



# PARAMETROS DH

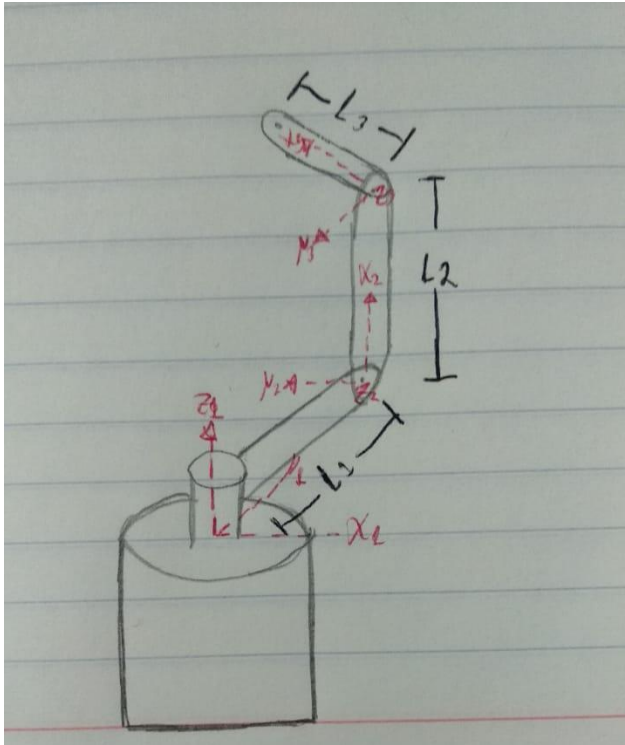
Jose Navarro Cervantes

8°B T/M

Ing. Mecatrónica

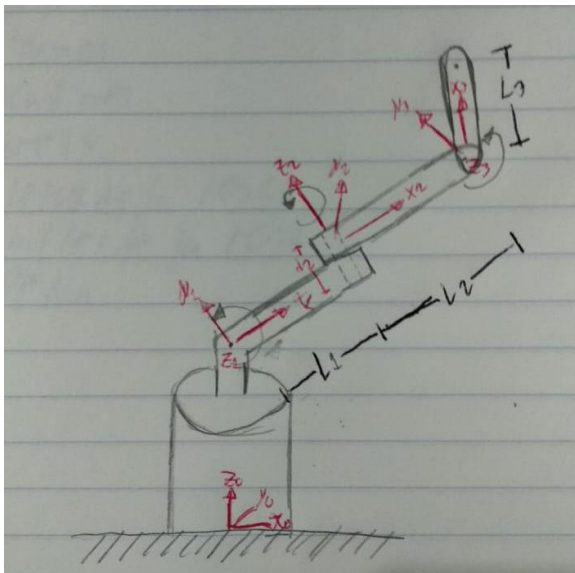
Cinemática de robots

Robot #2



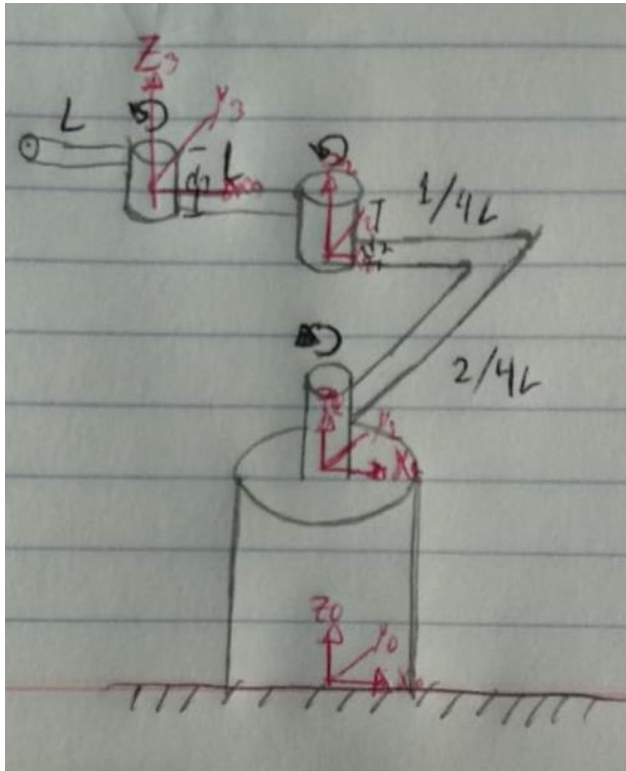
i	$a_{i-1}$	$\alpha_{i-1}$	$d_i$	$\theta_i$
1	0	-90	0	$\theta_1$
2	L1	0	0	$\theta_2$
3	L2	0	0	$\theta_3$

Robot #3



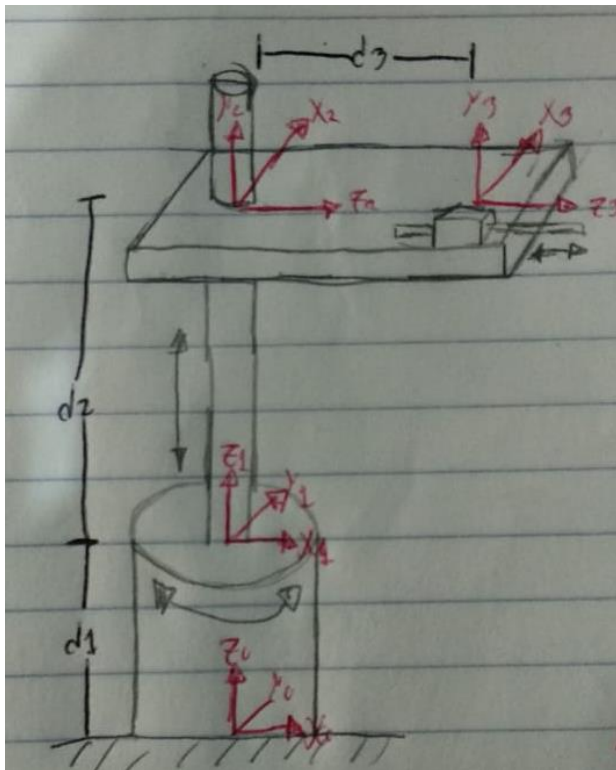
i	$a_{i-1}$	$\alpha_{i-1}$	$d_i$	$\theta_i$
1	0	-90	0	$\theta_1$
2	L1	90	d1	$\theta_2$
3	L2	-90	d2	$\theta_3$

Robot #4



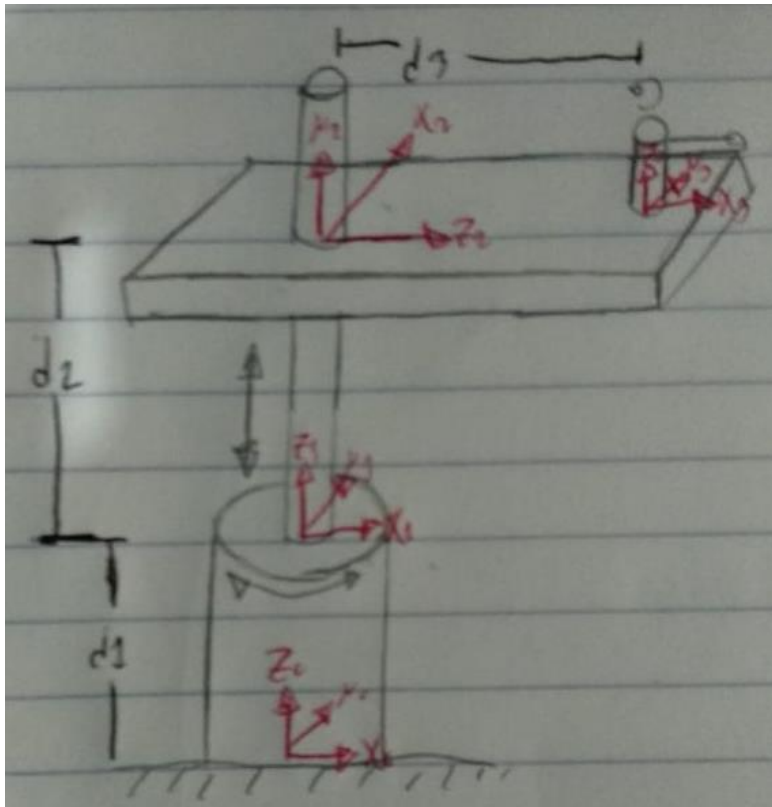
i	$a_{i-1}$	$\alpha_{i-1}$	$d_i$	$\theta_i$
1	0	0	$d_1$	$\theta_1$
2	0	90	$d_2$	90
3	0	0	$d_3$	0

Robot #5



i	$a_{i-1}$	$\alpha_{i-1}$	$d_i$	$\theta_i$
1	0	0	$d_1$	$\theta_1$
2	0	90	$d_2$	90
3	0	0	$d_3$	0

Robot #6



i	$a_{i-1}$	$\alpha_{i-1}$	$d_i$	$\theta_i$
1	0	0	$d_1$	$\theta_1$
2	0	90	$d_2$	90
3	0	-90	$d_3$	$\theta_3$