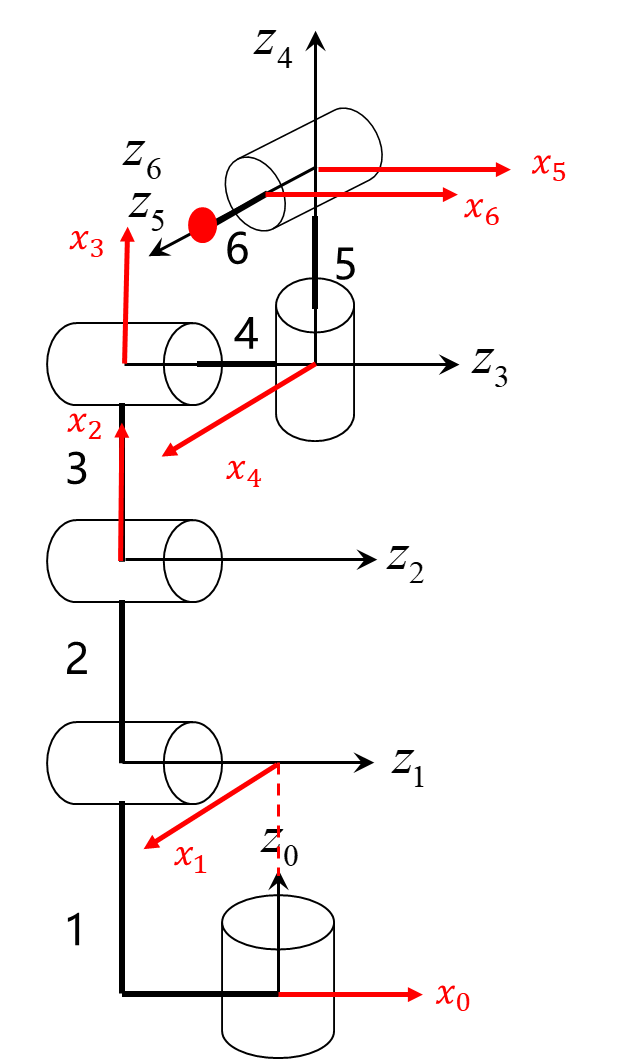
双足移动机器人技术及强化实践 实验3

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对ZJU-I型桌面机械臂，建立坐标系如图：



DH参数表：

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
|  |  |  |  |  |
| 1 | 0 | -90° | 230mm |  |
| 2 | 185mm | 0 | -54mm | (-90°) |
| 3 | 170mm | 0 | 0 |  |
| 4 | 0 | 90° | 77mm | (90°) |
| 5 | 0 | 90° | 77mm | (90°) |
| 6 | 0 | 0 | 85.5mm |  |