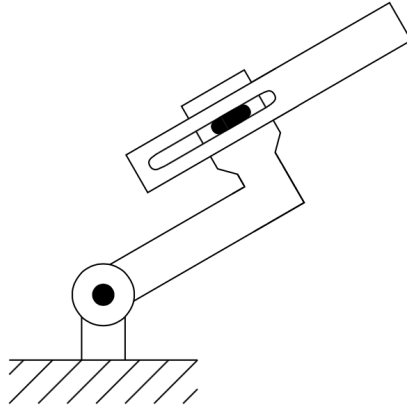
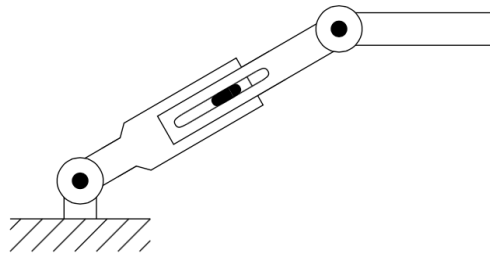


#### Homework 4 (Problem numbers from textbook)

- 3.4** Write the forward kinematics equations (attach the DH frames, write the DH table, then write the homogeneous transformation matrices and multiply them together to find the end effector coordinate frame in terms of the base frame) using the DH convention for the two-link manipulator (first joint revolute and second joint prismatic) shown below.



- 3.5** Write the forward kinematics equations using the DH convention for the three-link manipulator (first joint revolute, second joint prismatic, third joint revolute) shown below.



- 3.7** Write the forward kinematics equations using the DH convention for the three-link manipulator (first joint prismatic, second joint prismatic, third joint prismatic) shown below.

