

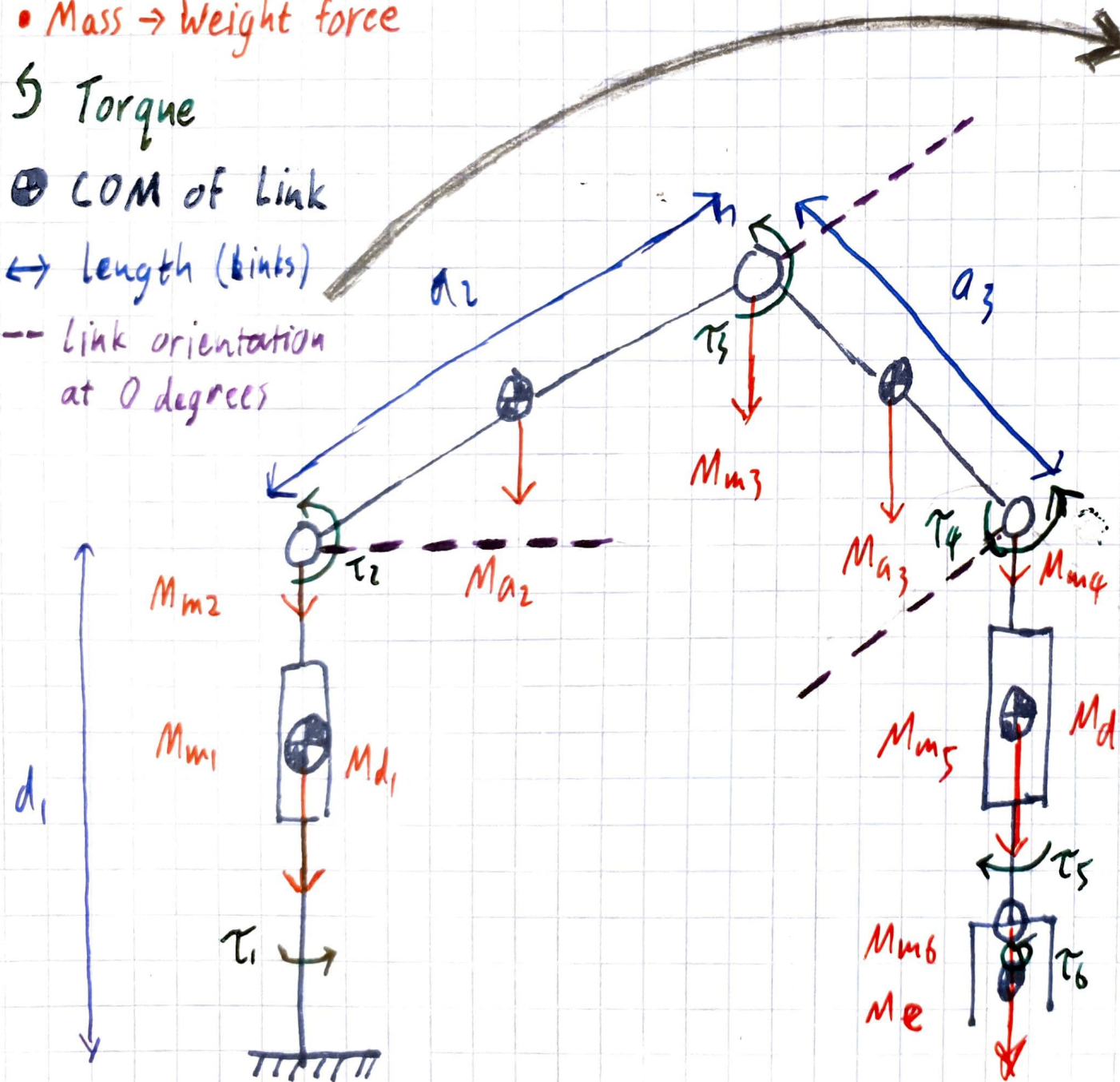
• Mass  $\rightarrow$  Weight force

$\hookrightarrow$  Torque

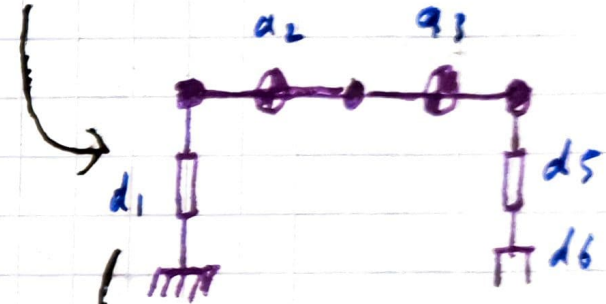
⊕ COM of Link

$\leftrightarrow$  length (links)

-- Link orientation at 0 degrees



Robot Arm Orientation with all angles at 0 deg



note the drawing of  $d_1$  is really exaggerated

$d_5$   
 $d_6$  (to COM)