**DH matrix, Jacobian-Origin-Z vectors, Gravity Matrix are being printed to the terminal using these function call respectively.**

# Print Homogenous Transformation Matrix

print\_DH\_MATRIX()

# Print Origin Vectors, Origin Vectors and Jacobian Matrix

print\_J\_O\_Z\_vectors()

#Print GENERIC GRAVITY MATRIX

print\_generic\_gravity\_matrix()

# Home Position Of End Effector

q\_initial = sp.Matrix([0, 0, 0, 0, 0, 0])

**Joint Torques for each joint is being plotted and the circle traced by the end effector is also being plotted using the below function.**

#Plots JOINT TORQUES and PRINTS THE CIRCLE TRACED

print\_joint\_torques(q\_initial)