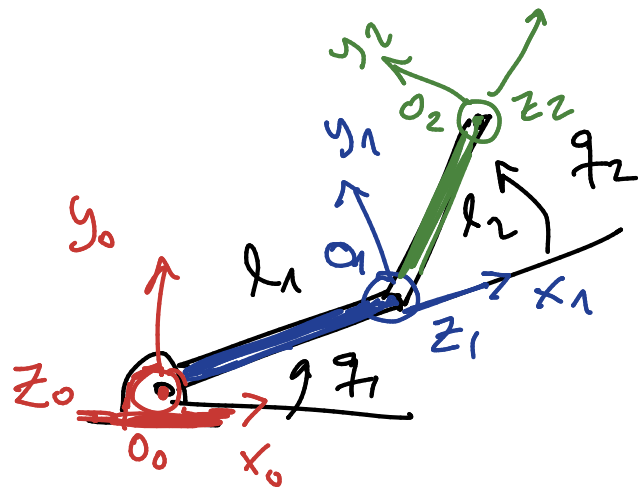


Example 3-1 - SHV Planar 2-link robot

DH convention



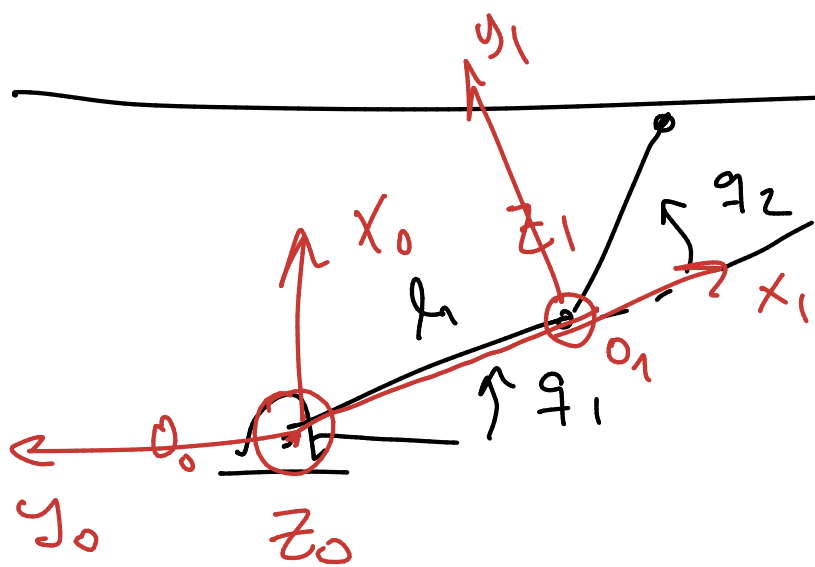
DH Table

Link	θ	d	a	α
1	q_1^*	0	l_1	0
2	q_2^*	0	l_2	0

0-1 : $\text{Rot}_{z, q_1} \text{Trans}_{x, l_1}$

1-2 : $\text{Rot}_{z, q_2} \text{Trans}_{x, l_2}$

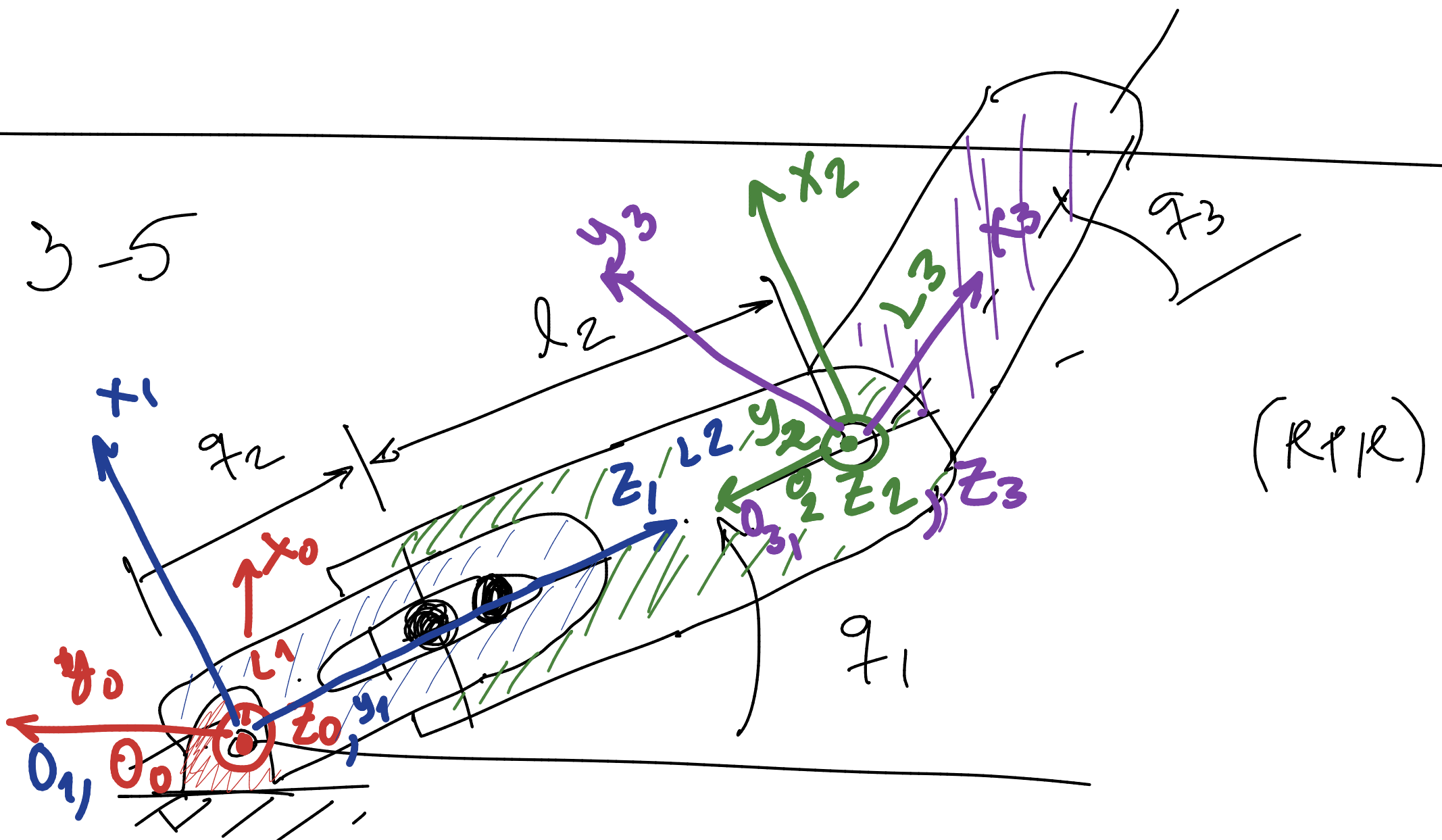
* : indicates the variable



0 → 1 : $\text{Rot}_{z, \frac{3\pi}{2} + q_1} \text{Trans}_{x, l_1}$

everything else the same.

Prob 3-5



(RPR)

0-1 : $\text{Rot}_{z, q_1} \text{Rot}_{x, \pi/2}$

1-2 : $\text{Trans}_{z, q_2 + l_2} \text{Rot}_{x, -\pi/2}$

2-3 : $\text{Rot}_{z, -\pi/2 + q_3}$