V. CONCLUSION AND RECOMENDATIONS

5.1 Conclusion

1. The inverse kinematic equations for a 6-DOF robotic arm have been obtained, and these equations have been tested in simulations performed on 3D graphics.

2. The inverse kinematic equations have been applied to the robotic arm, and the results show that the arm moves according to the target position, although there are still orientation errors.

5.2 Recomendations

1. Replace the belt with a wider one. Avoid slack installation, as this can cause the belt to slip.

2. Add a sensor to joint 4.

3. To facilitate data recording before the robot automatically moves, you can use a camera using the camera calibration method.