Published on Sep 24, 2017
I'm at IROS http://www.iros2017.org/ learning about robots and meeting wonderful roboticists (and my lab has 6 great papers). Unfortunately I'm missing my Intro to Robotics class. Usually at 8:30 am we would be talking about Kinematics from Ch 3.3 of "Robot Dynamics and Control". This lecture discusses inverse kinematics, why we prefer closed form solutions, why there may be 0 or many solutions, and how to find the wrist center.

## Intro to Robotics: Inverse Kinematics Lecture 8, Fall 2017


19:42

Aaron Becker

https://www.youtube.com/watch?v=TPjclVs4RIY

## Inverse Kinematics Position: Intro Robotics, Lecture 9


15:27

Aaron Becker

https://www.youtube.com/watch?v=9HfcMkfLh6k

## Inverse Kinematics and Trajectory Execution of a robot manipulator using ROS Moveit and Arduino.   17:00  He builds a robot and Software

https://www.youtube.com/watch?v=G-XXnPHYhxs

The **ROS** packages in this repository were created to provide an improved alternative Inverse Kinematics solver to the popular inverse Jacobian methods in KDL. TRAC-IK handles joint-limited chains better than KDL without increasing solve time.

http://wiki.ros.org/trac_ik

TRACLabs Inc. is glad to announce the public release of our Inverse Kinematics solver TRAC-IK.  TRAC-IK is a faster, significantly more reliable drop-in replacement for KDL's pseudoinverse Jacobian solver.

https://www.ros.org/news/2015/11/introducing-a-better-inverse-kinematics-package.html

# Evolutionary Inverse Kinematics
# for ROS and MoveIt

Philipp Ruppel
May 30, 2017
Master Thesis

Position feedback from Servo

URDF of the manipulator

Checking motor controllers.

Moveit UI.

Ik using Moveit commander.

Trajectory Execution

**MATLAB**

Control PR2 Arm Movements Using ROS Actions and Inverse Kinematics - MATLAB Video

https://www.youtube.com/watch?v=l6j9deRD93g