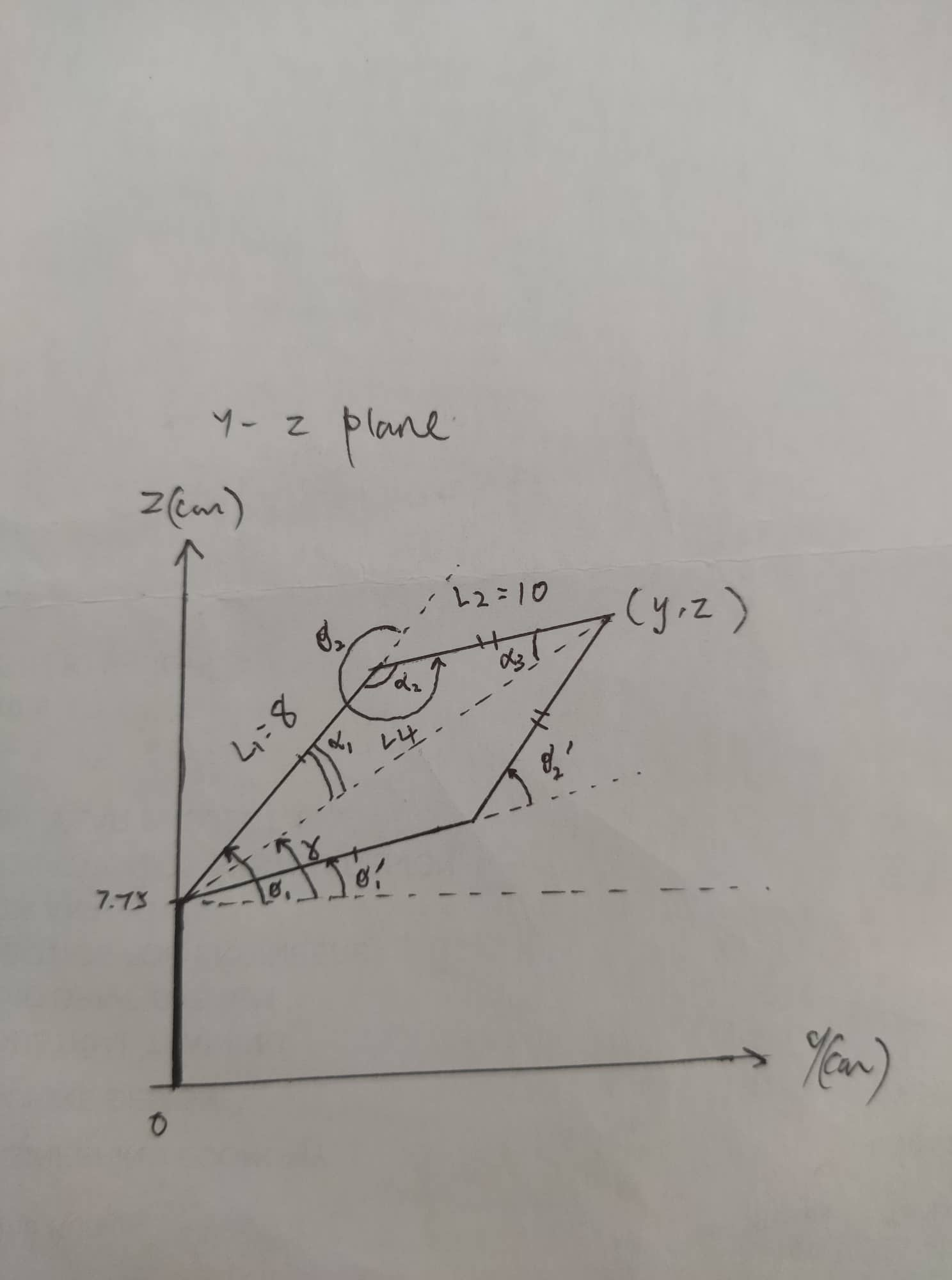
***Table x:*** *DH Parameter Algorithms*

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
|  |  |  |  |  |
| 1 |  | 7.75 | 0 |  |
| 2 |  | 0 | 8 | 0 |
| 3 |  | 10 | 0 | 0 |

1. **Forward Kinematic**

=

1. **Inverse Kinematic**



***Figure x:*** *Free body diagram for inverse kinematics*

Where can be calculated as shown by using cosine rule: