Frame {s} is our fixed frame, i.e. the spatial frame

The hip frame {H} is translated by l_0 and rotated by θ_0 with respect to frame $\{s\}$

The knee frame {K} is translated by l_1 and rotated by θ_1 with respect to frame $\{H\}$

The foot frame {F} is translated by l_2 with respect to frame $\{K\}$