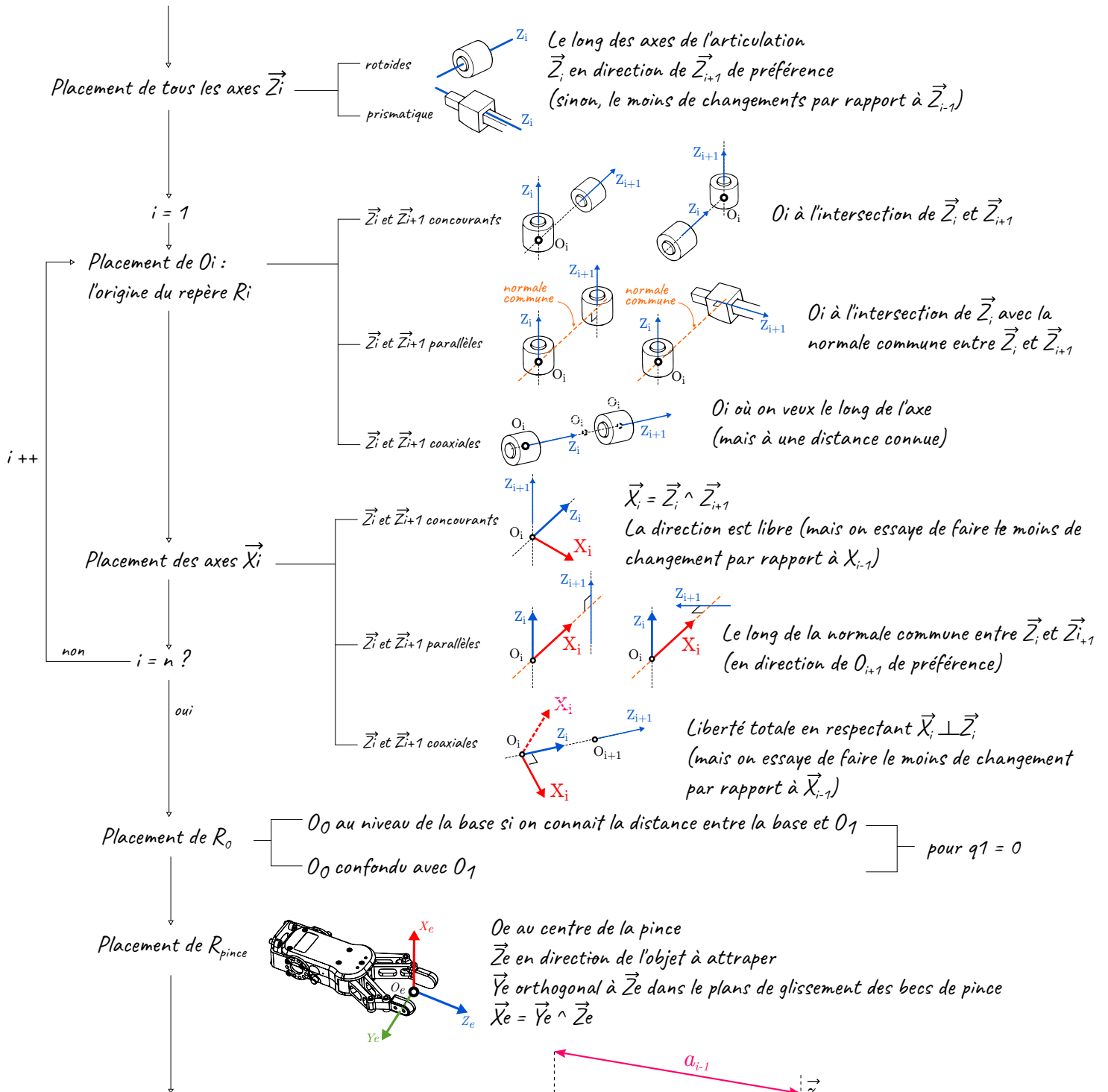
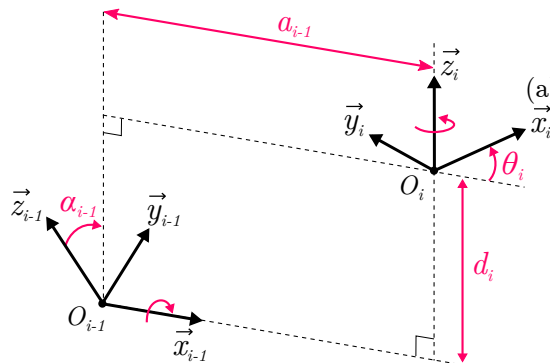


Numérotation des articulations et des segments de 1 à n



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

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