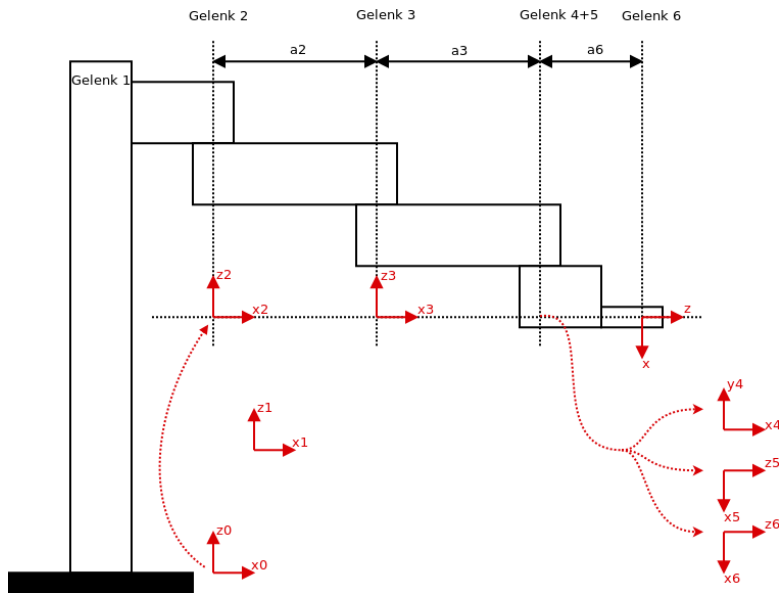


COBRA industrial robot Kinematic

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1 Gelenke

$d_1 = d_1$	$q_1 = 0^\circ$
$d_2 = 0$	$q_2 = \theta_2$
$d_3 = 0$	$q_3 = \theta_3$
$d_4 = 0$	$q_4 = \theta_4$
$d_5 = 0$	$q_5 = \theta_5$
$d_6 = 0$	$q_6 = \theta_6$

2 Armteile

$a_1 = a_1$	$\alpha_1 = 0^\circ$
$a_2 = 0$	$\alpha_2 = 0^\circ$
$a_3 = 0$	$\alpha_3 = 0^\circ$
$a_4 = 0$	$\alpha_4 = 90^\circ$
$a_5 = 0$	$\alpha_5 = 90^\circ$
$a_6 = 0$	$\alpha_6 = 0^\circ$