



FIG. 1 – Robot manipulateur RRRRR

Paramètres de Denavit-Hartenberg:

| | 1 | 2 | 3 | 4 | 5 | |
|----------------------|---|---|---|---|---|--|
| σ_i | | | | | | |
| α_{i-1} | | | | | | |
| a_{i-1} | | | | | | |
| θ_i | | | | | | |
| r_i | | | | | | |
| $q_i(\text{figure})$ | | | | | | |

$$T_{01} = \begin{pmatrix} & & & \\ & & & \\ & & & \\ \hline 0 & 0 & 0 & 1 \end{pmatrix}$$

$$T_{12} = \begin{pmatrix} & & & \\ & & & \\ & & & \\ \hline 0 & 0 & 0 & 1 \end{pmatrix}$$

$$T_{23} = \begin{pmatrix} & & & \\ & & & \\ & & & \\ \hline 0 & 0 & 0 & 1 \end{pmatrix}$$

$$T_{34} = \begin{pmatrix} & & & \\ & & & \\ & & & \\ \hline 0 & 0 & 0 & 1 \end{pmatrix}$$

$$T_{45} = \begin{pmatrix} & & & \\ & & & \\ & & & \\ \hline 0 & 0 & 0 & 1 \end{pmatrix}$$