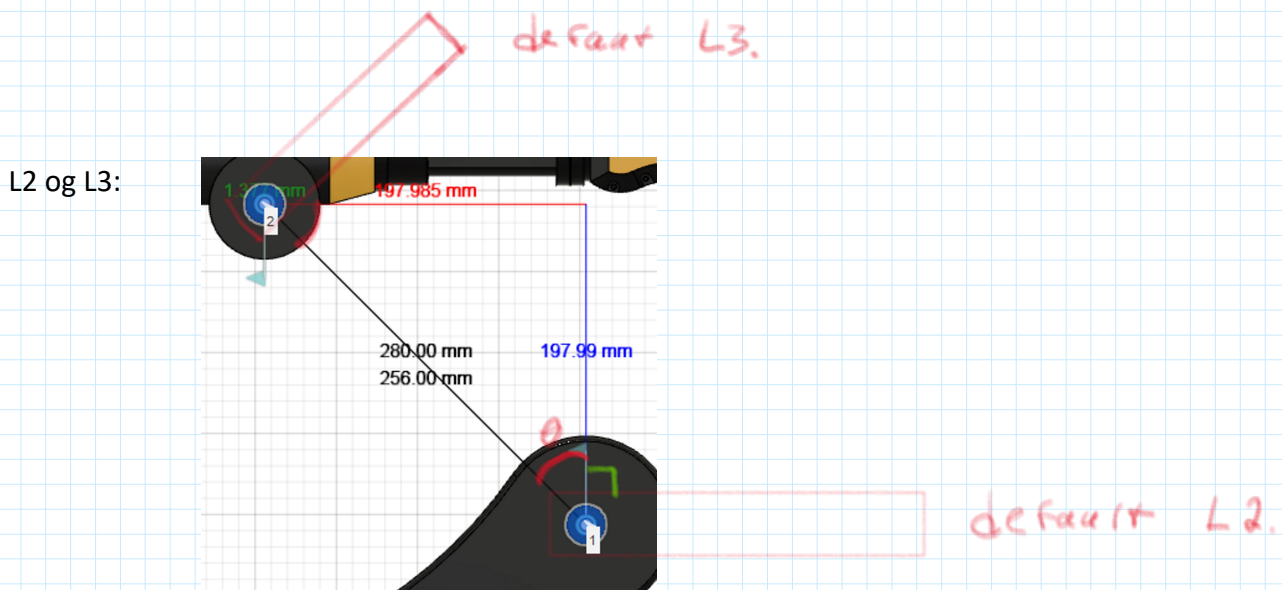


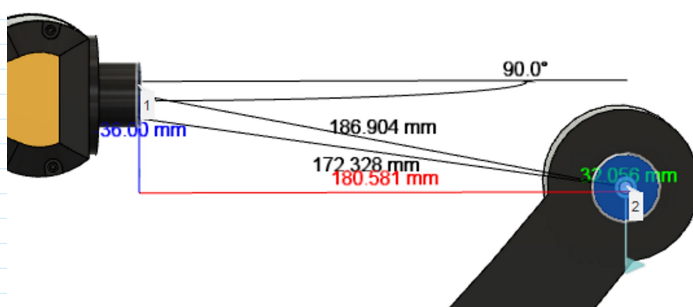
Calculate dh-parameters offset so it has the correct start position like in the 3d model of the arm. We need to do this so that the joint angles calculated on the SerialLink object corresponds to the correct joint angles in the 3d model in gazebo. This way we will get the correct pose even though we do all the calculations on the SerialLink object i matlab.

L1: Orad offset siden min/max limit er lik.



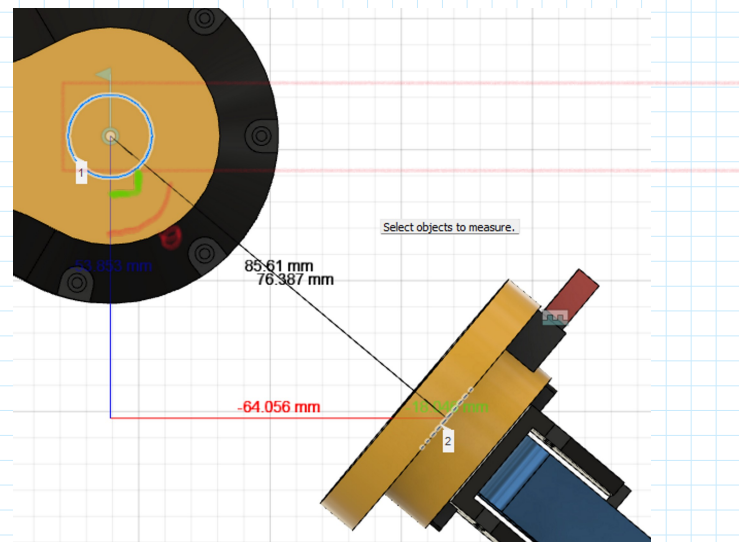
$$L2 \text{ offset} = \frac{\pi}{2} + \cos^{-1}\left(\frac{197.99 \text{ mm}}{280 \text{ mm}}\right) = \underline{\underline{2.35619 \text{ rad}}}$$

$$L3 \text{ offset} = -\left(\frac{\pi}{2} - \cos^{-1}\left(\frac{197.985 \text{ mm}}{280 \text{ mm}}\right)\right) = \underline{\underline{-0.7853734 \text{ rad}}}$$



L4: 0rad offset siden det er et "roll" ledd med rett rotasjon.

L5:



default LS.

$$LS \text{ offset} = \frac{\pi}{2} - \cos^{-1}\left(\frac{53,853 \text{ mm}}{85,61 \text{ mm}}\right) = \underline{\underline{0,68033 \text{ rad}}}$$

L6: 0rad offset siden det er et "roll" ledd med rett rotasjon.