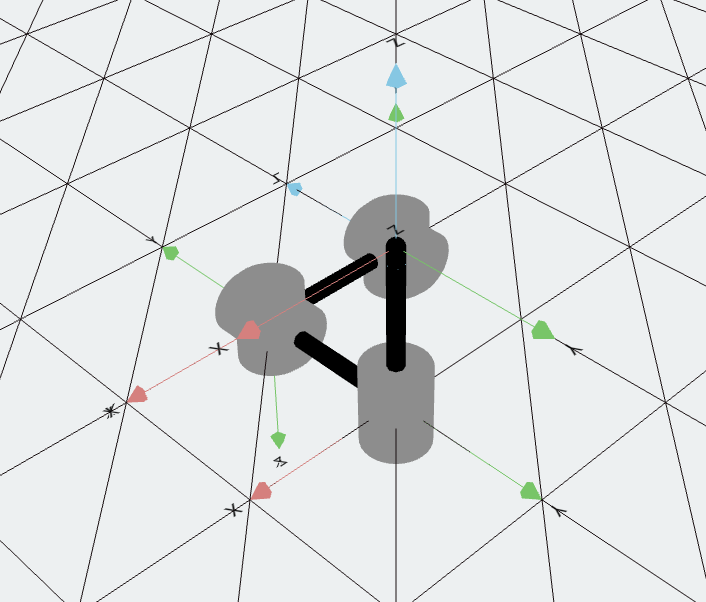
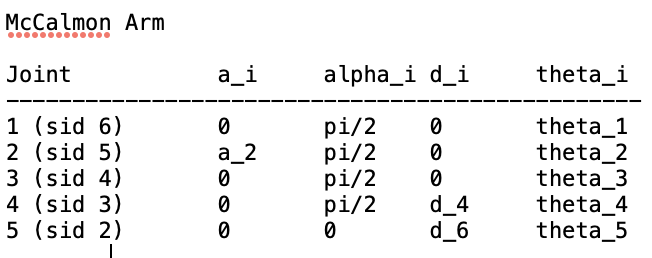
**DH Parameter Table (resting arm position is outstretched vertically) -** [**demo**](https://mathcs.holycross.edu/~kwalsh/dh.html?dh=%5B%7B%22theta_offset%22%3A0%2C%22alpha%22%3A90%2C%22a%22%3A0%2C%22d%22%3A2%2C%22min%22%3A-180%2C%22max%22%3A180%7D%2C%7B%22theta_offset%22%3A90%2C%22alpha%22%3A0%2C%22a%22%3A2%2C%22d%22%3A0%2C%22min%22%3A-90%2C%22max%22%3A90%7D%2C%7B%22theta_offset%22%3A0%2C%22alpha%22%3A0%2C%22a%22%3A2%2C%22d%22%3A0%2C%22min%22%3A-90%2C%22max%22%3A90%7D%2C%7B%22theta_offset%22%3A90%2C%22alpha%22%3A90%2C%22a%22%3A0%2C%22d%22%3A0%2C%22min%22%3A-90%2C%22max%22%3A90%7D%2C%7B%22theta_offset%22%3A0%2C%22alpha%22%3A0%2C%22a%22%3A0%2C%22d%22%3A2%2C%22min%22%3A-90%2C%22max%22%3A90%7D%5D)

|  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- |
|  | **name** | **motion** | **𝜃** | **𝛼** | **a** | **d** | **comments** |
| Joint 1 (servo id=6) | base | rotate | 𝜃1 | 90° | 0 | d1 | d1 is baseplate to shoulder distance |
| Joint 2 (servo id=5) | shoulder | bend | 90°+𝜃2 | 0 | a2 | 0 | a2 is shoulder to elbow distance |
| Joint 3 (servo id=4) | elbow | bend | 𝜃3 | 0 | a3 | 0 | a3 is elbow to wrist distance |
| Joint 4 (servo id=3) | wrist | bend | 90°+𝜃4 | 90° | 0 | 0 |  |
| Joint 5 (servo id=2) | hand | rotate | 𝜃5 | 0 | 0 | d5 | d5 is wrist to end-effector distance |
| Joint 6 (servo id=1) | grip | grasp | N/A | N/A | N/A | N/A |  |

**DH Parameter Table (resting arm position is outstretched rightward) -** [**demo**](https://mathcs.holycross.edu/~kwalsh/dh.html?dh=%5B%7B%22theta_offset%22%3A0%2C%22alpha%22%3A90%2C%22a%22%3A0%2C%22d%22%3A2%2C%22min%22%3A-180%2C%22max%22%3A180%7D%2C%7B%22theta_offset%22%3A0%2C%22alpha%22%3A0%2C%22a%22%3A2%2C%22d%22%3A0%2C%22min%22%3A0%2C%22max%22%3A180%7D%2C%7B%22theta_offset%22%3A0%2C%22alpha%22%3A0%2C%22a%22%3A2%2C%22d%22%3A0%2C%22min%22%3A-90%2C%22max%22%3A90%7D%2C%7B%22theta_offset%22%3A90%2C%22alpha%22%3A90%2C%22a%22%3A0%2C%22d%22%3A0%2C%22min%22%3A-90%2C%22max%22%3A90%7D%2C%7B%22theta_offset%22%3A0%2C%22alpha%22%3A0%2C%22a%22%3A0%2C%22d%22%3A2%2C%22min%22%3A-90%2C%22max%22%3A90%7D%5D)

|  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- |
|  | **name** | **motion** | **𝜃** | **𝛼** | **a** | **d** | **comments** |
| Joint 1 (servo id=6) | base | rotate | 𝜃1 | 90° | 0 | d1 | d1 is baseplate to shoulder distance |
| Joint 2 (servo id=5) | shoulder | bend | 𝜃2 | 0 | a2 | 0 | a2 is shoulder to elbow distance |
| Joint 3 (servo id=4) | elbow | bend | 𝜃3 | 0 | a3 | 0 | a3 is elbow to wrist distance |
| Joint 4 (servo id=3) | wrist | bend | 90°+𝜃4 | 90° | 0 | 0 |  |
| Joint 5 (servo id=2) | hand | rotate | 𝜃5 | 0 | 0 | d5 | d5 is wrist to end-effector distance |
| Joint 6 (servo id=1) | grip | grasp | N/A | N/A | N/A | N/A |  |

**McCalmon Arm -** [**demo**](https://mathcs.holycross.edu/~kwalsh/dh.html?dh=%5B%7B%22theta_offset%22%3A0%2C%22alpha%22%3A90%2C%22a%22%3A0%2C%22d%22%3A0%2C%22min%22%3A-180%2C%22max%22%3A180%7D%2C%7B%22theta_offset%22%3A0%2C%22alpha%22%3A90%2C%22a%22%3A2%2C%22d%22%3A0%2C%22min%22%3A-90%2C%22max%22%3A90%7D%2C%7B%22theta_offset%22%3A0%2C%22alpha%22%3A90%2C%22a%22%3A0%2C%22d%22%3A0%2C%22min%22%3A0%2C%22max%22%3A180%7D%2C%7B%22theta_offset%22%3A0%2C%22alpha%22%3A90%2C%22a%22%3A0%2C%22d%22%3A2%2C%22min%22%3A-90%2C%22max%22%3A90%7D%2C%7B%22theta_offset%22%3A0%2C%22alpha%22%3A0%2C%22a%22%3A0%2C%22d%22%3A2%2C%22min%22%3A-90%2C%22max%22%3A90%7D%5D)

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