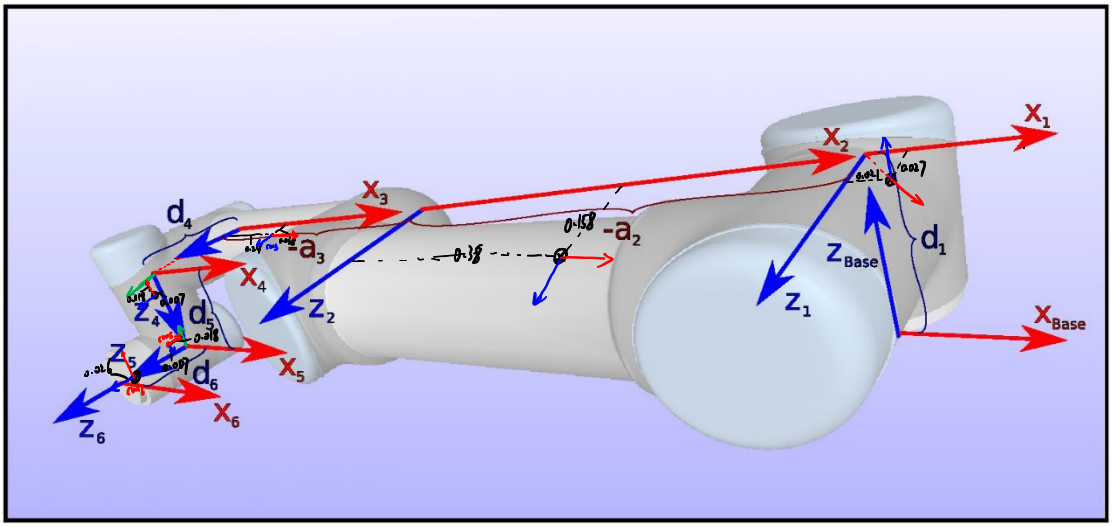

Linki	θ_i	d_i	a_i	α_i
1	q_1	0.1273	0	$\frac{\pi}{2}$
2	q_2	0	-0.612	0
3	q_3	0	-0.5723	0
4	q_4	0.163941	0	$\frac{\pi}{2}$
5	q_5	0.1157	0	$-\frac{\pi}{2}$
6	q_6	0.0922	0	0
EF				
cm1	$q_1 - \arctan\frac{0.027}{0.021}$	0.1273	$\sqrt{0.027^2+0.021^2}$	0
cm2	q_2	0.158	-(0.612-0.38)	0
cm3	q_3	0.068	-(0.5723-0.28)	0
cm4	$q_4+\frac{\pi}{2}$	0.163941+0.007	-0.018	0
cm5	$q_5-\frac{\pi}{2}$	0.1157-0.007	-0.018	0
cm6	$q_6+\frac{\pi}{2}$	0.0922-0.026	0	0

[Base, Upper Arm, Lower arm, Wrist 2, Wrist 3, Tool Mounting Bracket]

a = [0, -0.612, -0.5723, 0, 0, 0]

d = [0.1273, 0, 0, 0.163941, 0.1157, 0.0922]

alpha = [1.570796327, 0, 0, 1.570796327, -1.570796327, 0]

mass = [7.1, 12.7, 4.27, 2.000, 2.000, 0.365]

center_of_mass = [[0.021, 0, 0.027], [0.38, 0, 0.158], [0.24, 0, 0.068], [0.0, 0.007, 0.018], [0.0, 0.007, 0.018], [0, 0, -0.026]]

Definition for Center of mass parameters