

remote_center_manipulator.xacro

p4_rcm_instrument_holder
link10

needle_driver.xacro

needle_driver_house
link11

p4_rcm_instrument_holder_upper_bar_joint
..upper_bar ▶
instr..holder
axis=[0 -1 0]
mimick hand_pitch
multiplier: 1

p4_rcm_parallelagram_upper_bar
link9

p4_rcm_upper_bar_base_joint
par..base ▶
..upper_bar
axis=[0 1 0]
mimick hand_pitch
multiplier: -1

p4_rcm_parallelagram_base
link8

p4_rcm_pivot_plate
link7

p4_hand_pitch
pivot_pl.. ▶
par..base
axis=[0 -1 0]

p4_hand_roll
p4_rcm_base ▶
pivot_plate
axis=[1 0 0]

p4_instrument_slide
..holder ▶
..house
axis=[0 0 1]

p4_instrument_roll
needle_driver_house ▶
needle_driver_neck
axis=[0 0 1]

needle_driver_neck
link12

p4_instrument_pitch
needle_driver_neck ▶
needle_driver_head
axis=[-1 0 0]

needle_driver_neck
link12

z_0
 x_0
 y_0

p4_instrument_pitch

needle_driver_head
link13

p4_instrument_jaw_left
needle_driver_head ▶
..jawbone_left
axis=[0 0 -1]

p4_instrument_jaw_right
needle_driver_head ▶
..jawbone_right
axis=[0 0 1]

needle_driver_jawbone_left
link14L

needle_driver_jawbone_right
link14R

side view

front view