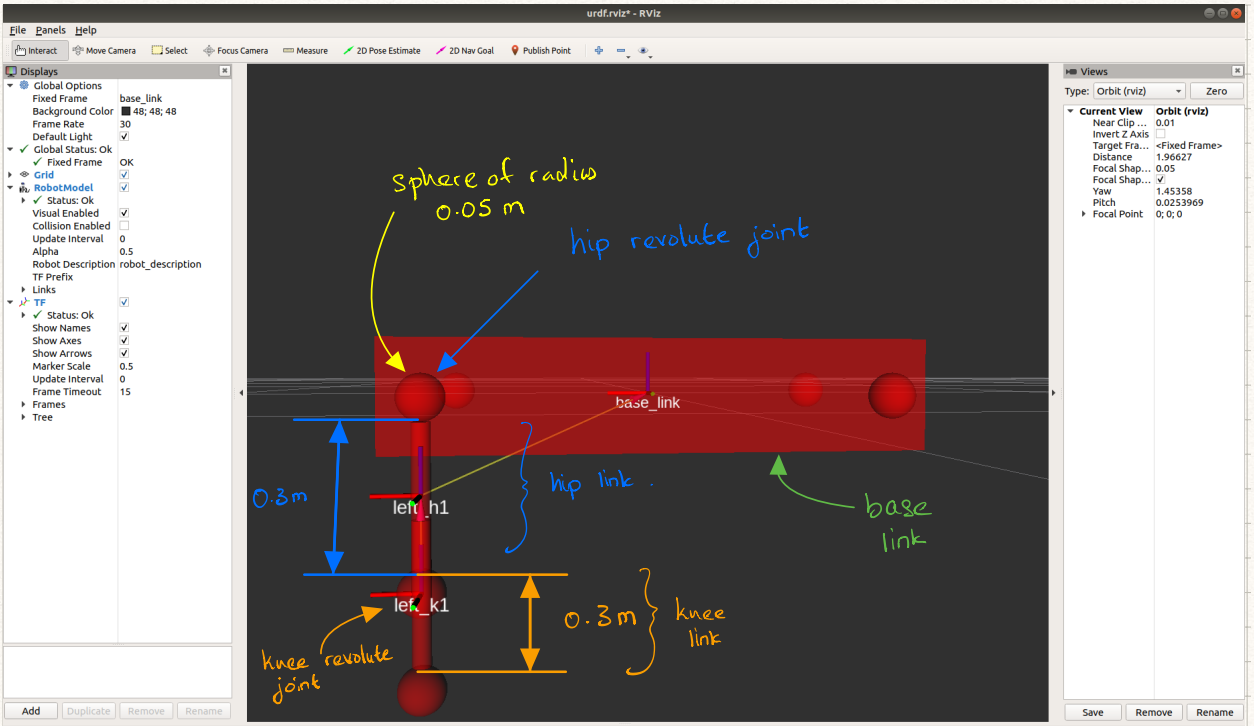
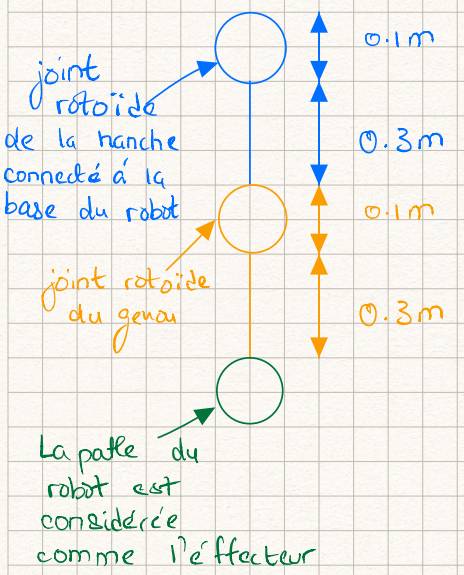
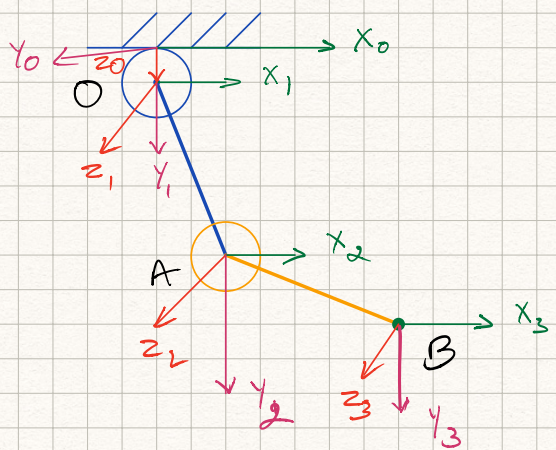


From above digram of the one_leg_robot, it can be represented as follows:



la représentation géométrique du modèle est comme suit:

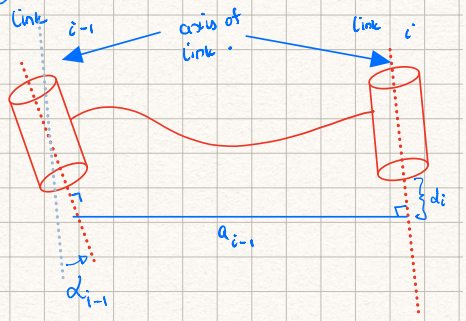


a_{i-1} • link length
↳ mutual perpendicular distance between axis of two joints.
• distance from z_i to z_{i+1} measured along x_i

α_{i-1} • link twist
↳ angle from axis $i-1$ to i
• angle from z_i to z_{i+1} measured about x_i

d_i • link offset
↳ offset distance of one link to the next (from common axis)
• Distance from x_{i-1} to x_i measured along z_i

θ_i • joint angle
↳ rotation of link with respect to its neighbourhood (along common axis)
• angle from x_{i-1} to x_i measured about z_i



d_i applies to prismatic joints

θ_i applies to revolute joints.

axis (i)	a_{i-1}	α_{i-1}	d_i	θ_i
1	0	0	0	θ_1
2	0.3	0	0.3	θ_2
3	0.3	0	0	θ_3