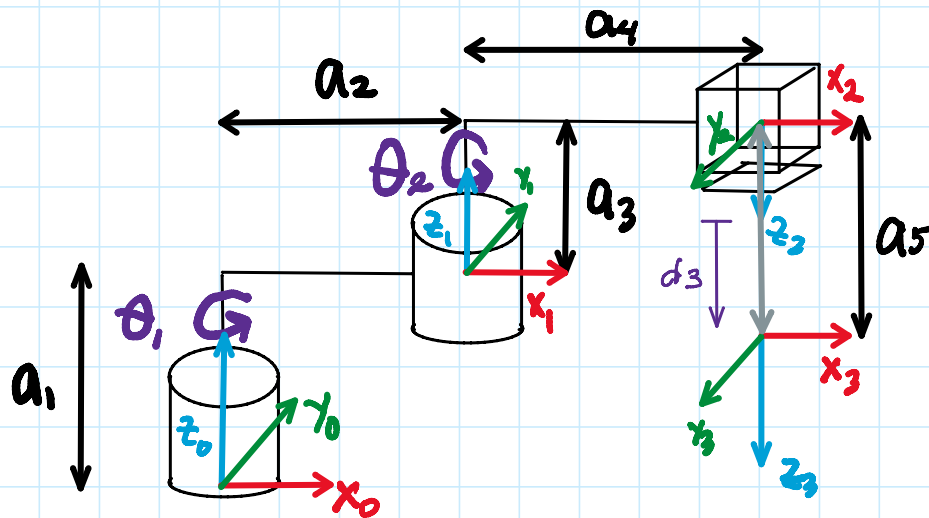


# Position Vectors of SCARA Manipulator

Friday, 4 November 2022

11:01 am

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



$${}^0P = \begin{bmatrix} a_2 \cos \theta_1 \\ a_2 \sin \theta_1 \\ a_1 \end{bmatrix} \begin{matrix} {}^0x \\ {}^0y \\ {}^0z \end{matrix}$$

$${}^1P = \begin{bmatrix} a_4 \cos \theta_2 \\ a_4 \sin \theta_2 \\ a_3 \end{bmatrix} \begin{matrix} {}^1x \\ {}^1y \\ {}^1z \end{matrix}$$

$${}^2P = \begin{bmatrix} 0 \\ 0 \\ a_5 + d_3 \end{bmatrix} \begin{matrix} {}^2x \\ {}^2y \\ {}^2z \end{matrix}$$