UNIVERSIDAD POLITÉCNICA
DE LA ZONA METROPOLITANA DE GUADALAJARA

Materia: Cinemática de robots
Profesor: Morán Garabito Carlos Enrique

PRACTICA #1

UNIVERSIDAD POLITÉCNICA
DE LA ZONA METROPOLITANA DE GUADALAJARA

T/M 8`B

UPZMG

Alumno: CHRISTIAN SALVADOR GOMEZ CARRILLO,

Materia: **Cinemática de robots**
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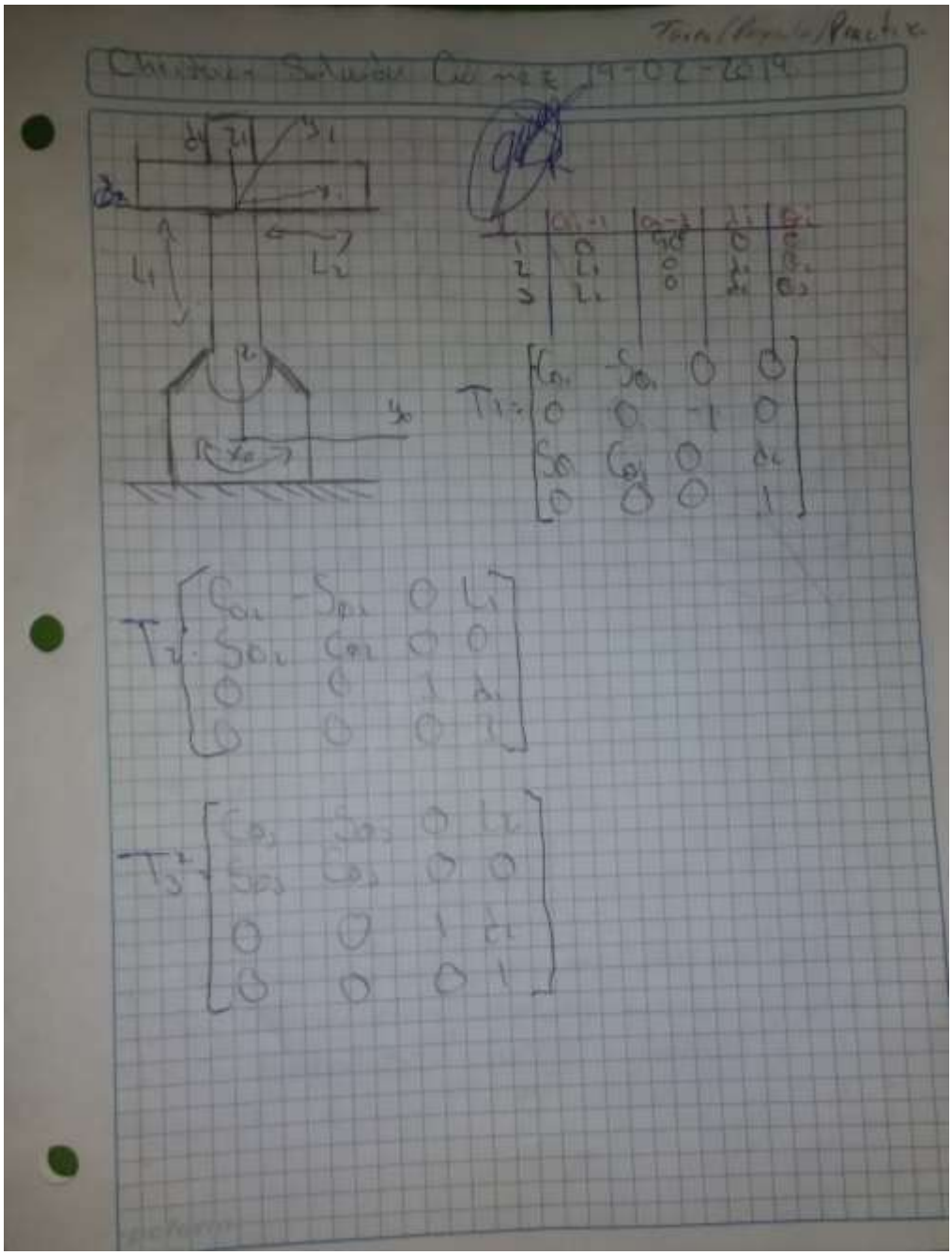

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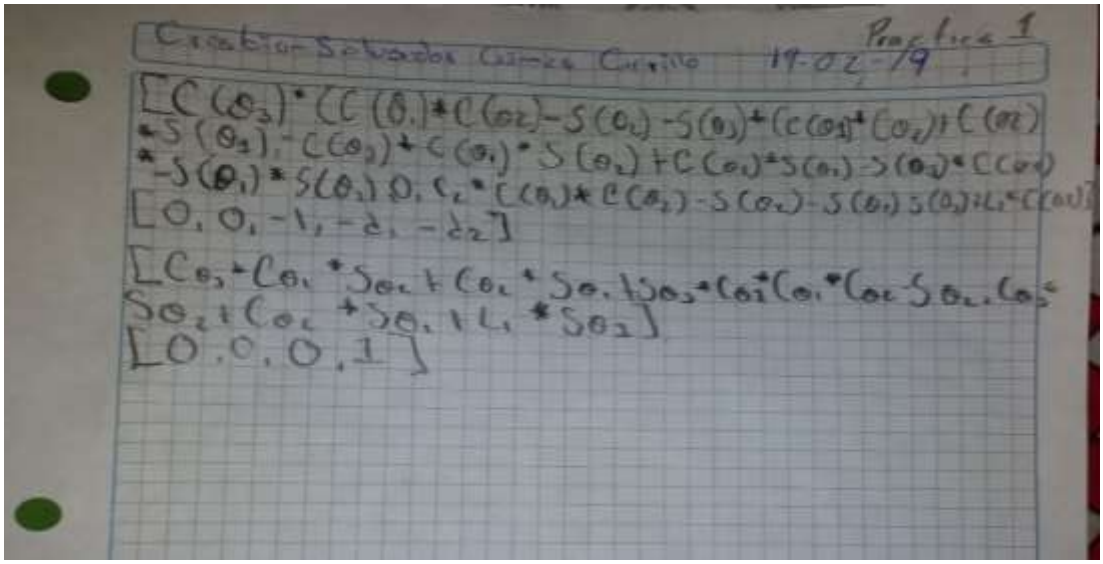

Código de Matlab:

```
T1=[cos(theta1),-sin(theta1),0,0;0,0,-1,0;sin(theta1),cos(theta1),0,0;0,0,0,1]
syms L1
T2=[cos(theta2),-sin(theta2),0,L1;sin(theta2),cos(theta2),0,0;0,0,1,d1;0,0,0,1]
syms L2
T3=[cos(theta3),-sin(theta3),0,L2;sin(theta3),cos(theta3),0,0;0,0,1,d2;0,0,0,1]
```

i	Ai-1	α-1	Di	Θi
1	0	90°	0	Θ1
2	L1	0	D1	Θ2
3	L2	0	D2	Θ3

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