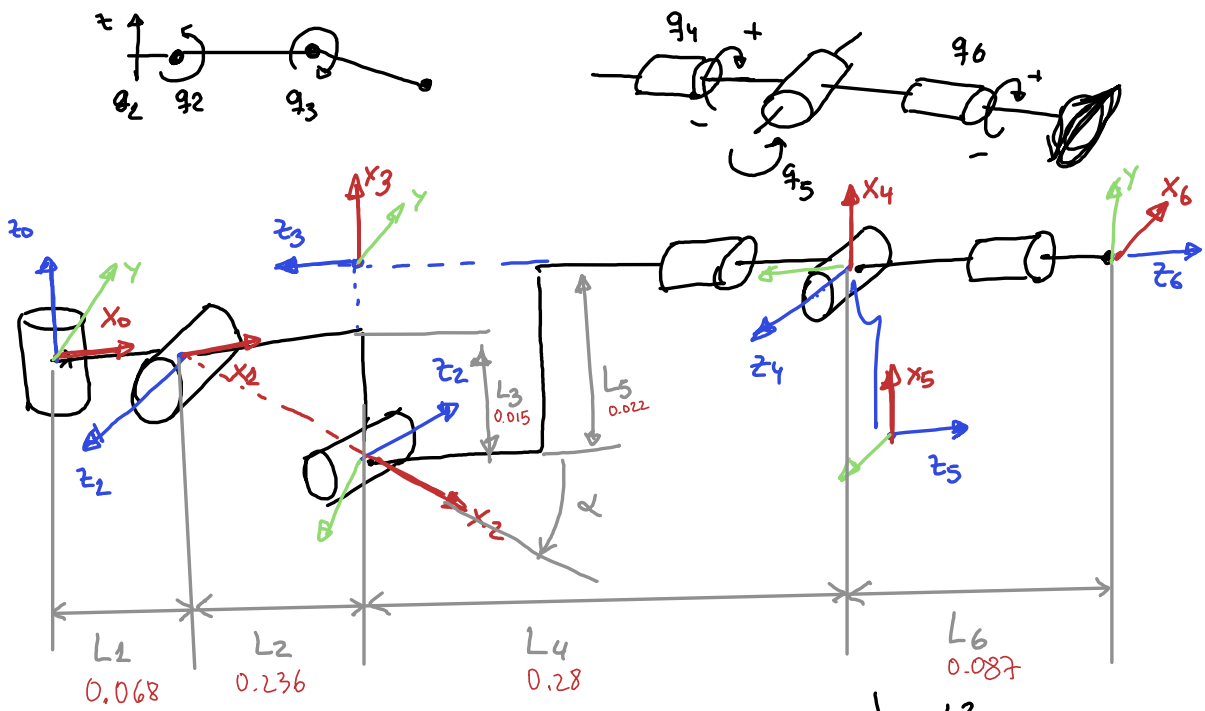


Referencias del robot

Patiz rectiz: 180 180 90 180 180 180



$$L_c = \sqrt{L_2^2 + L_3^2}$$

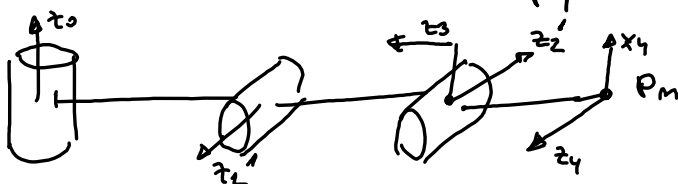
$$L_d = \sqrt{L_5^2 + L_4^2}$$

$$\alpha = \arctan \frac{L_3}{L_2}$$

$$\beta = \arctan \frac{L_5}{L_4}$$

DH	θ	d	a	α
1	q_2	0	L_1	$\frac{\pi}{2}$
2	$q_2 - \alpha$	0	L_c	π
3	$q_3 - \frac{\pi}{2} - \alpha$	0	L_5	$\frac{\pi}{2}$
4	q_4	$-L_4$	0	$\frac{\pi}{2}$
5	q_5	0	0	$\frac{\pi}{2}$
6	$q_6 - \frac{\pi}{2}$	L_6	0	0

Modelo simplificado Pm

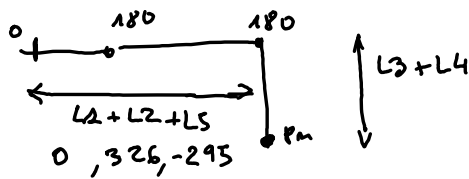
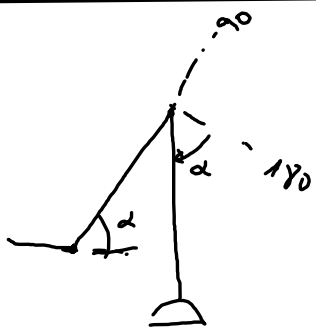


$$q_2' = q_2 - \alpha$$

$$q_3' = q_3 - \beta - \alpha$$

q_2	0	L_2	$\frac{\pi}{2}$
q_2'	0	L_c	π
$q_3' - \frac{\pi}{2}$	0	0	$\frac{\pi}{2}$
q_4	$-L_d$	0	$\frac{\pi}{2}$

utilizo solo por obtener P_m , dado que se llega grado β



Tipices

$$L_1 = 0.068$$

$$L_2 = 0.236$$

$$L_3 = 0.0149$$

$$L_4 = 0.28$$

$$L_5 = 0.022$$

$$L_6 = 0.087$$