

# Kinematics Input Data

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| Joint | Type      | a | alpha     | d   | theta |
|-------|-----------|---|-----------|-----|-------|
| 1     | revolute  | 0 | $-\pi/2.$ | 1   | q1    |
| 2     | revolute  | 0 | $\pi/2.$  | 1   | q2    |
| 3     | prismatic | 0 | 0         | d3  | 0     |
| 4     | revolute  | 0 | $-\pi/2.$ | 0.5 | q4    |
| 5     | revolute  | 0 | $\pi/2.$  | 0   | q5    |
| 6     | revolute  | 0 | 0         | 0.5 | q6    |