Tableau 2. Résultats pour la cinématique directe.

|  |  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Variables articulaires | | | | Pose obtenue dans Matlab | | | | | |
| *d*1  [mm] | **2  [°] | **3  [°] | **4  [°] | *x*  [mm] | *y*  [mm] | *z*  [mm] | *w*  [°] | *p*  [°] | *r*  [°] |
| 134 | 68 | -26 | 10 |  |  |  |  |  |  |
| 200 | 70 | -45 | 25 |  |  |  |  |  |  |
| 0 | 100 | 75 | 50 |  |  |  |  |  |  |

Tableau 3. Résultats pour la cinématique inverse.

|  |  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- | --- |
| Pose obtenue dans RobotStudio | | | | | | Variables articulaires obtenues dans MATLAB | | | |
| *x*  [mm] | *y*  [mm] | *z*  [mm] | *w*  [°] | *p*  [°] | *r*  [°] | *d*1  [mm] | **2  [°] | **3  [°] | **4  [°] |
| -915.29 | -661.39 | 697.96 | -11.6 | -9.58 | 60.97 |  |  |  |  |
| 546.19 | 671.32 | 148.18 | -180 | 80 | -115 |  |  |  |  |
| 0 | -1429.41 | 132.04 | -169.27 | -10.55 | -135.99 |  |  |  |  |