



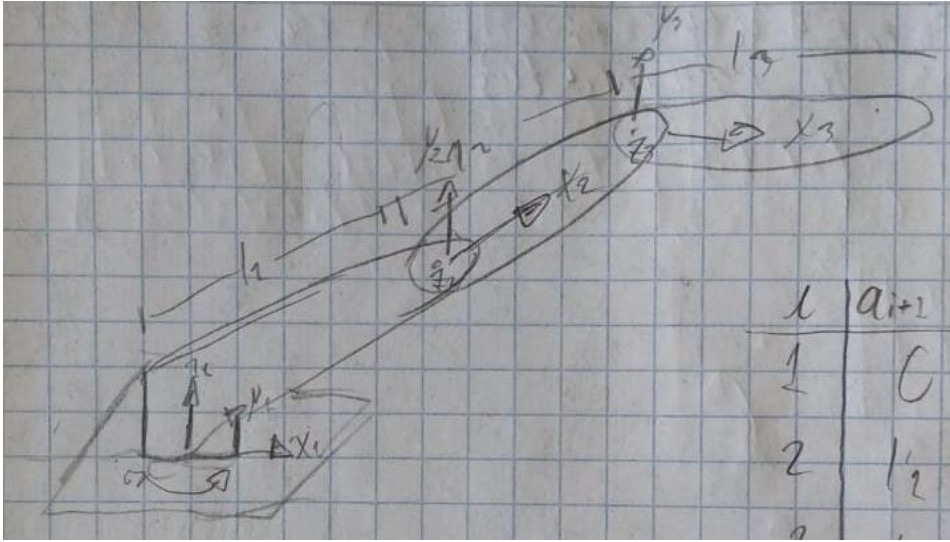
# PRACTICA 1

Jose Navarro Cervantes

Ing. Mecatrónica

8°B T/M

Cinemática de robots



i	$a_{i-1}$	$\alpha_{i-1}$	$d_i$	$\theta_i$
1	0	-90	0	$\theta_1$
2	$L_1$	0	0	$\theta_2$
3	$L_2$	0	0	$\theta_3$

$$T_i^{i-1} = \begin{bmatrix} C\theta_i & -S\theta_i & 0 & a_{i-1} \\ S\theta_i C\alpha_{i-1} & C\theta_i C\alpha_{i-1} & -S_{i-1} & -d_i S\alpha_{i-1} \\ S\theta_i S\alpha_{i-1} & C\theta_i S\alpha_{i-1} & C_{i-1} & d_i S\alpha_{i-1} \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$T_1^0 = \begin{bmatrix} C\theta_1 & -S\theta_1 & 0 & 0 \\ S\theta_1 & C\theta_1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$T_2^1 = \begin{bmatrix} C\theta_1 & -S\theta_1 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ -S\theta_2 & -C\theta_2 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$T_3^2 = \begin{bmatrix} C\theta_3 & -S\theta_3 & 0 & 0 \\ S\theta_3 & C\theta_3 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$