

## A Robotica Input data for 6-Link Arm

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DOF = 6

The Denavit-Hartenberg parameters:

```
joint1 = revolute
a1      = 0
alpha1  = -Pi/2
d1      = 1
theta1  = q1
joint2  = revolute
a2      = 0
alpha2  = Pi/2
d2      = 1
theta2  = q2
joint3  = prismatic
a3      = 0
alpha3  = 0
d3      = d3
theta3  = 0
joint4  = revolute
a4      = 0
alpha4  = -Pi/2
d4      = 1/2
theta4  = q4
joint5  = revolute
a5      = 0
alpha5  = Pi/2
d5      = 0
theta5  = q5
joint6  = revolute
a6      = 0
alpha6  = 0
d6      = 1/2
theta6  = q6
```