Table 6: Parameters of the robot shown in Fig. 3 [9].

A [mm]	B [mm]	C [mm]	D [mm]	E [mm]	F [mm]	G [mm]	H [mm]	I [mm]	J [mm]
1276	1620	901.5	656	245.5	851.5	420	455	400	855

Table 7: Parameters D-H for the robot KR 6 R900 sixx AGILUS.

i	α_i [rad]	d_i [mm]	a_i [mm]	θ_i [rad]
1	$-\pi/2$	$d_1 = I$	$a_1 = 25$	$q_1 = \pi/2$
2	0	0	$a_2 = H$	$q_2 = -\pi/2$
3	$\pi/2$	0	$a_3 = 35$	$q_3 = 0$
4	$-\pi/2$	$d_4 = -(G-1.4)$	0	$q_4 = 0$
5	$\pi/2$	0	0	$q_5 = 0$
6	π	$d_6 = -80$	0	$q_6 = 0$

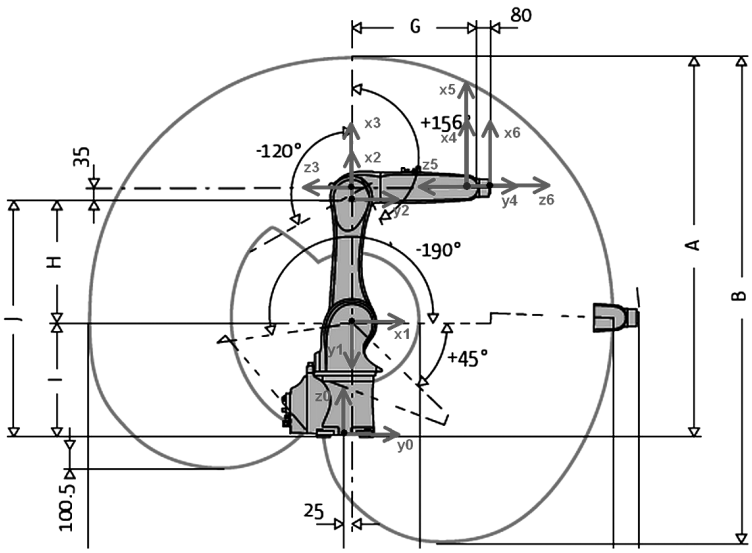

Figure 3: Dimensions of the robot KR 6 R900 sixx AGILUS [9] with marked coordinate systems.

Since all the necessary calculations are performed in the script VBscript, declaration of variables in the KRL file is not necessary, either.