

$$Q^{2} = l^{2} + a_{1}^{2} - 2 l \alpha_{2} \cos \phi$$

$$Cos \left(\frac{3\pi}{2} - \Theta_{3} - a tan 2(a_{31} d_{4})\right) = \frac{d_{1}^{2} + a_{3}^{2} + a_{2}^{2} - (z_{c} - d_{1})^{2} + (\sqrt{\kappa_{c}^{2} + \chi_{c}^{2}} - a_{1})^{2}}{2(\sqrt{d_{4}^{2} + a_{3}^{2}})(a_{2})}$$

$$- sin \left(\Theta_{3} + a tan 2(a_{3}, d_{4})\right) = 0$$

$$- sin \left(\Theta_{7}\right) = 0$$

$$\Theta_{7} = a tan 2\left(D, \sqrt{1 - D^{2}}\right)$$

$$\Theta_{3} = a tan 2\left(D, \sqrt{1 - D^{2}}\right) - a tan 2(a_{3}, d_{4})$$

$$\Theta_{2}.$$

 $\beta_1 = a + a \wedge 2 \left( z_c - d_1 \sqrt{x_c^2 + y_c^2} - a_1 \right)$ 

R3 (0,02,03) R6 (04,05,06) = Rd

=Applying Euler Angle formulas

Oy = atan 2 (m23, m,3) 05 = 9 tan 2 ( 1-m32, m33) O6 = a tan 2(m32, -m31)

 $R_6^3(\Theta_4, \Theta_5, \Theta_6) = [R_3^0(\Theta_1, \Theta_2, \Theta_3)]^T R_d = M \Rightarrow \text{ with components } m_{xy}$ 

by from forward Kin,

 $\Theta_2 = \beta_1 - \beta_2$ 

Oy, Os, Os

$$\cos\left(\frac{3\pi}{2} - \Theta_3 - \operatorname{atan} 2(a_{31} d_4)\right) =$$



Cos 
$$\phi$$

= D

 $\beta_{2} = a tand ( \sqrt{a_{3}^{2} + d_{4}^{2}} \sin (a tan 2(a_{3}, d_{4}) + \Theta_{3} - \frac{\pi}{2}), a_{2} + \sqrt{a_{3}^{2} + d_{4}^{2}} \cos (a tan 2(a_{3}, d_{4}) + \Theta_{3} - \frac{\pi}{2}))$ 

-> elbow up config.





































