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 1. Consider The Following RRRR Manipulator (image Courtesy J. J. Craig): It Has The Following Forward Kinematics And Rotational Jacobian:

$${}^0_4T = \begin{bmatrix} 2 & 6 & 6 & 6 \\ 6 & 4 & C_{12} & c_{34} \\ -\sqrt{2}s_{12}s_{34} & -c_{12}s_{34} & \sqrt{2}s_{12}c_{34} & \sqrt{2}s_{12} \\ \sqrt{2}c_{12}s_{34} & -s_{12}(s_{34}-1) & c_{12}c_{34} & \sqrt{2}c_{12}s_{34} \end{bmatrix}$$
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