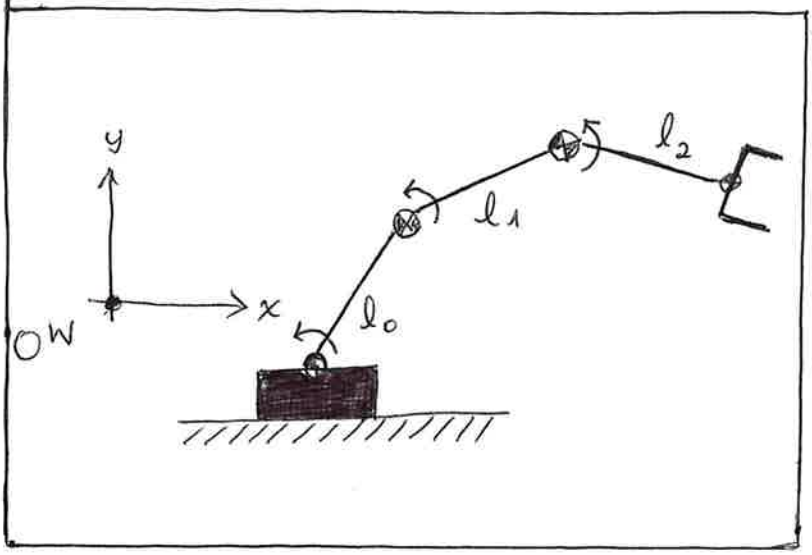
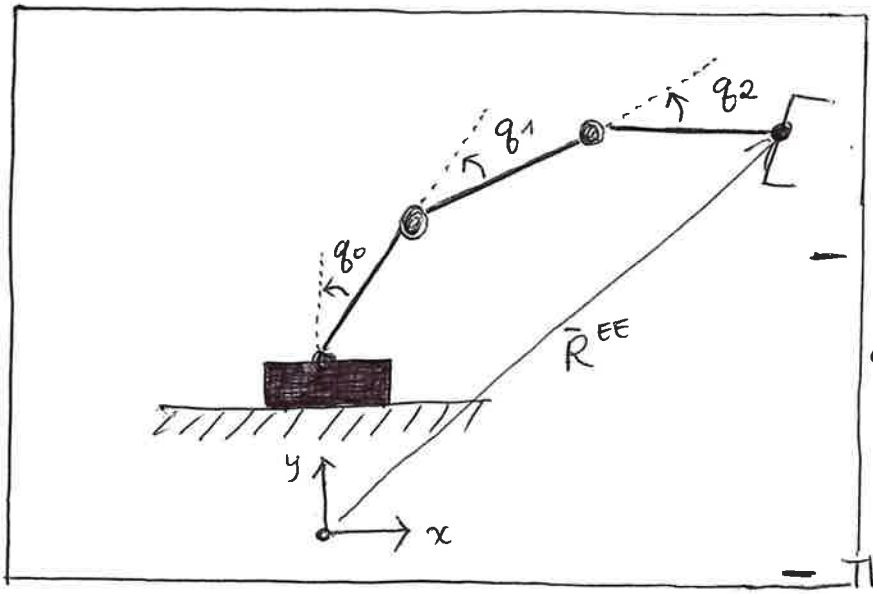


- 3 DoF, Planar (x-y) Robot
- by right-hand-rule ⊕ rotation is counter-clockwise about z-axis (out of page)
- l_0, l_1, l_2 are the link lengths, denoting cartesian distance between each rotation axis (= joints)



- the configuration $\vec{q} = \begin{bmatrix} q_0 \\ q_1 \\ q_2 \end{bmatrix}$ describes the angle of each joint
- The end effector pose, $\bar{R}^{EE}$, can be calculated given the kinematics (l_0, l_1, l_2) and $\vec{q}$