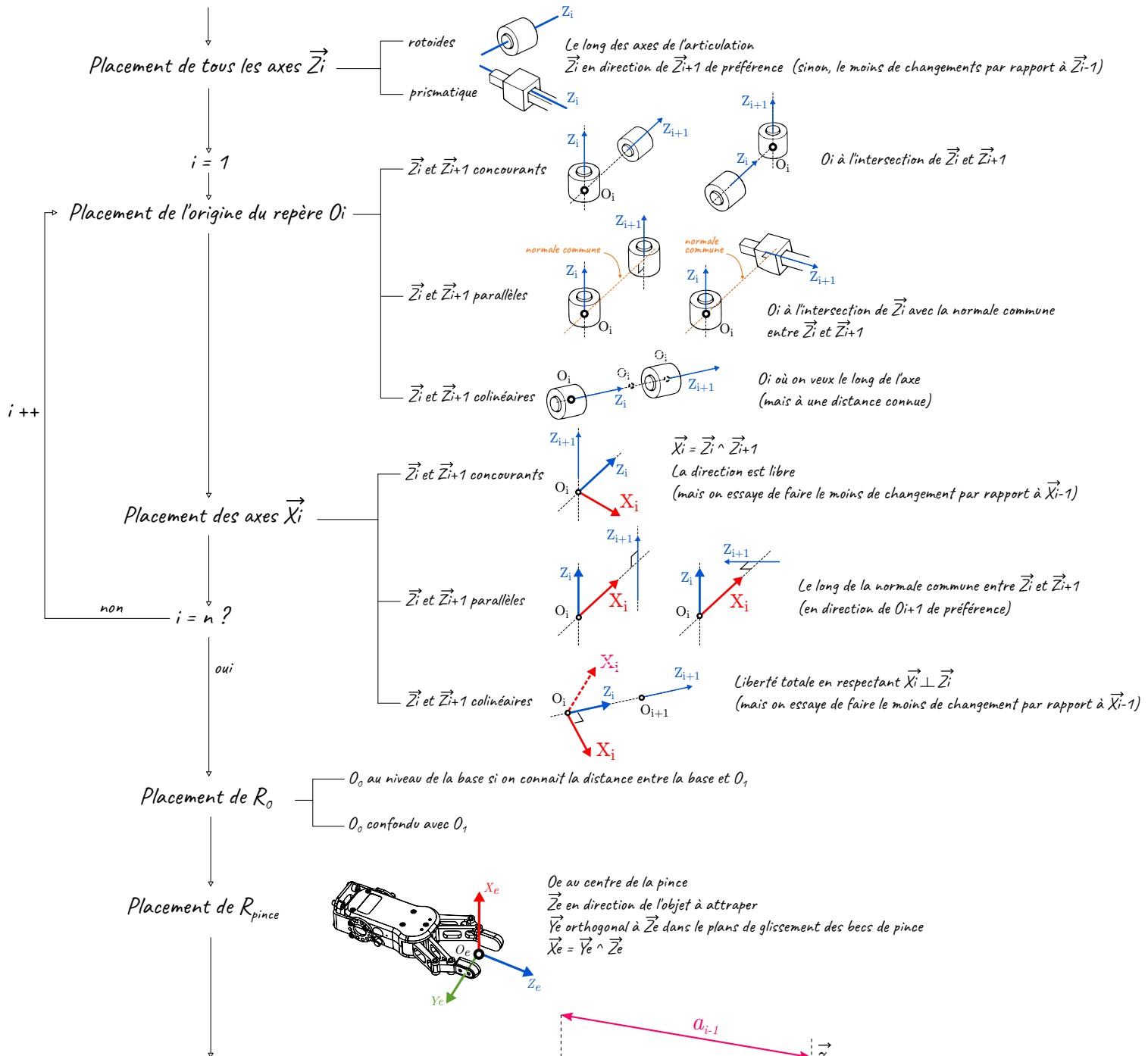
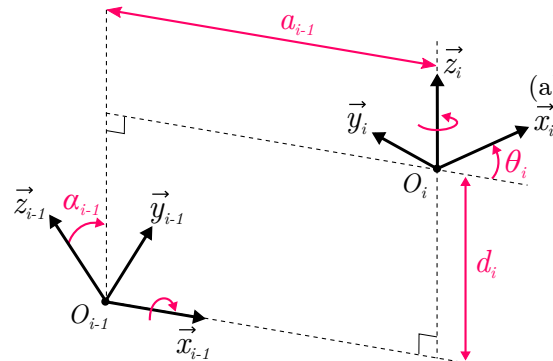


Numérotation des articulations et des segments de 1 à n



Symbol	Name	Description
a_{i-1}	Link Length	$\vec{Z}_{i-1} \xrightarrow[\text{rotation}]{\perp, \text{distance}} \vec{Z}_i$
α_{i-1}	Twist Angle	$\vec{Z}_{i-1} \xrightarrow[\text{translation}]{\text{rotation}} \vec{Z}_i$
d_i	Joint Offset	$\vec{X}_{i-1} \xrightarrow[\text{rotation}]{\perp, \text{distance}} \vec{X}_i$
θ_i	Joint Angle	$\vec{X}_{i-1} \xrightarrow[\text{translation}]{\text{rotation}} \vec{X}_i$



segment i	σ_i	a_{i-1}	α_{i-1}	d_i	θ_i
0T_1	1				
1T_2	2				
...	...				
${}^{n-1}T_n$	n				

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