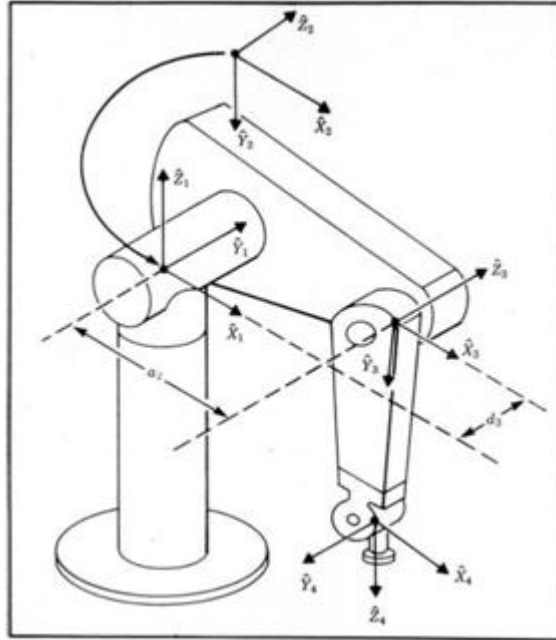# MMC Homework 3

1. Program Forward Kinematics for Puma 560 Robots using Matlab

choose   [a2, a3, d3, d4] as [1   0.3 0.5 1]   and $^6P_T = [0\,0\,0.3]^T$

a)   When $\theta_1 = 30°$, $\theta_2 = 30°$, $\theta_3 = 30°$, $\theta_4 = 30°$, $\theta_5 = 30°$, $\theta_6 = 30°$,   find $^0_T T$.

b)   Find 8 sets of solution from Inverse Kinematics with the $^0_T T$
       Confirm that one of 8 solution sets is the joint angle set in a)