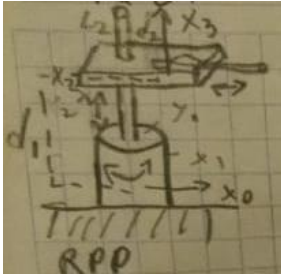
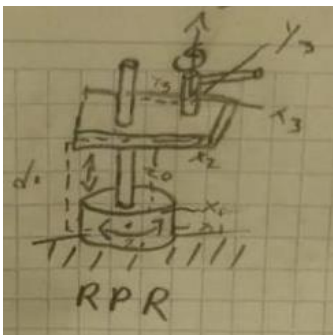


TAREA.4

Curiel Sánchez Héctor David
CINEMATICA DE ROBOTS



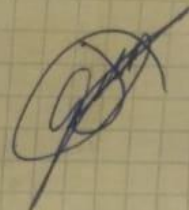
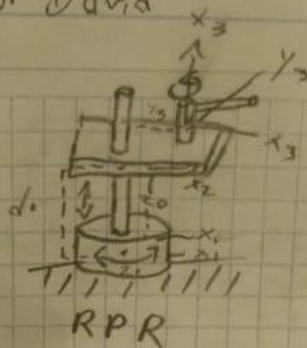
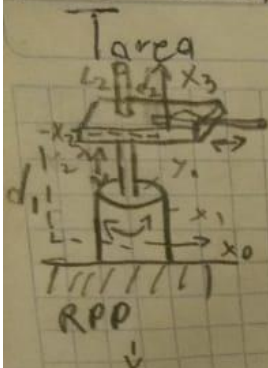
i	A_{i-1}	α_{i-1}	d_i	θ_i
1	0	0	D1	θ_1
2	0	-90°	D2	θ_2
3	L1	0	0	θ_3



i	A_{i-1}	α_{i-1}	d_i	θ_i
1	0	0	D1	θ_1
2	0	90°	D2	θ_2
3	L1	-90°	0	θ_3

Curiel Sanchez Hector David

12/02/2019



i	a_{i-1}	α_{i-1}	d_i	θ_i	i	a_{i-1}	α_{i-1}	d_i	θ_i
1	0	0	d_1	θ_1	1	0	0	d_1	θ_1
2	0	90°	d_2	θ_2	2	0	90°	d_2	θ_2
3	L_1	0	0	θ_3	3	L_1	-90°	0	θ_3