Teach Pendant

1. When testing the inverse kinematic model with the common positions of interest, did you observe any invalid kinematic solutions? Why was the solution invalid? Provide an example.

2. Show the results that you obtained from running the teach pendant in follow mode. How well did the arm track the desired waypoints? Comment on the transient and steady-state responses of tracking along the x, y and z axes.

3. The timer developed in the Teach Pendant Learn application does not depend on the distance between the waypoints. What is a major drawback to this application? Can you recommend a way to solve this?