Multilink Simulation

Example case1:

Base Frame Position (x,y,z): (0,0,0)

Base Orientation values (alpha, beta, gamma): (0, 0, 90)

Make a 3 joint robot by adding 2 links

Alpha	a	d	theta
0	0	0	0
0	2	3	45
0	3	0	90

Example case 2:

(Puma 560)

Base Frame Position (x,y,z): (0,0,0)

Base Orientation values (alpha, beta, gamma): (0, 0, 90)

Make a 6 joint robot by adding 5 links

Alpha	a	d	theta
90	0	6	56
0	4	1	-100
90	0	0	100
90	0	4	120
90	0	0	20
0	0	1	200