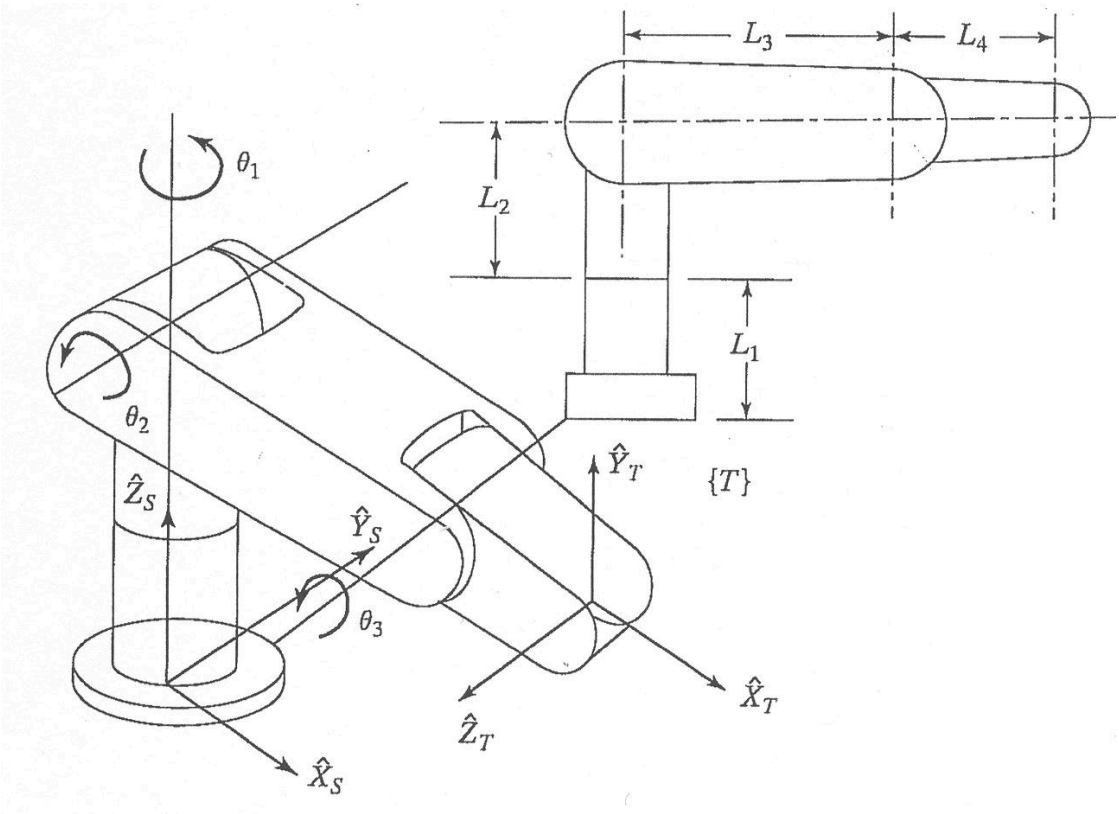
Forward Kinematic exercise

Given the following 3R robot



Where L_1=4, L_2=3, L_3=2, and L_4=1.

Write a Live script file (.mlx)

1) Draw on top of the figure de necessary frame
2) Derive the DH parameters table and the neighboring homogeneous transformation matrices ${}^{i-1}T_i$, for i=1,2,3, as functions of the joint angles
3) Implement the forward kinematics, that is ${}^{T}T_s$,
4) Calculate the result for the following joint angles: (0, 0, 0), (0, π/2, 0), and (0, π/2, π/6).