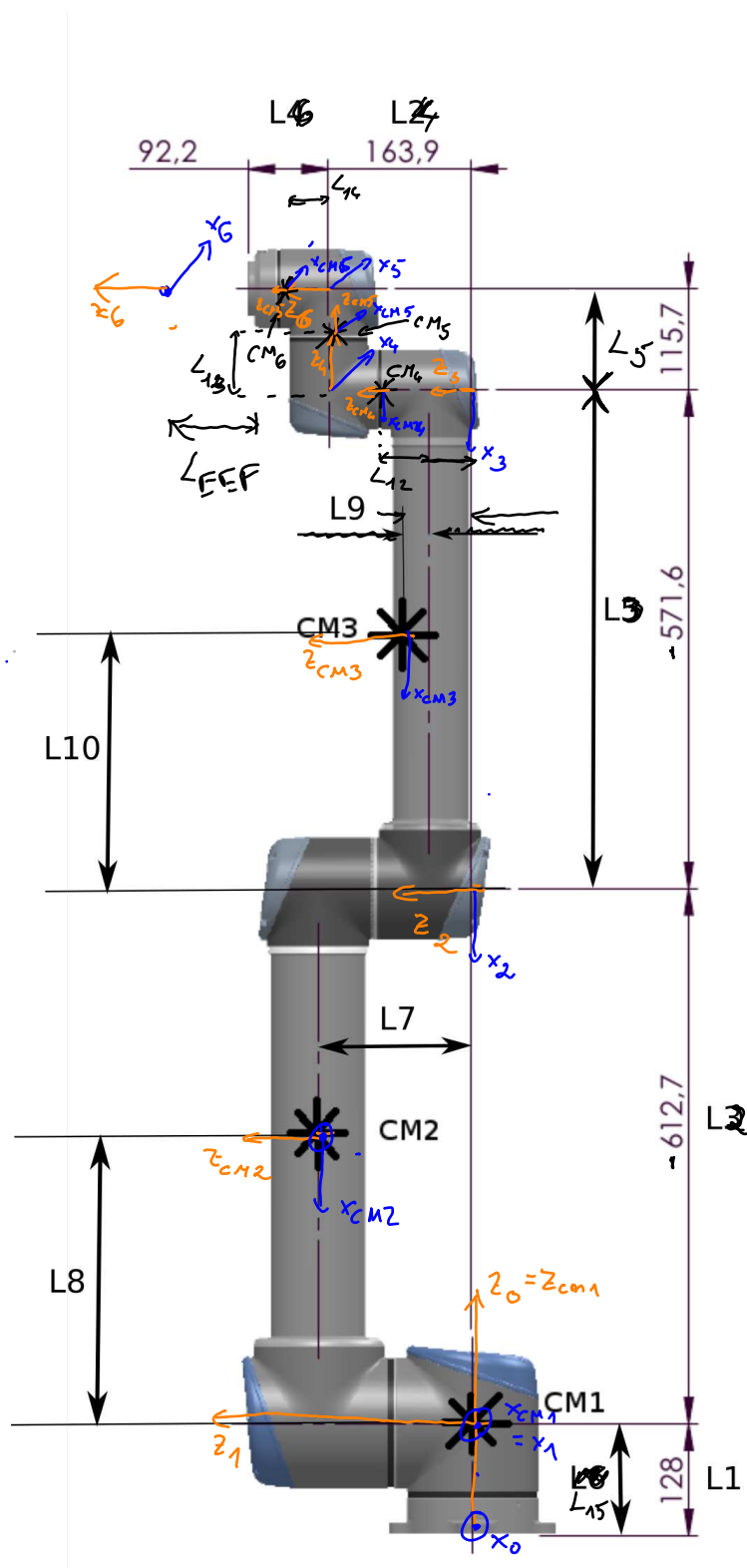


Important: The Joint values q_2 and q_4 contain offsets of $-\pi/2$ in this drawing



$L1=118$
 $L2=-612.1$
 $L3=-571.6$
 $L4=163.9$
 $L5=115.7$
 $L6=92.2$
 $L7=150$
 $L8=L2/2$
 $L9=-10$
 $L10=L3/2$
 $L11=115.7$
 $L12=L4/2$
 $L13=L5/2$
 $L14=(L6+LEEF)/2$
 $L15=100$
 $L16=L6+LEEF$
 $LEEF=140$

combination of info from manufacturors table & Denavit's definition

DH-table:

i	q_i	d	a	α
1	q_1	L_1	0	$\pi/2$
2	$q_2 - \pi/2$	0	L_2	0
3	q_3	0	L_3	0
4	$q_4 - \pi/2$	L_4	0	$\pi/2$
5	q_5	L_5	0	$-\pi/2$
6	q_6	L_6	0	0

CM_1	q_1	L_{15}	0	0
CM_2	$q_2 - \frac{\pi}{2}$	L_7	L_8	0
CM_3	q_3	L_9	L_{10}	0
CM_4	$q_4 - \frac{\pi}{2}$	L_{12}	0	0
CM_5	q_5	L_{13}	0	0
CM_6	q_6	L_{14}	0	0

Figure 5.1: Universal Robot UR-10 with dimensions and kinematic parameters.