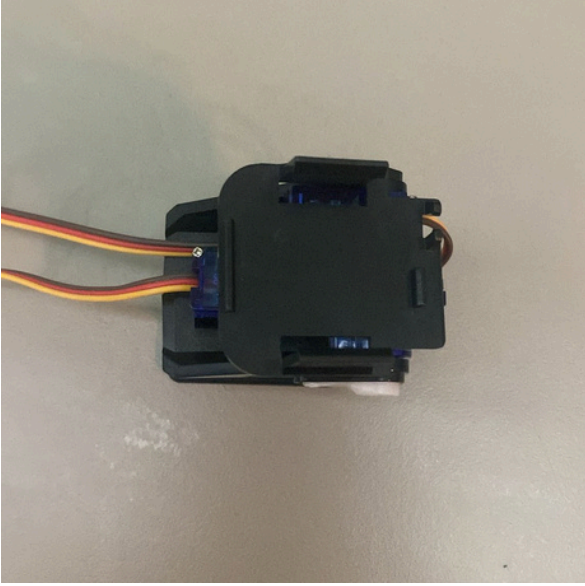
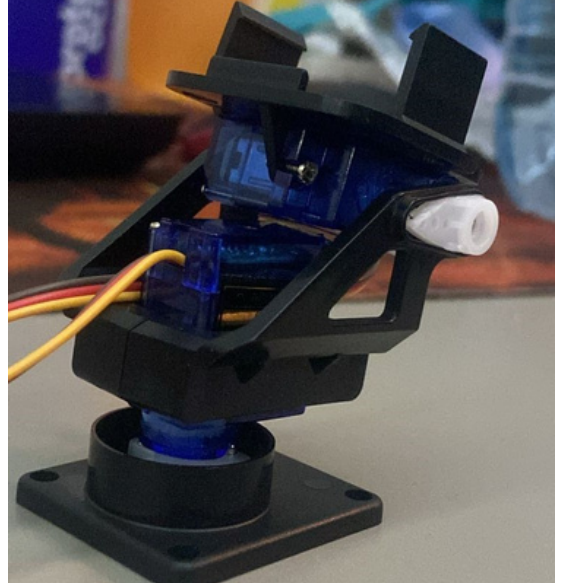


# ROBOTİK PROGRAMLAMA ÖDEVİ

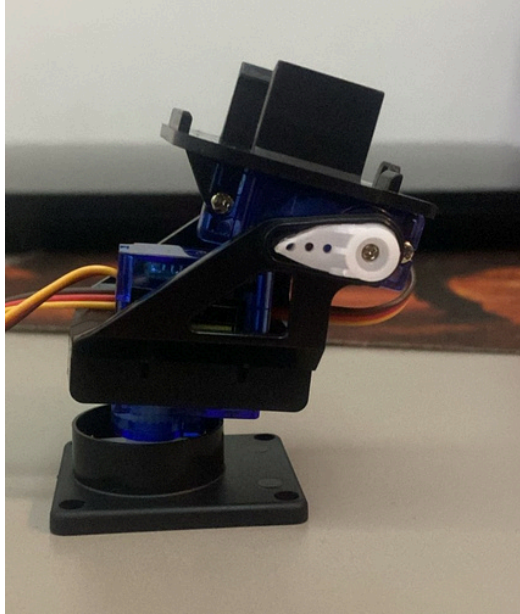
ÜST



ÇAPRAZ



YAN



DH TABLOSU

LINK	$\theta$	d (cm)	a (cm)	$\alpha$
1	$\theta_1$	2	2.4	180
2	$\theta_2$	4	2.4	0

## MOTOR 1 DÖNÜŞÜM MATRİSİ

$$T1 = \begin{bmatrix} \cos(\theta_1) & -\sin(\theta_1)\cos(180^\circ) & \sin(\theta_1)\sin(180^\circ) & l\cos(\theta_1) \\ \sin(\theta_1) & \cos(\theta_1)\cos(180^\circ) & -\cos(\theta_1)\sin(180^\circ) & l\sin(\theta_1) \\ 0 & \sin(180^\circ) & \cos(180^\circ) & d1 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

## MOTOR 2 DÖNÜŞÜM MATRİSİ

$$T2 = \begin{bmatrix} \cos(\theta_2) & -\sin(\theta_2)\cos(0^\circ) & \sin(\theta_2)\sin(0^\circ) & l\cos(\theta_2) \\ \sin(\theta_2) & \cos(\theta_2)\cos(0^\circ) & -\cos(\theta_2)\sin(0^\circ) & l\sin(\theta_2) \\ 0 & \sin(0^\circ) & \cos(0^\circ) & d2 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

