



link i	θ_i	d_i	a_i	α_i
1	q_1	L_1	0	$\frac{\pi}{2}$
2	$-\frac{\pi}{2} + q_2$	L_7	L_3	$-\pi$
3	$-\frac{\pi}{2} + q_3$	$L_7 - L_{11}$	0	$\frac{\pi}{2}$
4	$\frac{\pi}{2} + q_4$	$L_5 - L_{12}$	$L_2 - L_{11}$	0
5	$-\frac{\pi}{2} + q_5$	L_{12}	0	$\frac{\pi}{2}$
6	$0 + q_6$	$L_4 + L_{13}$	0	0
cm1	$0 + q_1$	0	0	0
cm2	$-\frac{\pi}{2} + q_2$	L_7	L_8	0
cm3	$0 + q_3$	$L_7 - L_{11} - L_9$	L_{10}	0

Figure 3.1: 3DOF robot.