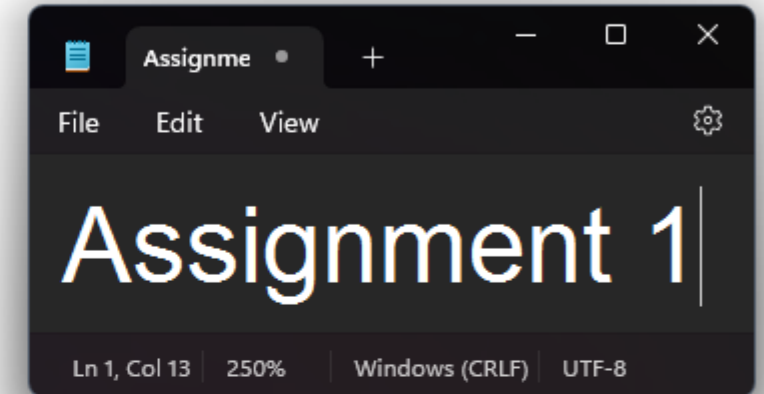
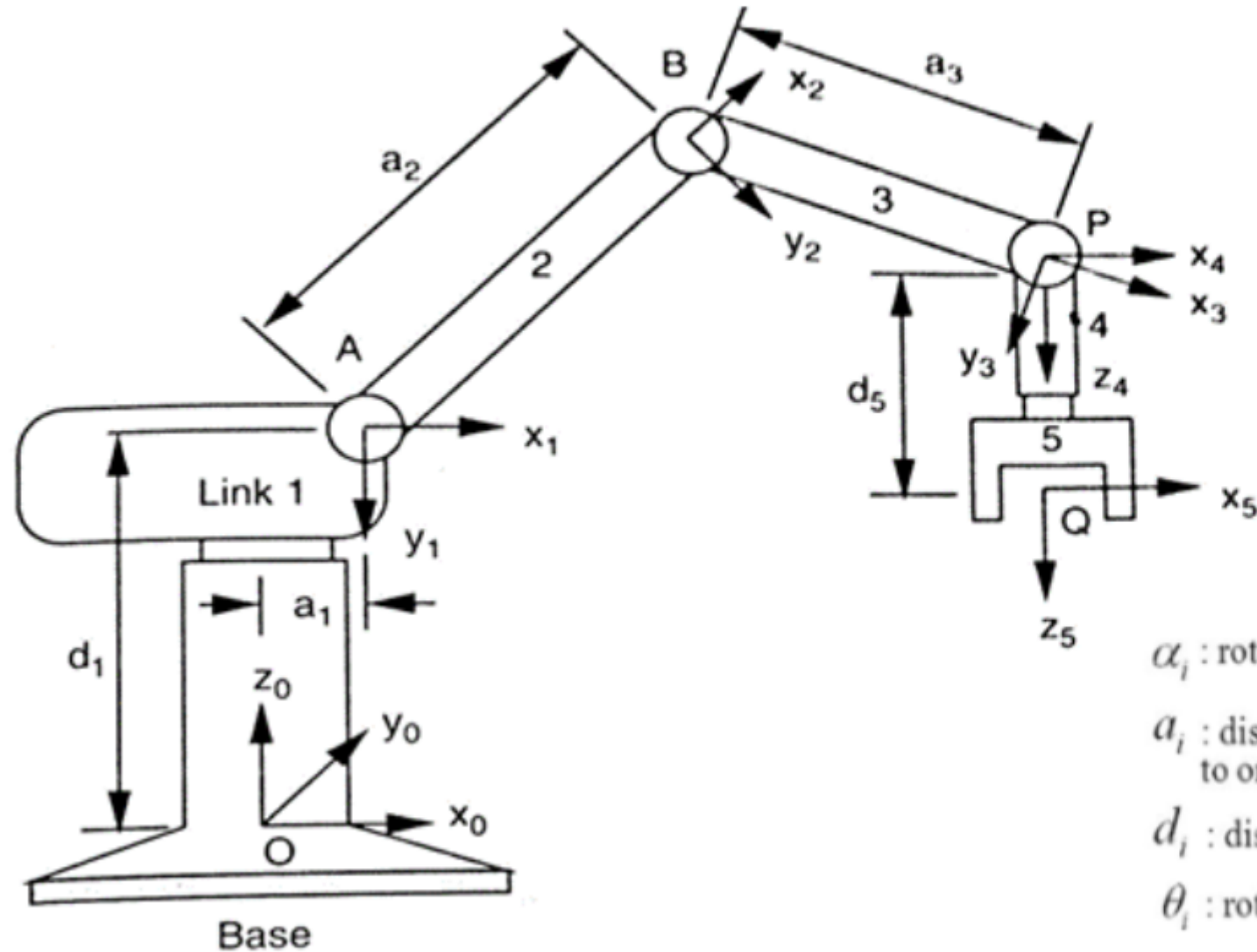


SCORBOT Robot (5 DOF Manipulator)



α_i : rotation angle from Z_{i-1} to Z_i about X_i

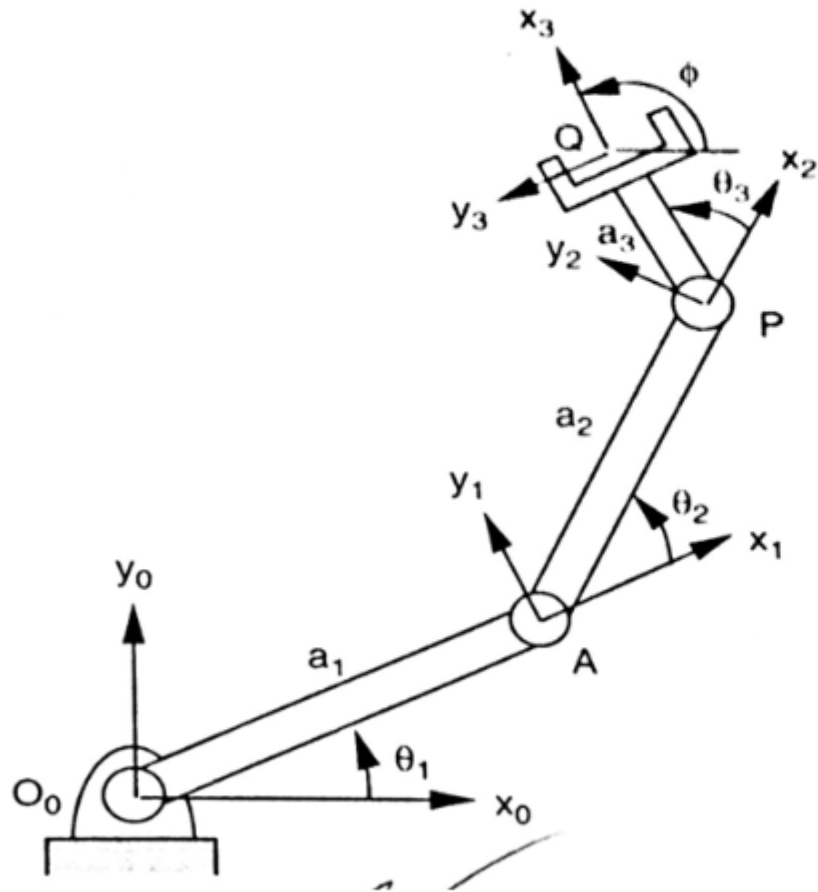
a_i : distance from intersection of Z_{i-1} & X_i to origin of i coordinate along X_i

d_i : distance from origin of $(i-1)$ coordinate to intersection of Z_{i-1} & X_i along Z_{i-1}

θ_i : rotation angle from X_{i-1} to X_i about Z_{i-1}

2	-90	a_1	0	θ_2
3	0	0	d_2	θ_3

Assignment: Calculate position of end effector of this 3 DOF Manipulator



Angles of three joints are **30 degree, 45 degree and 10 degree.**

$$a_1 = 10$$

$$a_2 = 8$$

$$a_3 = 3$$

