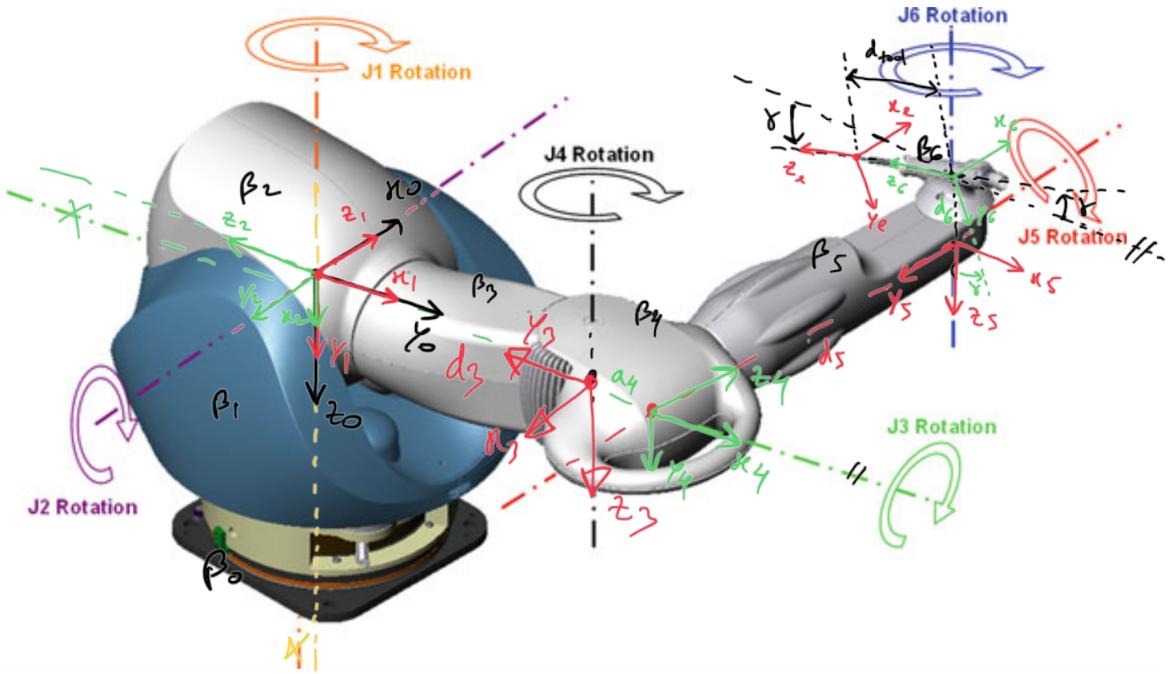


Spherical Shoulder



Link	d	r	a	α	Ref.
1	0	r_1	0	$\frac{\pi}{2}$	$\frac{\pi}{2}$
2	0	r_2	0	$-\frac{\pi}{2}$	$\frac{\pi}{2}$
3	$-d_3$	r_3	0	$\frac{\pi}{2}$	$\frac{\pi}{2}$
4	0	r_4	a_4	$\frac{\pi}{2}$	$-\frac{\pi}{2}$
5	d_5	r_5	0	$-\frac{\pi}{2}$	0
6	$-d_6$	r_6	0	$\frac{\pi}{2} - \gamma$	$-\frac{\pi}{2}$
e	d_{tool}	0	0	0	0

Following the DH Convention,
 } the reference frame of
 body 6 does not have
 its origin at the tool
 tip. Therefore, it is
 necessary to add reference
 frame e to body 6.