Robotics II
Final Project

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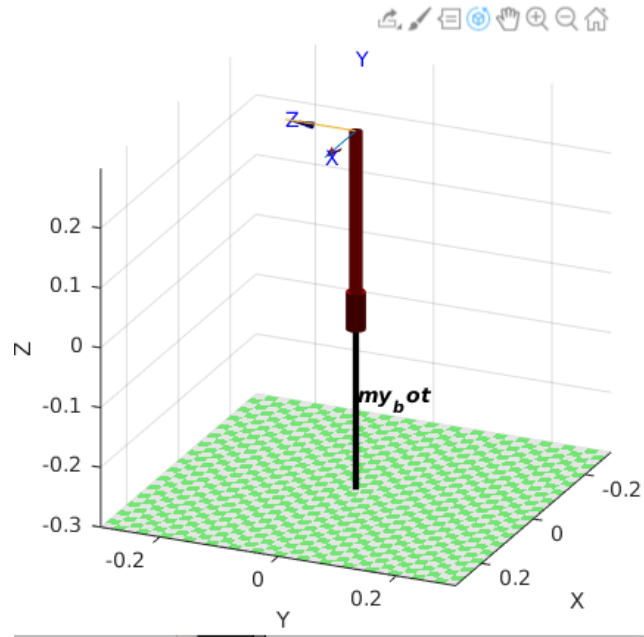
Contents

1 Denavit-Hartenberg

	α	a	d	θ
link 1	$\pi/2$	0	$L_1 = 0.3$	q_1
link 2	0	$L_2 = 0.3$	$d_2 = -0.09$	q_2
link 3	0	$L_3 = 0.2$	0	q_3

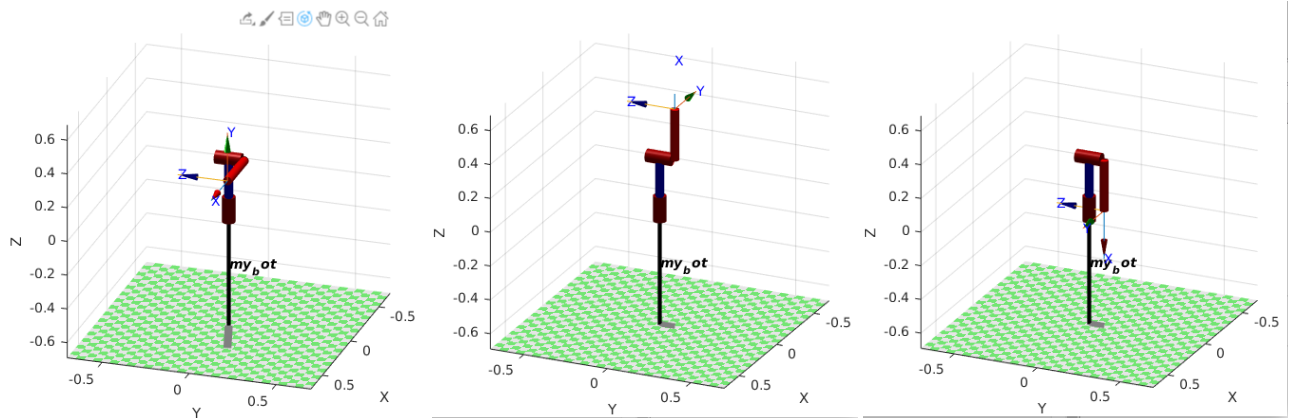**Frame 1**

Frame 2

Figure 1: (a) $q_2 = 0$; (b) $q_2 = 90$ deg; (c) $q_2 = -90$ deg
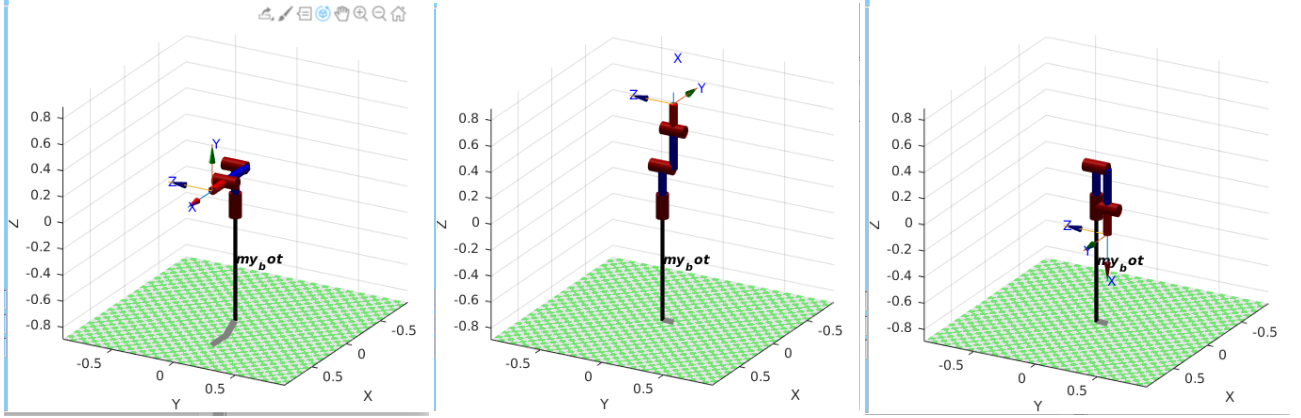
Frame 3

2 Centers of Mass

asdfg

Figure 2: (a) $q_2 = 0$, $q_3 = 0$; (b) $q_2 = 90$ deg, $q_3 = 0$; (c) $q_2 = $ -90 deg, $q_3 = 0$

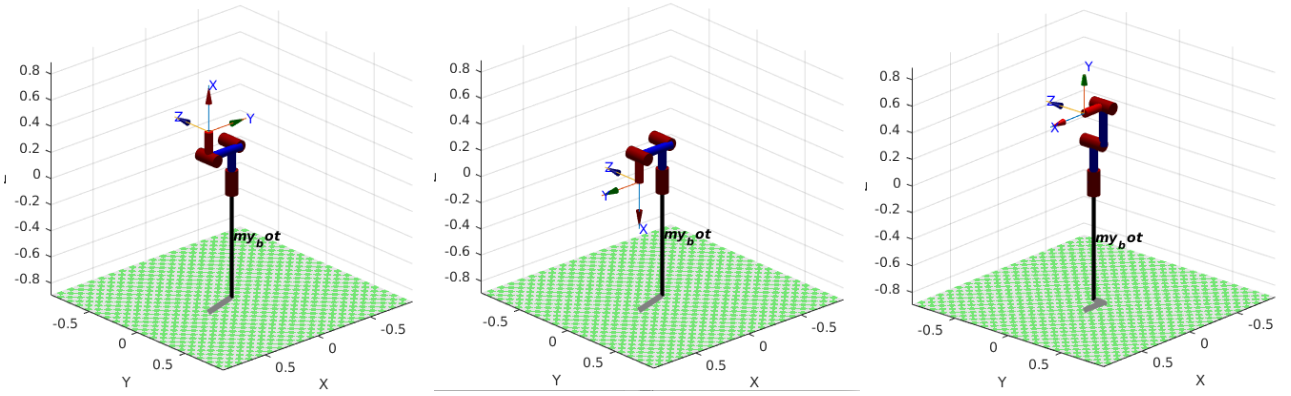Figure 3: (a) $q_2 = 0$, $q_3 = 90$ deg; (b) $q_2 = 0$ deg, $q_3 = $ -90 deg; (c) $q_2 = 90$ deg, $q_3 = $ -90 deg