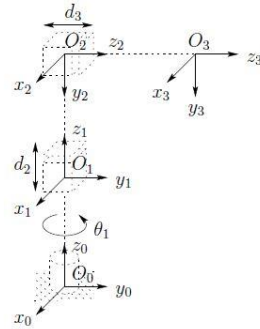# Example
Three Joints RPP Manipulator

OUTPUTS

```
StepSize(0-360):180
Insert the DH Table in a matrix form
ai Alphai di Thetai
[0   0   10   q(1)
 0  -90  q(2)  0
 0   0   q(3)  0]
Min q(1)=0
Max q(1)=180
Min q(2)=0
Max q(2)=2
Min q(3)=0
Max q(3)=4
```


Reachable Workspace

Workspace Boundary