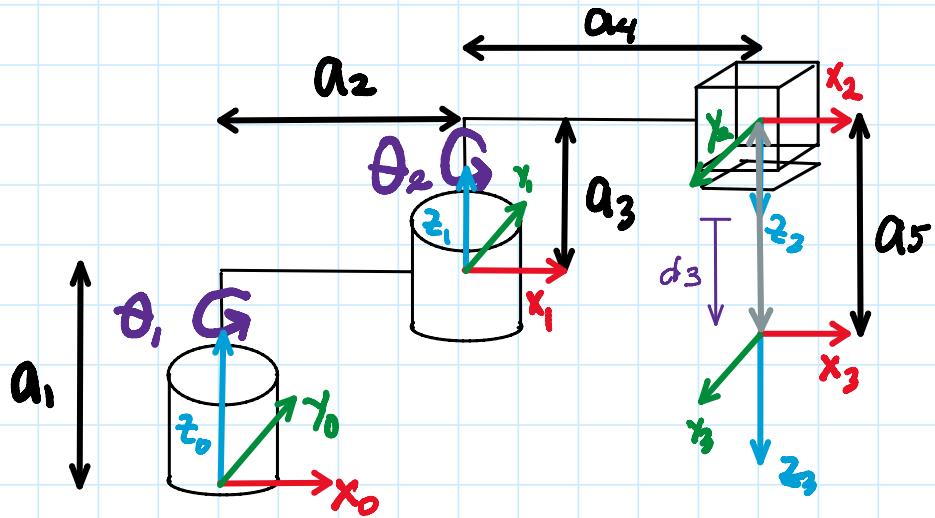


# Position Vectors of SCARA Manipulator

Friday, 4 November 2022 11:01 am

## 3. SCARA (Selective Compliance Articulated Robot for Assembly)



$${}^0P = \begin{bmatrix} a_2 \cos \theta_1 \\ a_2 \sin \theta_1 \\ a_1 \end{bmatrix} {}^0\begin{matrix} X \\ Y \\ Z \end{matrix}$$

$${}^1P = \begin{bmatrix} a_4 \cos \theta_2 \\ a_4 \sin \theta_2 \\ a_3 \end{bmatrix} {}^1\begin{matrix} X \\ Y \\ Z \end{matrix}$$

$${}^2P = \begin{bmatrix} 0 \\ 0 \\ d_3 + c_3 \end{bmatrix} {}^2\begin{matrix} X \\ Y \\ Z \end{matrix}$$