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) - 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) - 0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*cos(theta5) + 1.0\*((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*sin(theta5) - 0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4) + 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta5) - 0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1)\*cos(theta3) – 0\*cos(theta1))\*cos(theta8)

[6]:-1.0\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*sin(theta5) + ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*cos(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*sin(theta5))\*sin(theta6) + 0\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*cos(theta5) - ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*sin(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta5))\*cos(theta6) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta6)

[7]:theta7\*(-(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*sin(theta5) + ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*cos(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*sin(theta5))\*sin(theta6) + 0\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*cos(theta5) - ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*sin(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta5))\*cos(theta6) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta6)) - 0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) - 0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) - 0.04951\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) - 0.36665\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0.04951\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) - 0.39443\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*sin(theta5) + ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*cos(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*sin(theta5))\*sin(theta6) - 0.0405\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*sin(theta5) + ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*cos(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*sin(theta5))\*cos(theta6) - 0\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2)

+ 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*cos(theta5) - ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*sin(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta5))\*sin(theta6) + 0\*(0\*(-(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4))\*cos(theta5) - ((0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*cos(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*sin(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4))\*sin(theta5) - 1.0\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 1.0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 1.0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta5))\*cos(theta6) + 0.04951\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*sin(theta4) + 0.36665\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4) + 0.0405\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*sin(theta6) - 0.39443\*(-0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) + 0\*(1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) - 1.0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*sin(theta3) + (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*cos(theta3) + 1.0\*sin(theta3)\*cos(theta1))\*sin(theta4) + 0\*(0\*(-1.0\*sin(theta1)\*sin(theta2) + 0\*cos(theta1)\*cos(theta2))\*cos(theta3) - (1.0\*sin(theta1)\*cos(theta2) + 0\*sin(theta2)\*cos(theta1))\*sin(theta3) + 1.0\*cos(theta1)\*cos(theta3))\*cos(theta4) + 1.0\*(1.0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) + 0\*cos(theta1))\*cos(theta4) + 0\*sin(theta1)\*sin(theta2) - 0\*cos(theta1)\*cos(theta2) - 0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1))\*cos(theta6) + 0.3633\*sin(theta1)\*sin(theta2) - 0.04951\*sin(theta3)\*cos(theta1) - 0\*cos(theta1)\*cos(theta2) - 0\*cos(theta1)\*cos(theta3) + 0\*cos(theta1)

[8]:(0\*(-(1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*sin(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*cos(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta5))\*sin(theta6) + 1.0\*((1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*cos(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*sin(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*sin(theta5))\*cos(theta6) - 1.0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - 1.0\*(-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4) - 0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*sin(theta6))\*cos(theta8) + 1.0\*(-0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 1.0\*(1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*sin(theta5) - 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*cos(theta5) - 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) + 0\*(-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4) + 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta5) + 0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) - 0\*cos(theta2) + 0\*cos(theta3) – 0)\*sin(theta8)

[9]:-(0\*(-(1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*sin(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*cos(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta5))\*sin(theta6) + 1.0\*((1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*cos(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*sin(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*sin(theta5))\*cos(theta6) - 1.0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - 1.0\*(-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4) - 0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*sin(theta6))\*sin(theta8) + 1.0\*(-0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 1.0\*(1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*sin(theta5) - 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*cos(theta5) - 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) + 0\*(-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4) + 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta5) + 0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) - 0\*cos(theta2) + 0\*cos(theta3) – 0)\*cos(theta8)

[10]:0\*(-(1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*sin(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*cos(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta5))\*cos(theta6) - 1.0\*((1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*cos(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*sin(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*sin(theta5))\*sin(theta6) - 1.0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - 1.0\*(-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4) - 0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta6)

[11]:theta7\*(0\*(-(1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*sin(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*cos(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta5))\*cos(theta6) - ((1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*cos(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*sin(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*sin(theta5))\*sin(theta6) - 1.0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - 1.0\*(-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4) - 0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta6)) + 0.04951\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0.36665\*(1.0\*cos(theta2) + 0)\*cos(theta4) - 0\*(-(1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*sin(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*cos(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta5))\*sin(theta6) + 0\*(-(1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*sin(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*cos(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta5))\*cos(theta6) - 0.39443\*((1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*cos(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*sin(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*sin(theta5))\*sin(theta6) - 0.0405\*((1.0\*(1.0\*cos(theta2) + 0)\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4))\*cos(theta5) + 0\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - (-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4))\*sin(theta5) - 1.0\*(-1.0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*sin(theta5))\*cos(theta6) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*sin(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - 0.36665\*(-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4) + 0.04951\*(-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*cos(theta4) + 0.0405\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - 1.0\*(-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4) - 0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*sin(theta6) - 0.39443\*(1.0\*(1.0\*cos(theta2) + 0)\*cos(theta4) + 0\*(1.0\*sin(theta2)\*sin(theta3) - 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta3))\*cos(theta4) - 1.0\*(-1.0\*sin(theta2)\*cos(theta3) - 0\*sin(theta3)\*cos(theta2) + 0\*sin(theta3))\*sin(theta4) - 0\*sin(theta2)\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0\*cos(theta2) - 0\*cos(theta3) + 0)\*cos(theta6) - 0\*sin(theta2)\*sin(theta3) + 0.04951\*sin(theta2)\*cos(theta3) + 0\*sin(theta3)\*cos(theta2) - 0\*sin(theta3) + 0\*cos(theta2)\*cos(theta3) + 0.3633\*cos(theta2) - 0\*cos(theta3) + 0.27985