i	Joint type	a_i(m)	α_i(rad)	d_i(m)	θ_i(variable
1	R	0	0	0.0409	$\theta_1 = q_1$
2	R	0	$\pi/2$	0	$\theta_2 = q_2$
3	R	0.108	0	0	$\theta_3 = q_3$
4	R	0.100	0	0	$\theta_4 = q_4$
5	R	0.045	$\pi/2$	0	$\theta_5 = q_5$
6	P	0	0	d_6(var.)	$\theta_6 = 0$ (fixed)

$$T_0^1 = \begin{bmatrix} C_1 & -S_1 & 0 & 0 \\ S_1 & C_1 & 0 & 0 \\ 0 & 0 & 1 & d_1 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$T_1^2 = \begin{bmatrix} C_2 & 0 & S_2 & 0 \\ S_2 & 0 & -C_2 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$T_2^3 = \begin{bmatrix} C_3 & -S_3 & 0 & a_3C_3 \\ S_3 & C_3 & 0 & a_3S_3 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$T_3^4 = \begin{bmatrix} C_4 & -S_4 & 0 & a_4C_4 \\ S_4 & C_4 & 0 & a_4S_4 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$T_4^5 = \begin{bmatrix} C_5 & 0 & S_5 & a_5 C_5 \\ S_5 & 0 & -C_5 & a_5 S_5 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

$$T_0^6$$

$$\begin{bmatrix} S_1S_5 + C_1C_5C_6\,(C_{2+q_3+q_4}) & C_1S_{(q_2+q_3+q_4+q_5)} & -S_1C_6 + S_5C_1C_{(q_2+q_3+q_4)} & (0.2S_{(q_2+q_3+q_4)} + C_1 + C_{(q_2+q_3)})C_6 \\ S_1C_5C_{(q_2+q_3+q_4)} - S_5C_1 & S_1S_{(q_2+q_3+q_4+q_5)} & S_5S_1C_{(q_2+q_3+q_4)} + C_1C_5 & (0.2S_{(q_2+q_3+q_4)} + C_{(q_2+q_3)})S_1 \\ S_{(q_2+q_3+q_4)}C_{45} & -C_{(q_2+q_3+q_4)} & S_{(q_2+q_3+q_4)}S_5 & S_{(q_2+q_3+q_4)} + 0.2C_{(q_2+q_3+q_4)} + 0.2 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$