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Cinemática de robots

Parámetros DH

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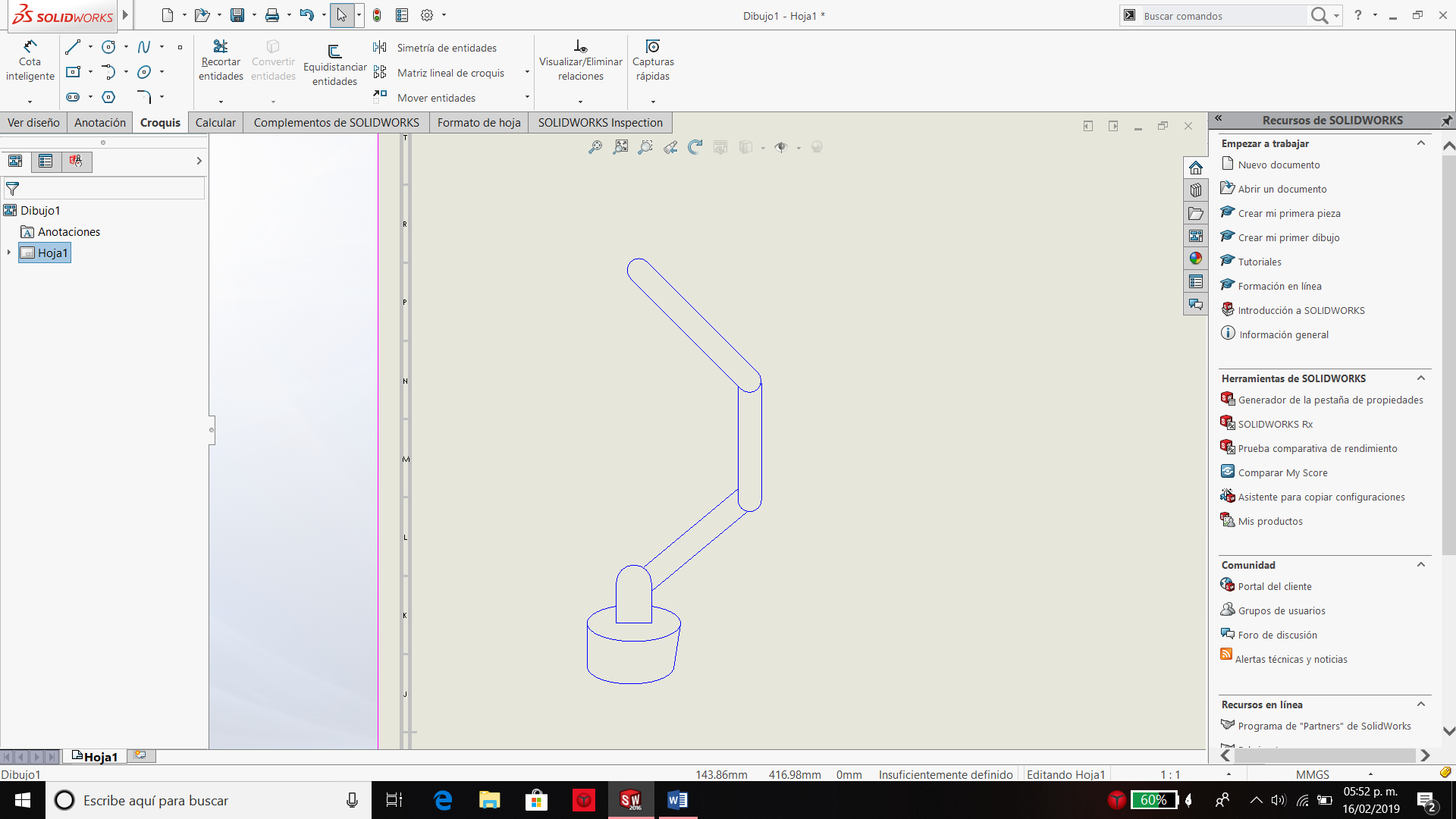
Prof.: Moran Garabito Carlos Enrique

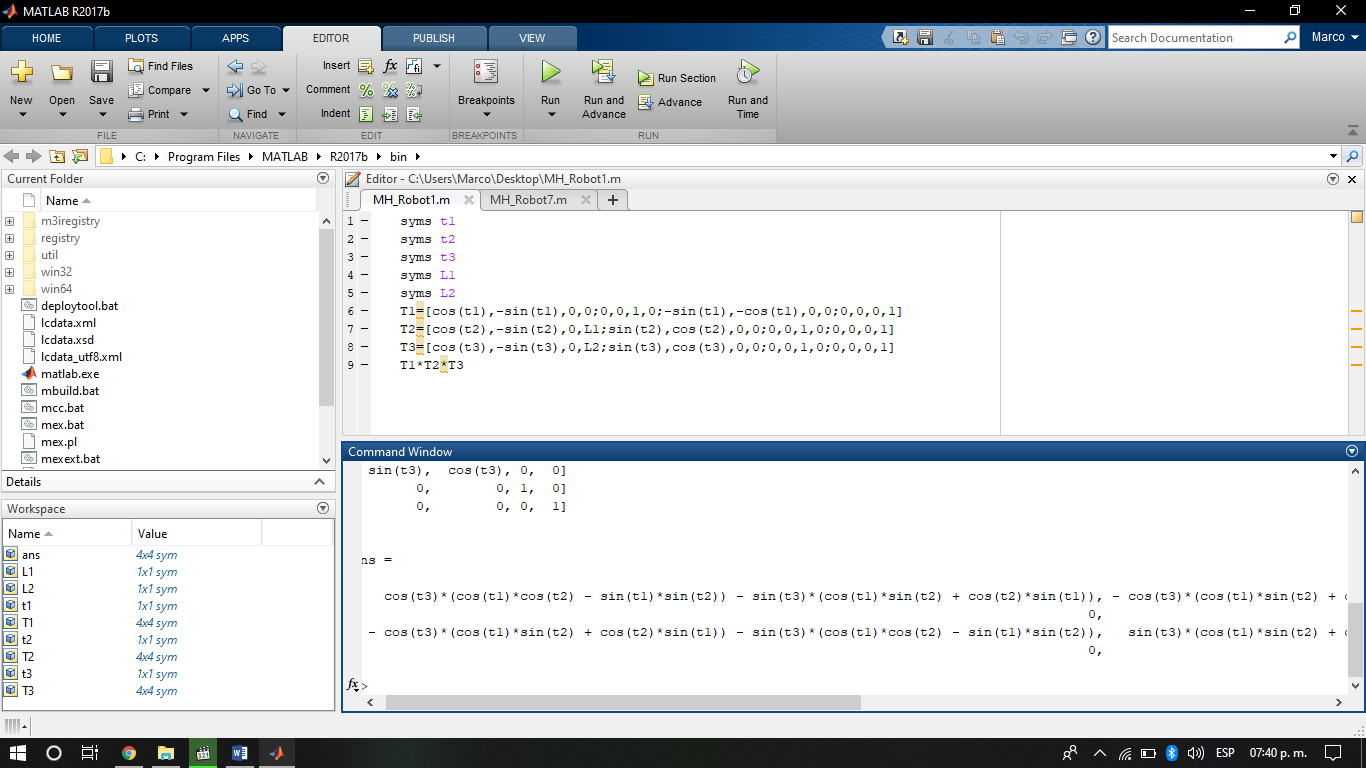
**Parámetros DH**

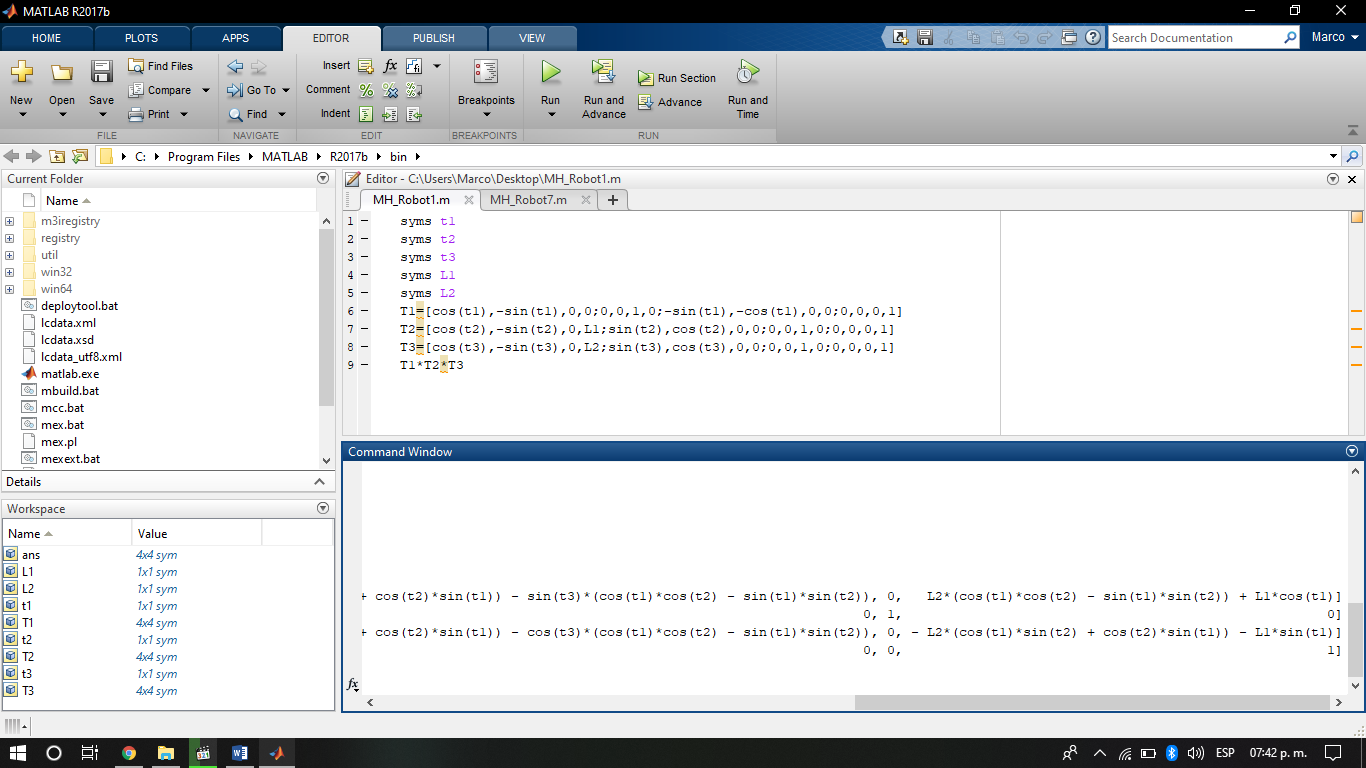
**Calculo de matrices homogéneas**

**Robot # 1.**

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| **i** | **ai-1** | **Ζi-1** | **di** | **θi** |
| **1** | **0** | **-90** | **0** | **Θ1** |
| **2** | **L1** | **0** | **0** | **Θ2** |
| **3** | **L2** | **0** | **0** | **Θ3** |

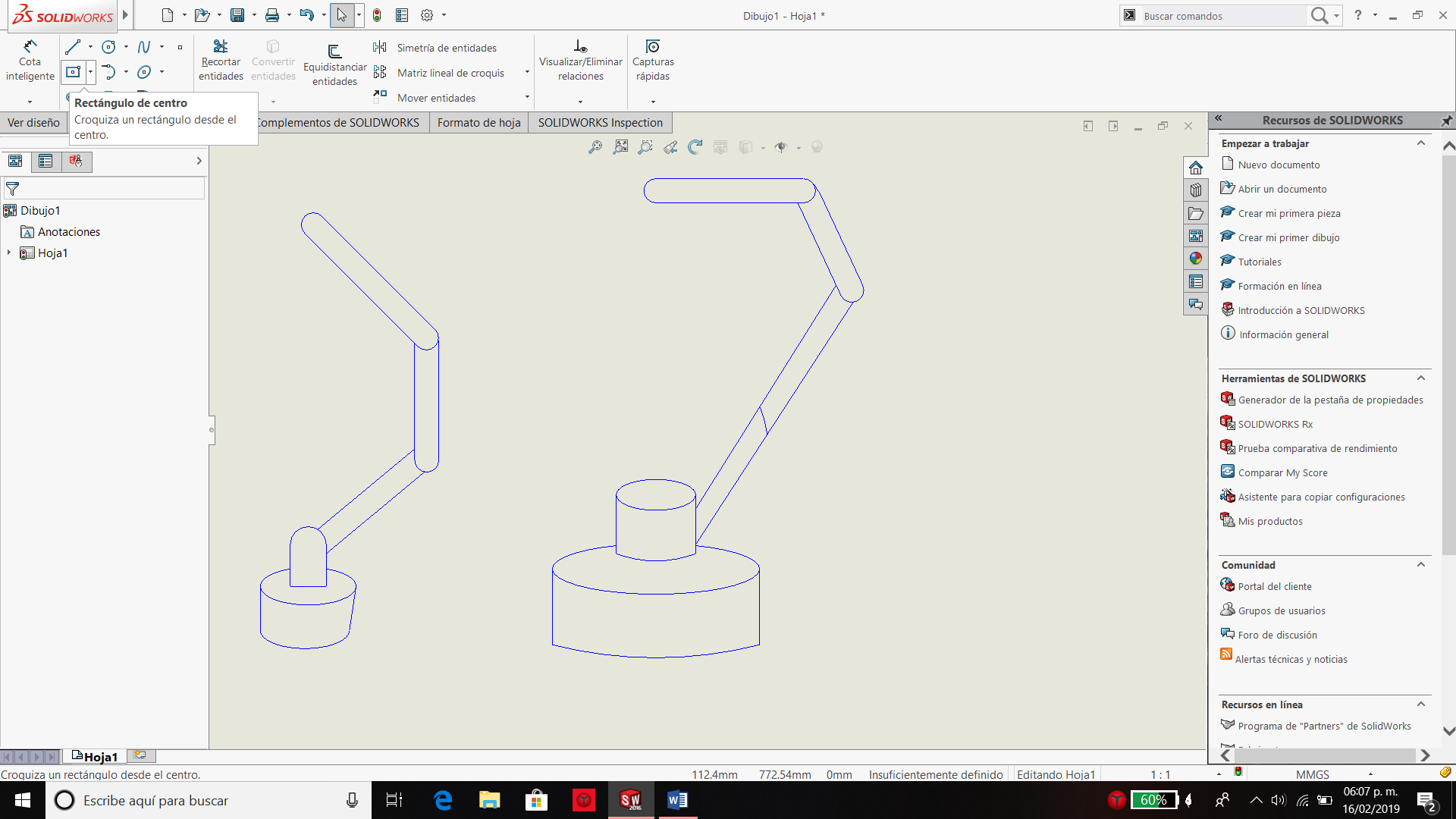


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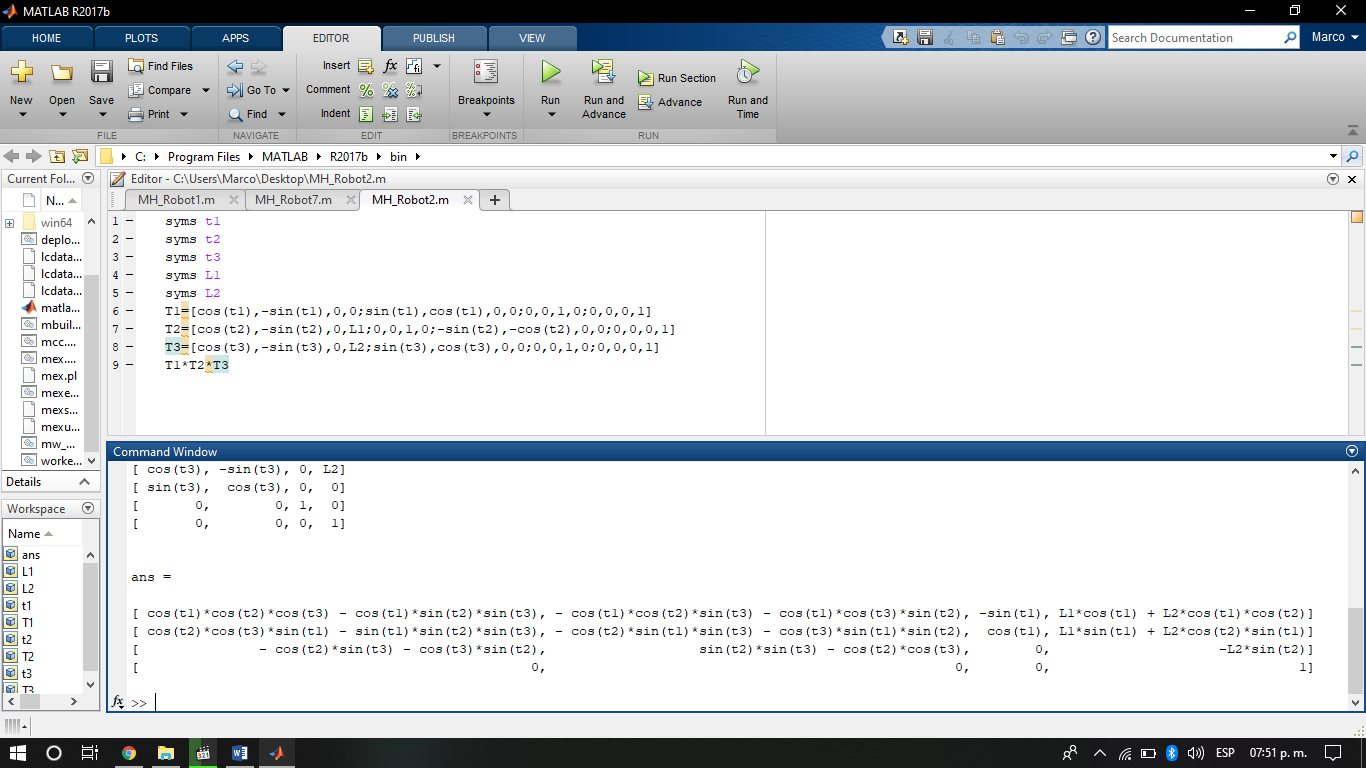
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**Robot 2**

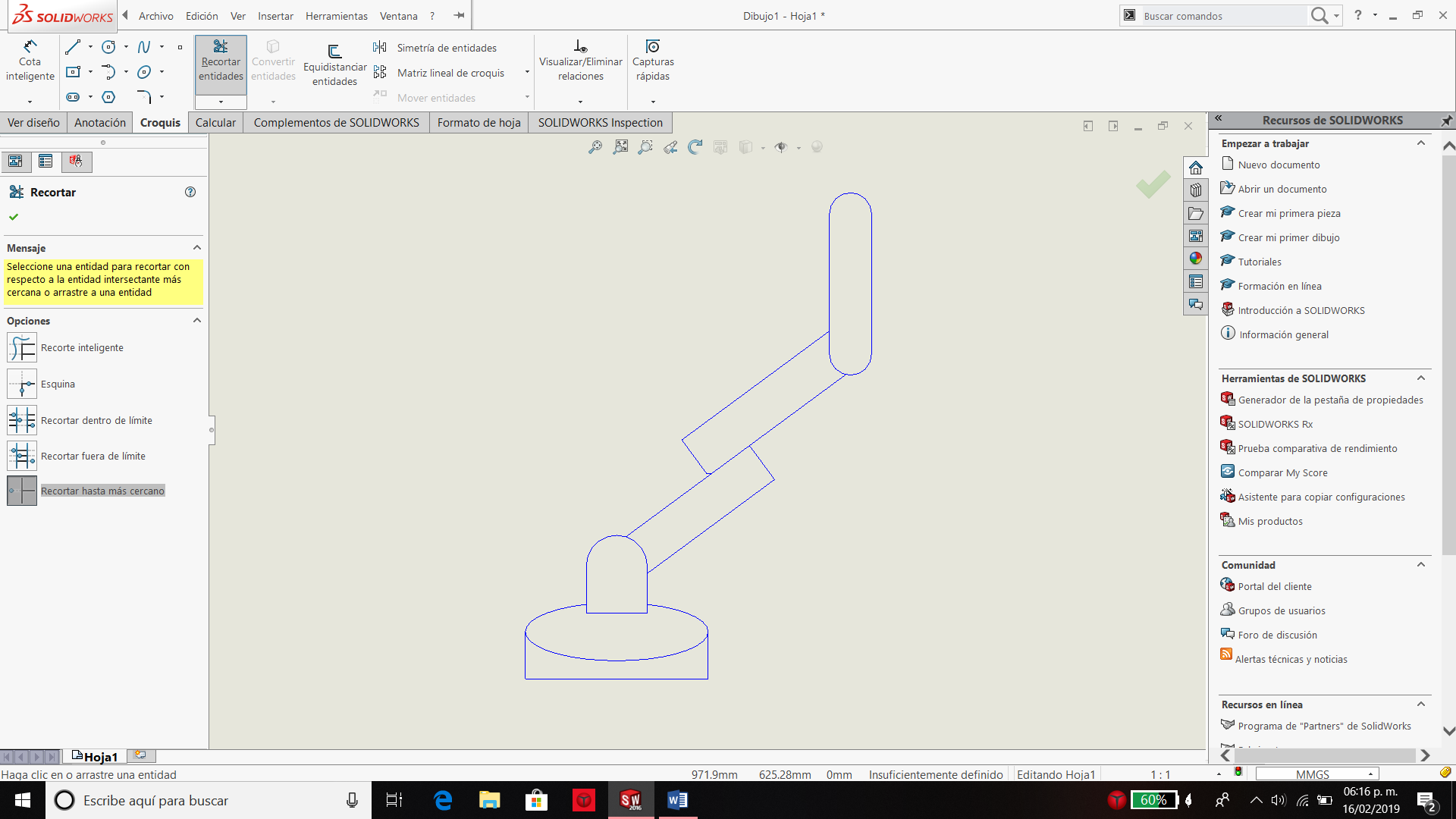
|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| **i** | **ai-1** | **Ζi-1** | **di** | **θi** |
| **1** | **0** | **0** | **0** | **Θ1** |
| **2** | **L1** | **-90** | **0** | **Θ2** |
| **3** | **L2** | **0** | **0** | **Θ3** |



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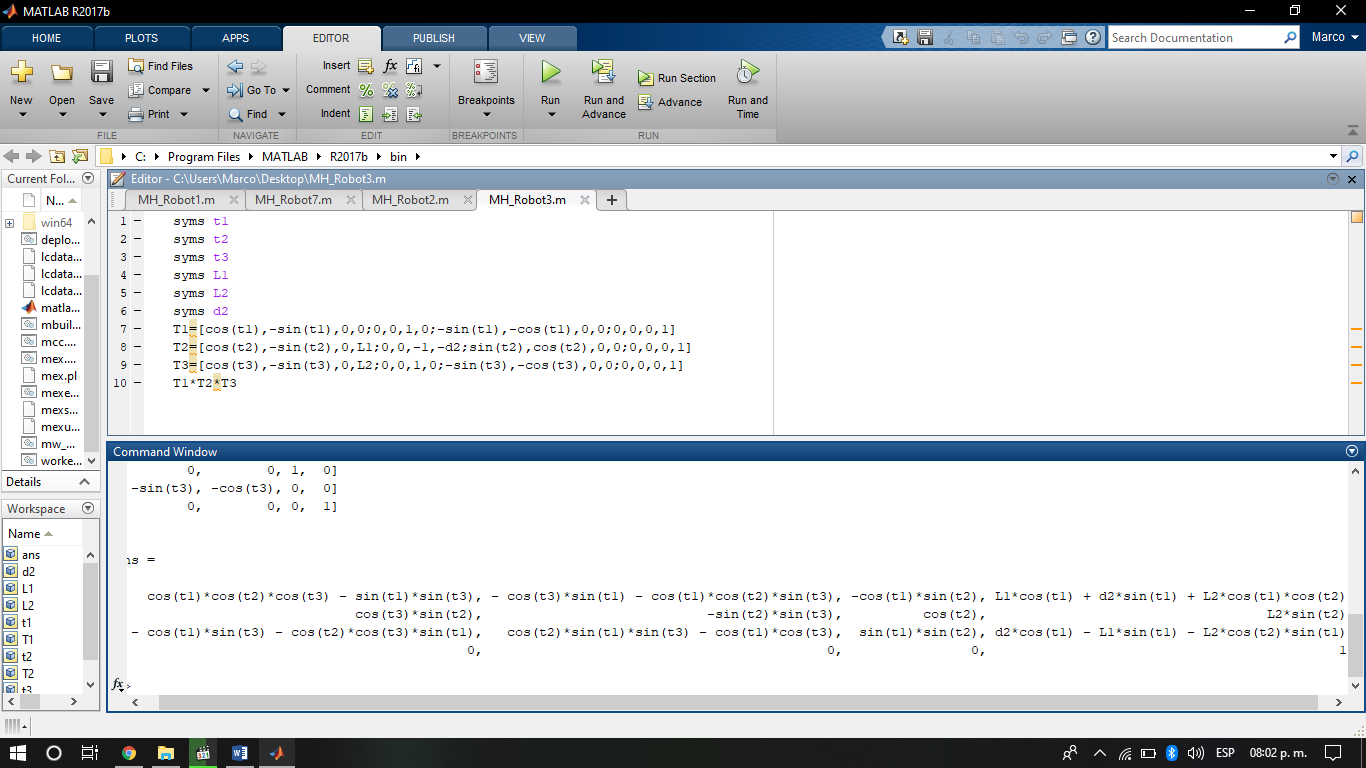
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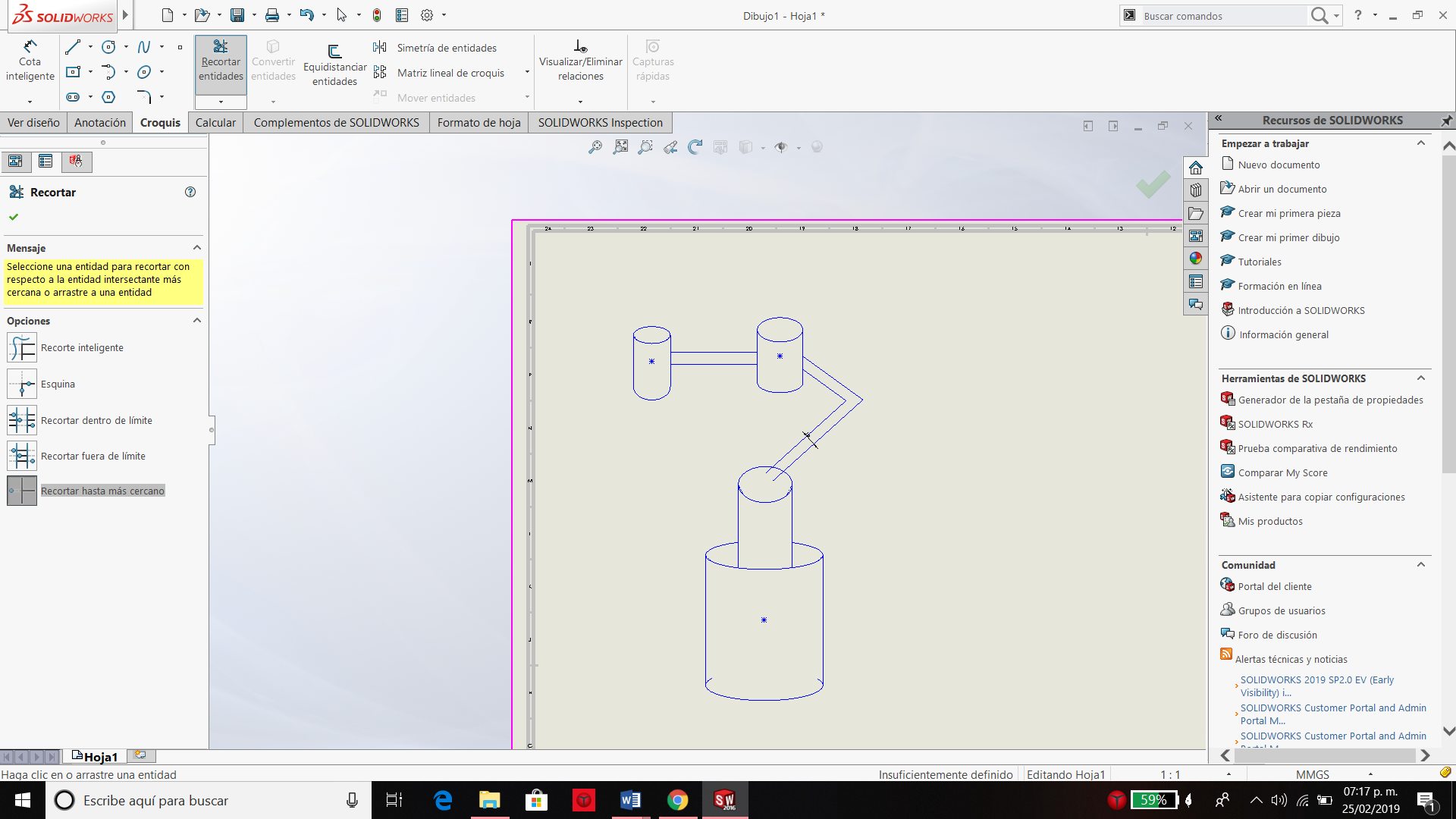
**Robot 3**



|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| **i** | **ai-1** | **Ζi-1** | **di** | **θi** |
| **1** | **0** | **-90** | **0** | **Θ1** |
| **2** | **L1** | **90** | **d2** | **Θ2** |
| **3** | **L2** | **-90** | **0** | **Θ3** |

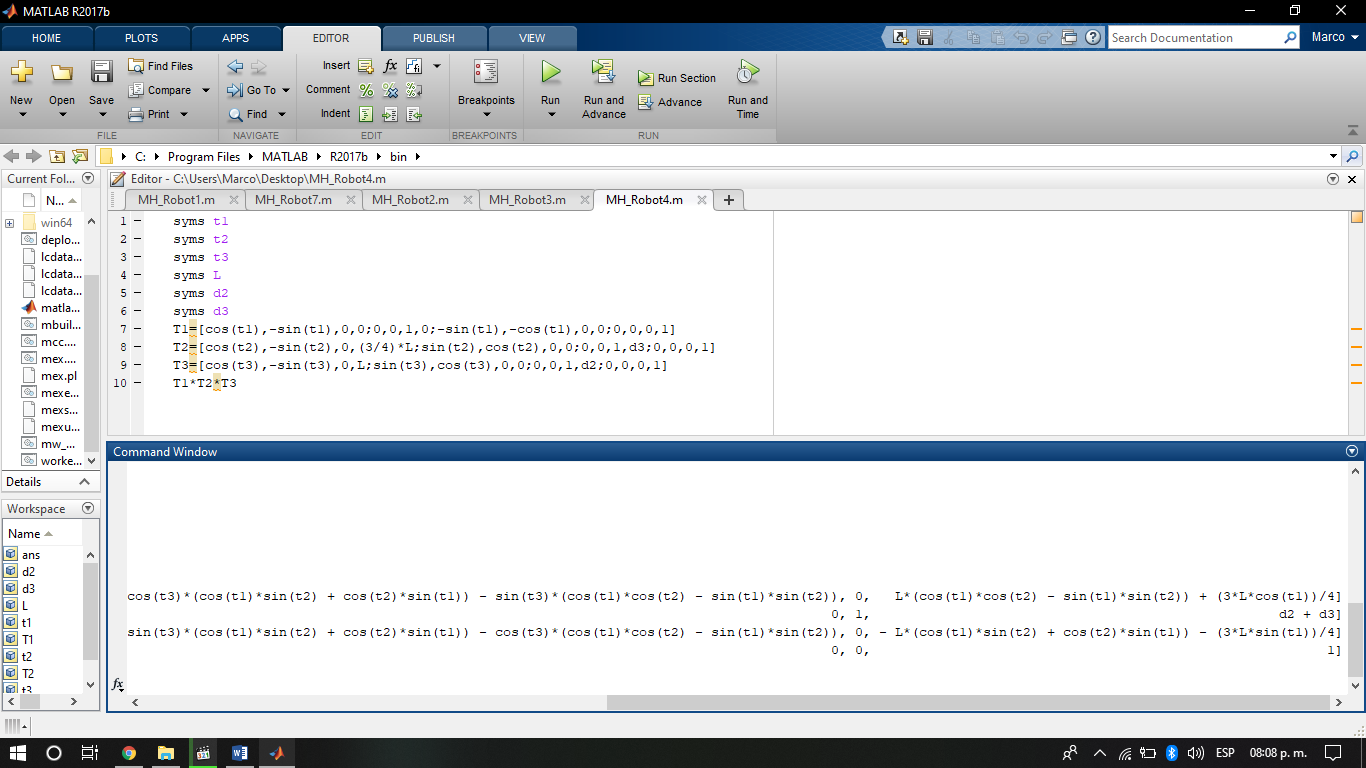
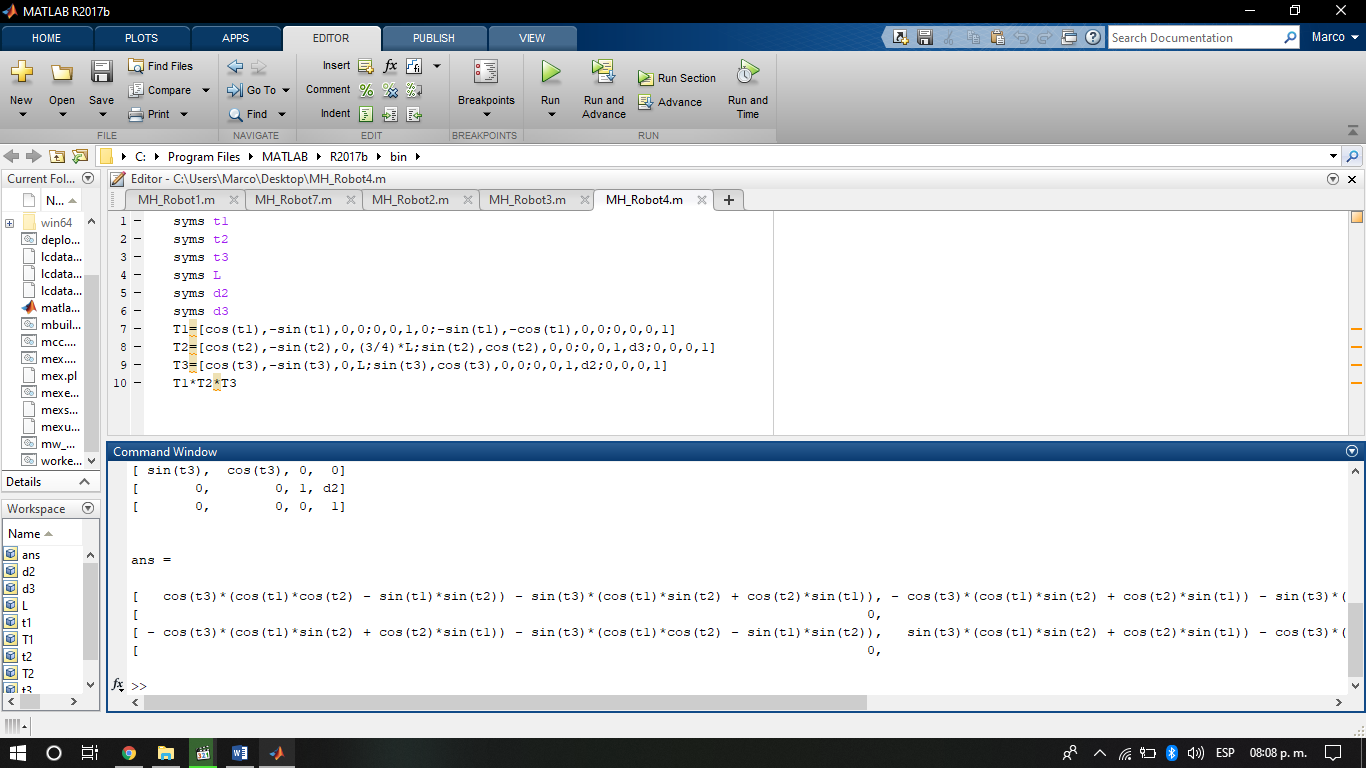
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**Robot 4**

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| **i** | **ai-1** | **Ζi-1** | **di** | **θi** |
| **1** | **0** | **0** | **0** | **Θ1** |
| **2** | **3/4L** | **0** | **0** | **0** |
| **3** | **L** | **0** | **d3** | **0** |

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