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Cinematica de robots  8 de marzo del 2019 8°B T/M

mtrices proyecto

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
|  |  |  |  |  |
| 1 | 0 | 0 | 0 |  |
| 2 | L1 | -90 | 0 |  |
| 3 | L2 | -90 | 0 |  |
| 4 | L3 | 0 | 0 |  |

= [cos(theta1) –sen(theta1) 0 0, sen(theta1) cos(theta1) 0 0, 0 0 1 0, 0 0 0 1]

= [cos(theta2) –sen(theta2) 0 L2, 0 0 1 0, -sen(theta2) –cos(theta2) 0 0, 0 0 0 1]

= [1 0 0 L2, 0 0 1 0, 0 -1 0 0, 0 0 0 1] 𝑇4 3 = [1 0 0 L3, 0 1 0 0, 0 0 1 0, 0 0 0 1]

= [(cos(theta1)(cos(theta2)) -(cos(theta1))(sin(theta2)) 0 L1+L2+L3,(cos(theta1))((sen(theta)) (sen(theta1))(sen(theta1)) 0 0, 0 0 -1 0, 0 0 0 1]

