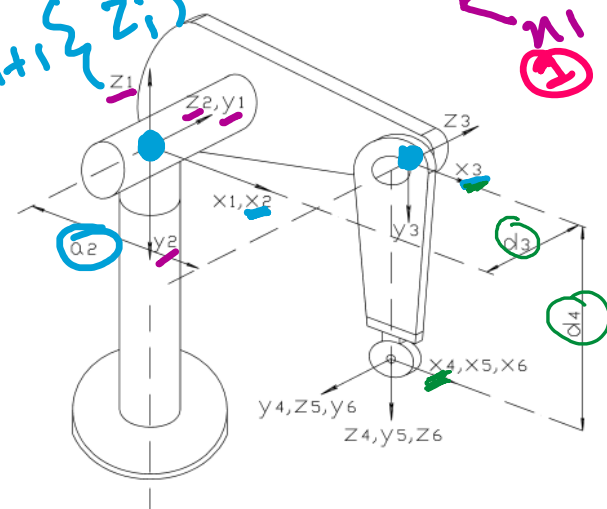


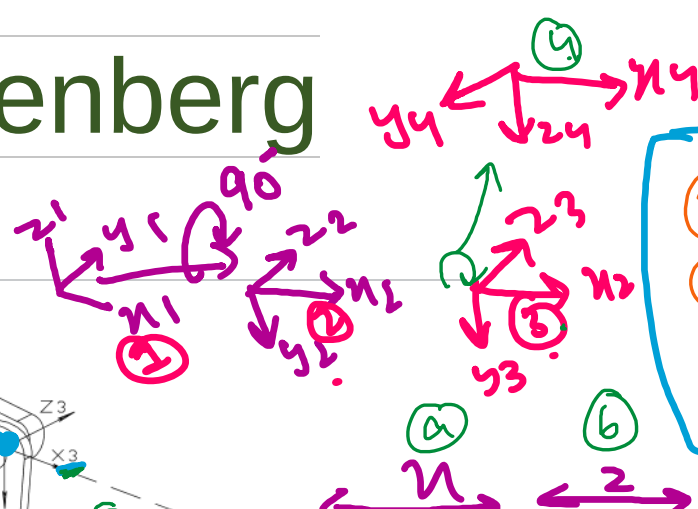
Denavit–Hartenberg Parameters

Tuesday, 21 September

(α_i, a_i, d_i)
 (z_{i+1}, z_i)



Picture 1: Robotic manipulator PUMA560 with assigned link parameters according to J.J. Craig



1-2

1	Q_1	-90°	D_1	0	Q_2	0°	D_2	0
2	Q_2	0°	D_2	a_2	Q_3	0°	D_3	d_3
3	Q_3	0°	D_3	a_3	Q_4	0°	D_4	d_4

i	α_{i-1}	a_{i-1}	d_i	θ_i
1	0°	0	0	θ_1
2	-90°	0	0	θ_2
3	0°	a_2	d_3	θ_3
4	-90°	a_3	d_4	θ_4
5	90°	0	0	θ_5
6	-90°	0	0	θ_6

Table 1: Link parameters for PUMA 560 robotic manipulator

<https://robotics.stackexchange.com/questions/11878/modified-dh-parameter-for-puma-560>