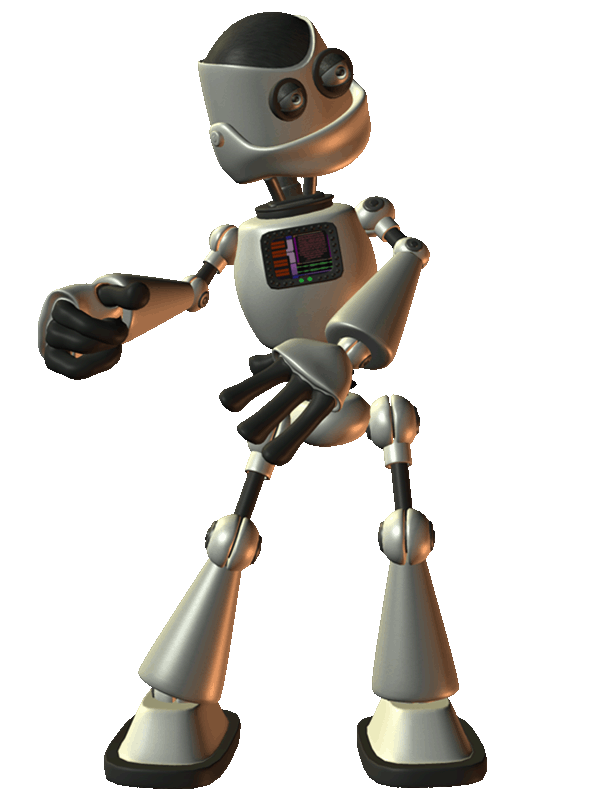
**UNIVERSIDAD POLITECNICA DE LA ZONA METROPOLITANA DE GUADALAJARA**

**CINEMATICA DE ROBOTS**

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**INGENIERIA MECATRONICA 8°B**

**PRACTICA #1**

**MAESTRO:**

**CARLOS ENRIQUE MORAN GARABITO**

**ALUMNO:**

**ALEXIS ISRAEL VIORATO ARAMBULA**

MATRICES DE MI ROBOT

T1 =

[ cos(theta1), -sin(theta1), 0, 0]

[ 0, 0, -1, 0]

[ sin(theta1), cos(theta1), 0, 0]

[ 0, 0, 0, 1]

T2 =

[ cos(theta2), -sin(theta2), 0, L1]

[ sin(theta2), cos(theta2), 0, 0]

[ 0, 0, 1, d1]

[ 0, 0, 0, 1]

T3 =

[ cos(theta3), -sin(theta3), 0, L2]

[ sin(theta3), cos(theta3), 0, 0]

[ 0, 0, 1, d2]

[ 0, 0, 0, 1]

[ cos(theta3)\*(cos(theta1)\*cos(theta2) - sin(theta1)\*sin(theta2)) - sin(theta3)\*(cos(theta1)\*sin(theta2) + cos(theta2)\*sin(theta1)), - cos(theta3)\*(cos(theta1)\*sin(theta2) + cos(theta2)\*sin(theta1)) - sin(theta3)\*(cos(theta1)\*cos(theta2) - sin(theta1)\*sin(theta2)), 0, L2\*(cos(theta1)\*cos(theta2) - sin(theta1)\*sin(theta2)) + L1\*cos(theta1)]

[ 0, 0, -1, - d1 - d2]

[ cos(theta3)\*(cos(theta1)\*sin(theta2) + cos(theta2)\*sin(theta1)) + sin(theta3)\*(cos(theta1)\*cos(theta2) - sin(theta1)\*sin(theta2)), cos(theta3)\*(cos(theta1)\*cos(theta2) - sin(theta1)\*sin(theta2)) - sin(theta3)\*(cos(theta1)\*sin(theta2) + cos(theta2)\*sin(theta1)), 0, L2\*(cos(theta1)\*sin(theta2) + cos(theta2)\*sin(theta1)) + L1\*sin(theta1)]

[ 0, 0, 0, 1]

