Part 1 (b)

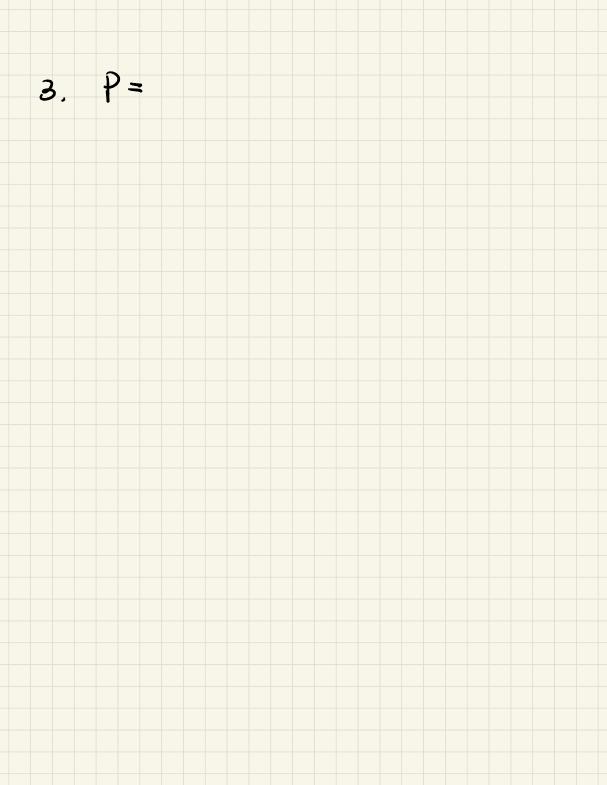
1.  $M = R_x(a) R_y(b) R_z(c)$ a, b, c correspond to  $R_x$ ,  $R_y$ ,  $R_z$ 

a, b, c correspond to Rx, Ry, Rz respectively.

 $\lambda$ . N' = MNP

$$p = T(x_0, y_0, z_0)R(\theta_0)R(\varphi_0)R(\delta_0)T_1^0R(\theta_1)R(\varphi_1)R(\delta_1)T_2^1R(\theta_2)T_3^2R(\theta_3)R(\varphi_3)x$$

Followed by the formula from the lecture, we should multiply the rotation matrix from A to B as M, then multiply the rotation N in an arbitrary coordinate system B, bast we multiply the joint's coordinates in A as p.



## Part 2.

https://drive.google.com/drive/folders/1dMkAiJDPgAzD86muCzP5ZRNFMdpE45U8?usp=sharing