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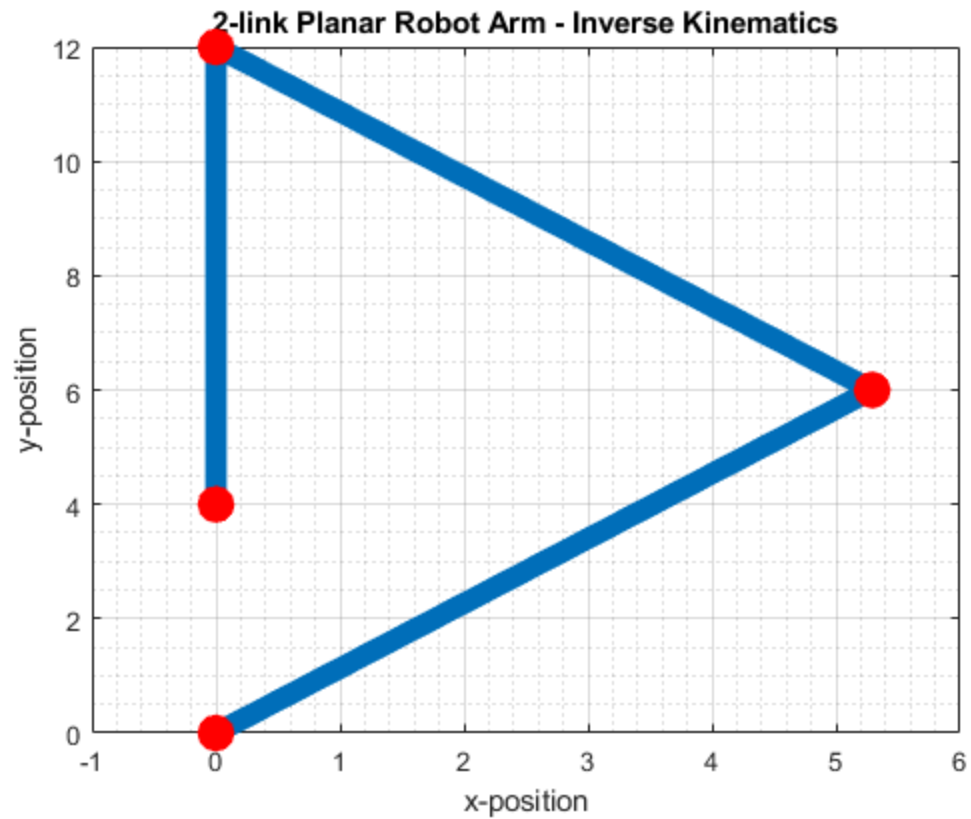
Housekeeping

Get Endpoint
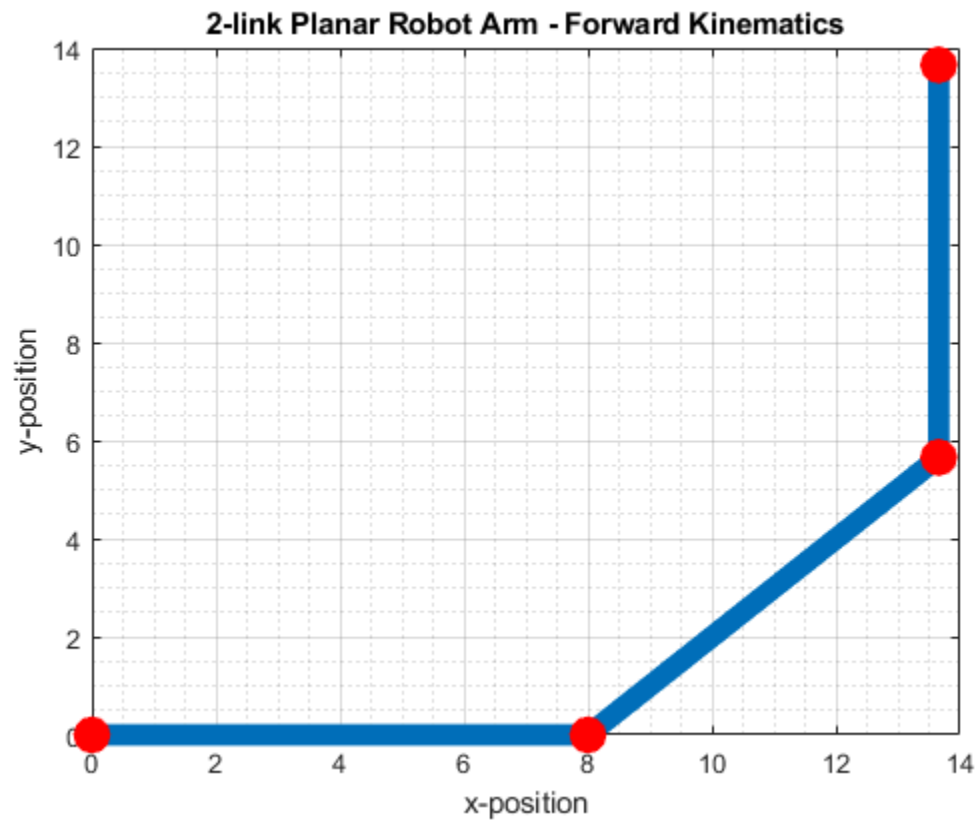
Get Configuration

```
The final configuration of the robot arm is:
Theta1: 0.848062 rad, Theta2: 1.445468 rad, Theta3: 2.418858 rad
```

2-link Planar Robot Arm - Inverse Kinematics

Functions

The final position of the endpoint is: (13.656854,13.656854)

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