Appendix A. Technical Drawing

	d	θ	a	α	ref
1	0	θ_1	0	$-\pi/2$	0
2	0	θ_2	0	$\pi/2$	$-\pi/2$
3	d_3	0	0	0	0
4	0	θ_4	0	$-\pi/2$	$\pi/2$
5	0	θ_5	a_5	$-\pi/2$	$-\pi/2$
6	0	θ_6	a_6	0	0

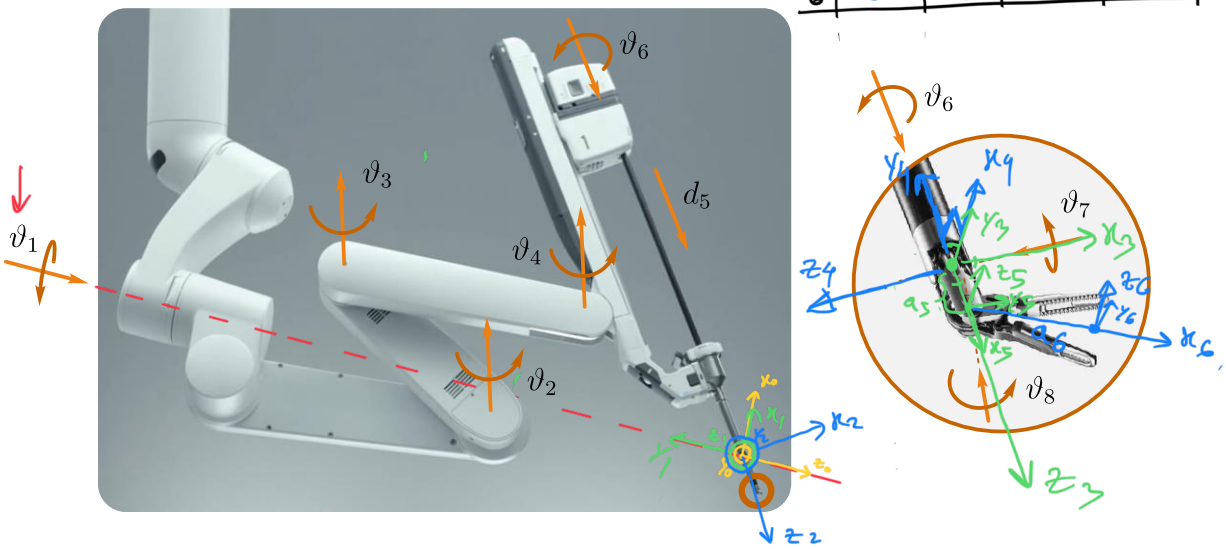

Figure A1. Rotation axes for ϑ_1 and ϑ_2 are orthogonal. Rotation axes for ϑ_2, ϑ_3 and ϑ_4 are parallel. Rotation axes for ϑ_6 and ϑ_7 intersect at a common point and are orthogonal. Rotation axes for ϑ_7 and ϑ_8 are orthogonal and they are spaced by 10 mm.

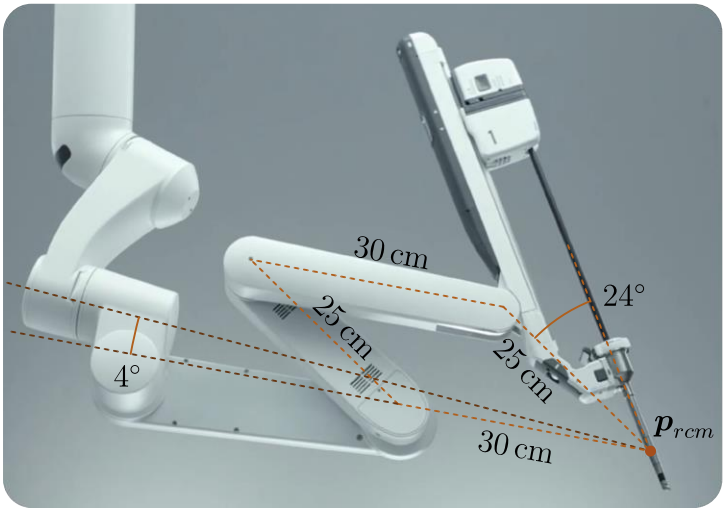

Figure A2. Additional dimensions and geometry. Joints 2, 3 and 4 are mechanically coupled, so that the parallelogram edges are always kept parallel. The rotation axis for ϑ_1 always intersects a fixed point in the manipulator, $\boldsymbol{p}_{rcm}$, termed the *remote center of motion*.