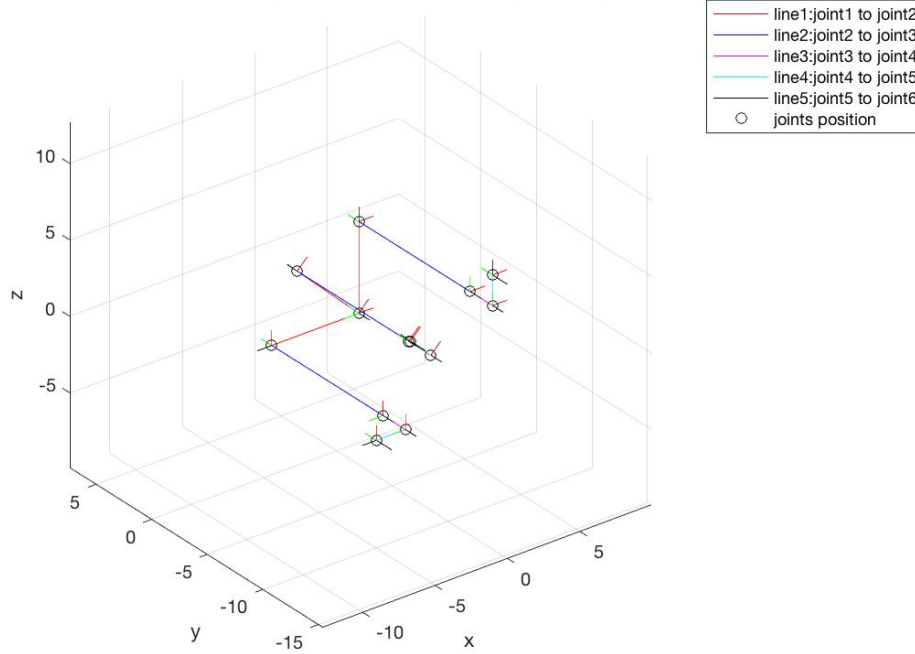


ESE446 Robotics and Dynamics, Assignment: Stanford Arm

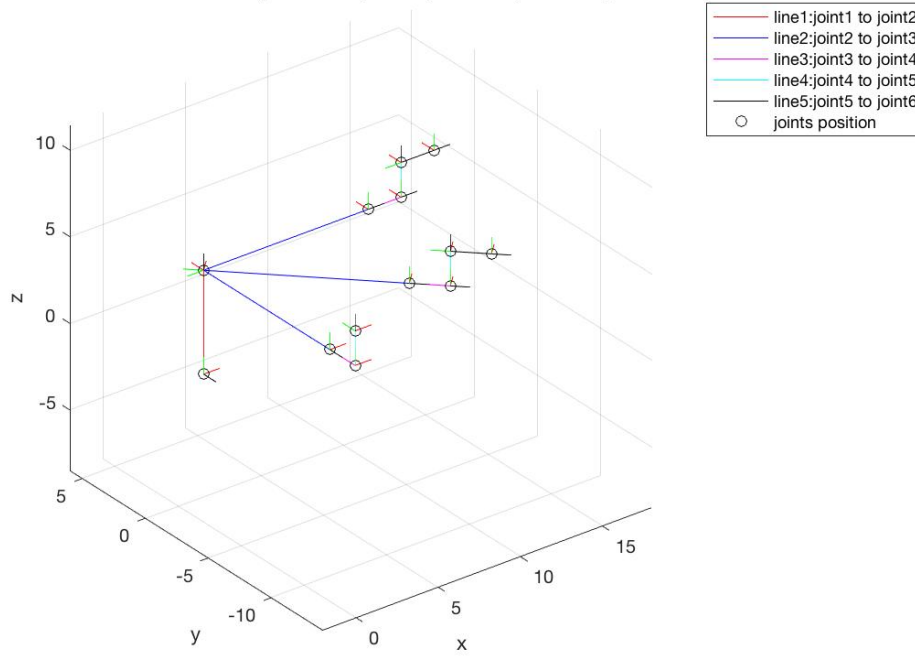
Rotate $\theta_1 = 0 \rightarrow 45 \rightarrow 90$

Stanford Arm: $\theta_1=90, \theta_2=0, d_3=10, \theta_4=0, \theta_5=0, \theta_6=0$

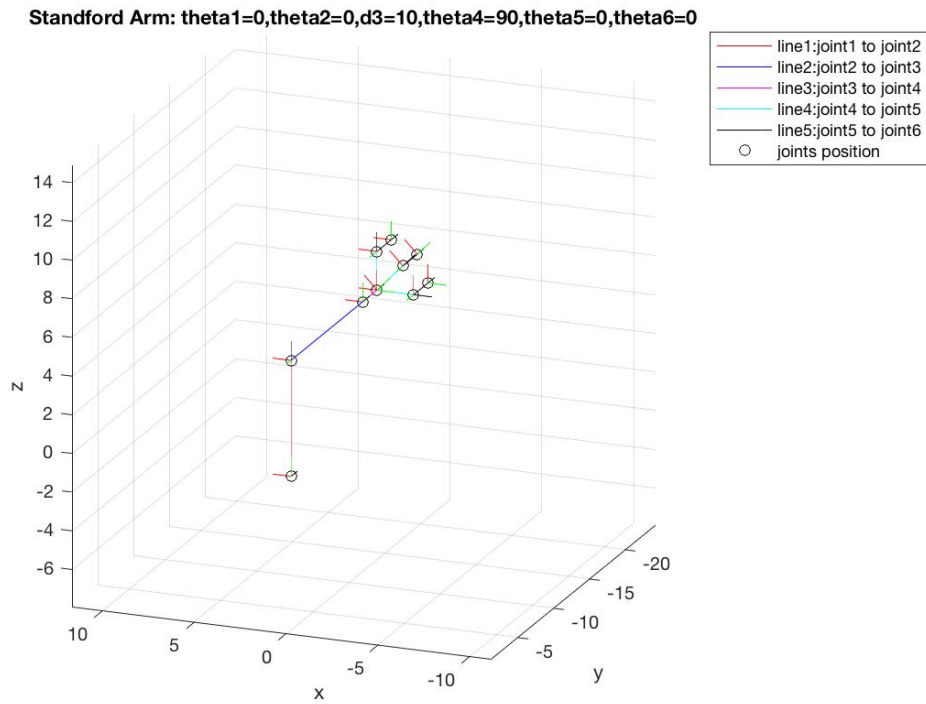


Rotate $\theta_2 = 0 \rightarrow 45 \rightarrow 90$

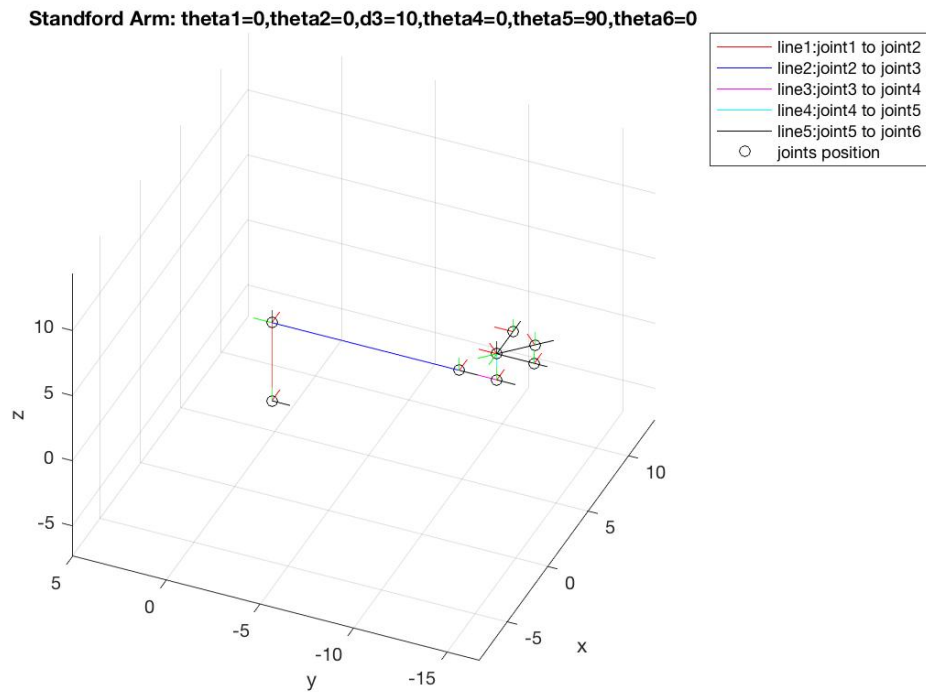
Stanford Arm: $\theta_1=0, \theta_2=90, d_3=10, \theta_4=0, \theta_5=0, \theta_6=0$



Rotate $\theta_4 = 0 \rightarrow 45 \rightarrow 90$



Rotate $\theta_5 = 0 \rightarrow 45 \rightarrow 90$



Rotate $\theta_6 = 0 \rightarrow 45 \rightarrow 90$

Stanford Arm: $\theta_1=0, \theta_2=0, d_3=10, \theta_4=0, \theta_5=0, \theta_6=90$

