



PARAMETROS DH

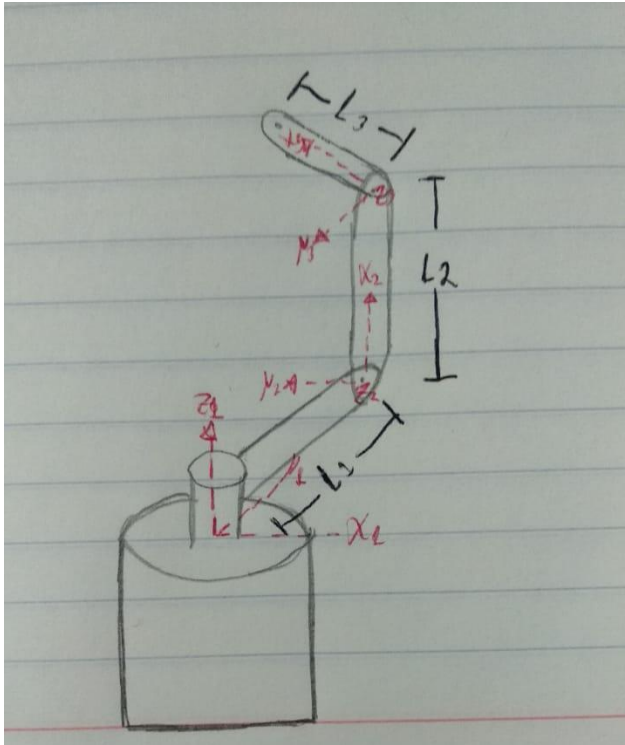
Jose Navarro Cervantes

8°B T/M

Ing. Mecatrónica

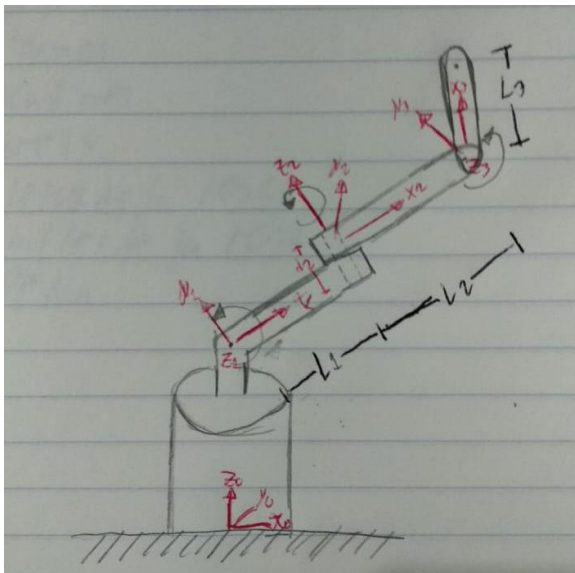
Cinemática de robots

Robot #2



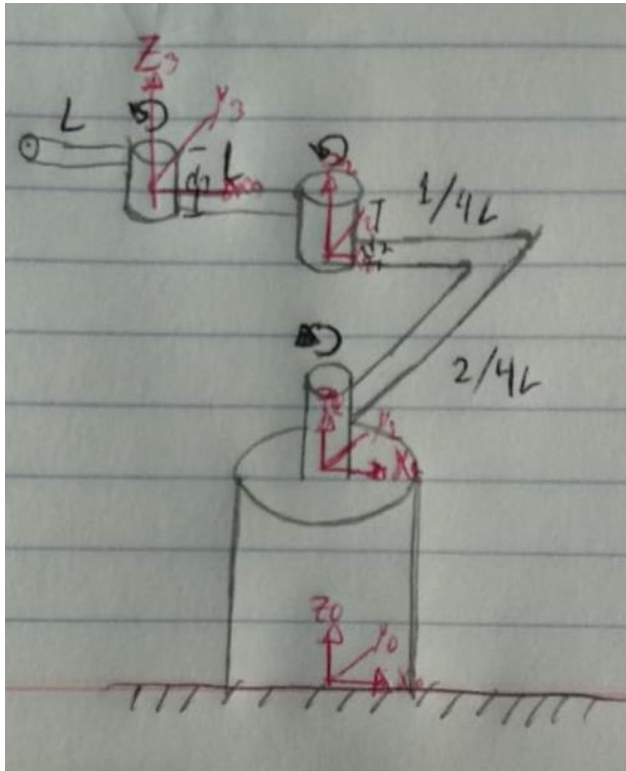
i	a_{i-1}	α_{i-1}	d_i	θ_i
1	0	-90	0	θ_1
2	L_1	0	0	θ_2
3	L_2	0	0	θ_3

Robot #3



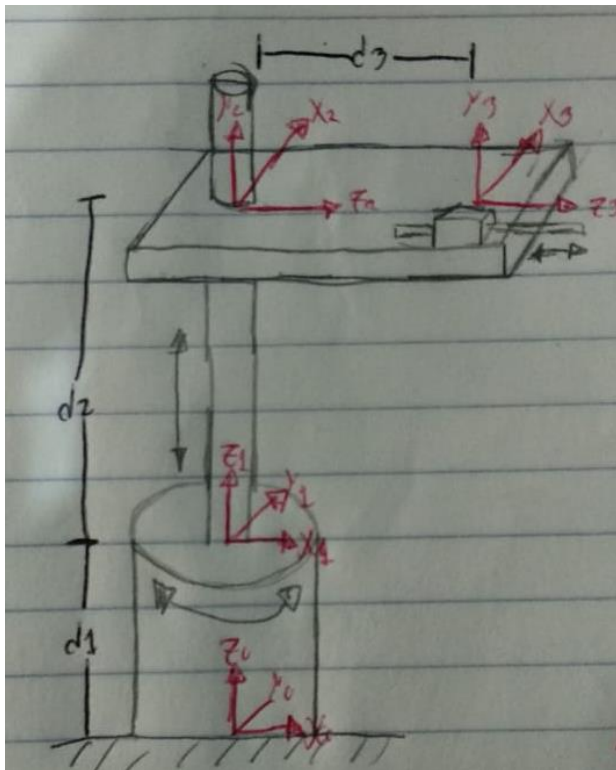
i	a_{i-1}	α_{i-1}	d_i	θ_i
1	0	-90	0	θ_1
2	L_1	90	d_1	θ_2
3	L_2	-90	d_2	θ_3

Robot #4



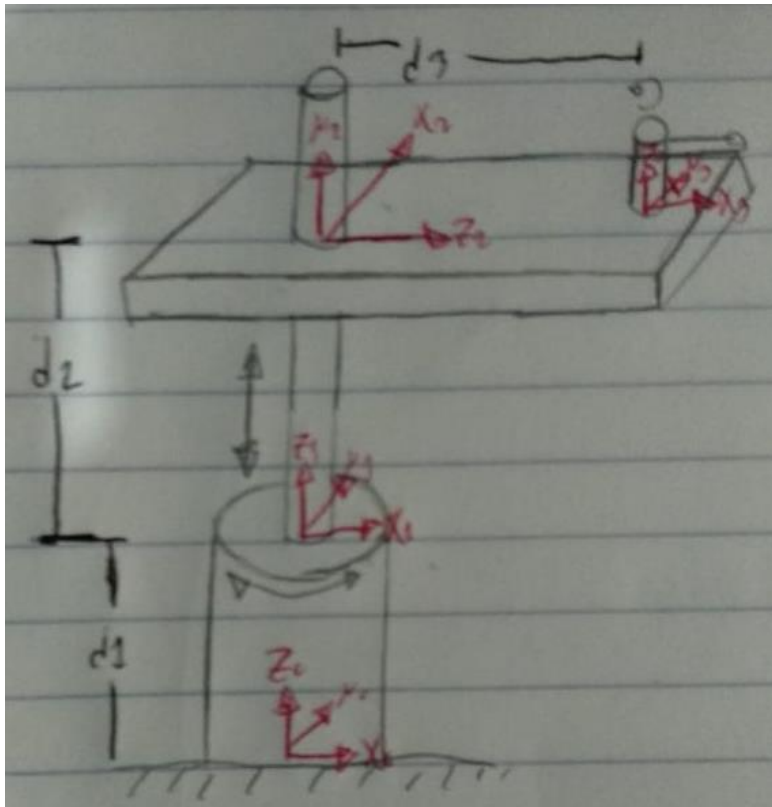
i	a_{i-1}	α_{i-1}	d_i	θ_i
1	0	0	d_1	θ_1
2	0	90	d_2	90
3	0	0	d_3	0

Robot #5



i	a_{i-1}	α_{i-1}	d_i	θ_i
1	0	0	d_1	θ_1
2	0	90	d_2	90
3	0	0	d_3	0

Robot #6

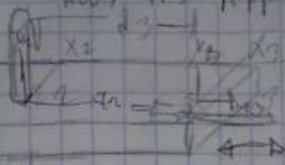


i	a_{i-1}	α_{i-1}	d_i	θ_i
1	0	0	d_1	θ_1
2	0	90	d_2	90
3	0	-90	d_3	θ_3

Tarea

ro Corvantes Jose

Robot #5 RPP



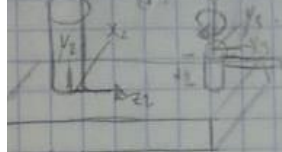
FECHA

12/2/2019

i	a_{i-1}	α_{i-1}	d_i	θ_i
1	0	0	d_1	θ_1
2	0	90	d_2	90
3	0	0	d_3	0



Robot #6 RPP



i	a_{i-1}	α_{i-1}	d_i	θ_i
1	0	0	d_1	θ_1
2	0	90	d_2	90
3	0	90	d_3	θ_2