



| Joint $i$ | $\theta_i$ | $d_i$ | $a_i$ | $\alpha_i$       |
|-----------|------------|-------|-------|------------------|
| 1         | $\theta_1$ | $d_1$ | 0     | $\frac{\pi}{2}$  |
| 2         | $\theta_2$ | 0     | $a_2$ | 0                |
| 3         | $\theta_3$ | 0     | $a_3$ | 0                |
| 4         | $\theta_4$ | $d_4$ | 0     | $\frac{\pi}{2}$  |
| 5         | $\theta_5$ | $d_5$ | 0     | $-\frac{\pi}{2}$ |
| 6         | $\theta_6$ | $d_6$ | 0     | 0                |