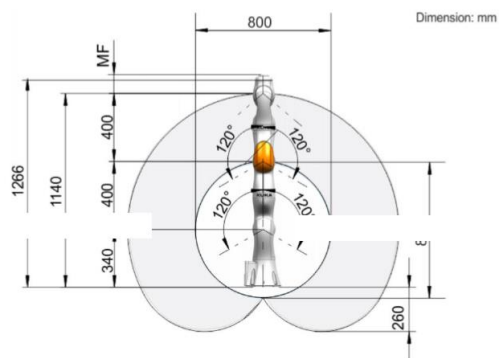


Question: Consider the following **KUKA LBR iiwa 7 R800** Light Weight robotic arm with the given dimensions and rotation axes:

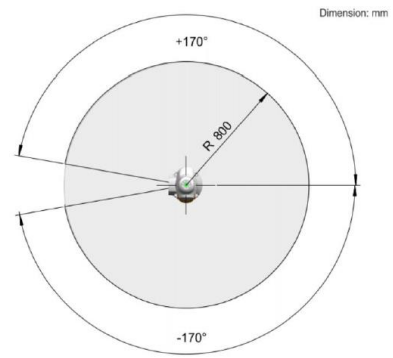
- Assign the coordinate frames of the robot manipulator and create the DH-table.
- Based on the D-H table, write a MATLAB script to compute the forward kinematic model using MATLAB Symbolic Toolbox or Live Editor.
- Verify the forward kinematics model (e.g. check the tip-point position for given joint variables)



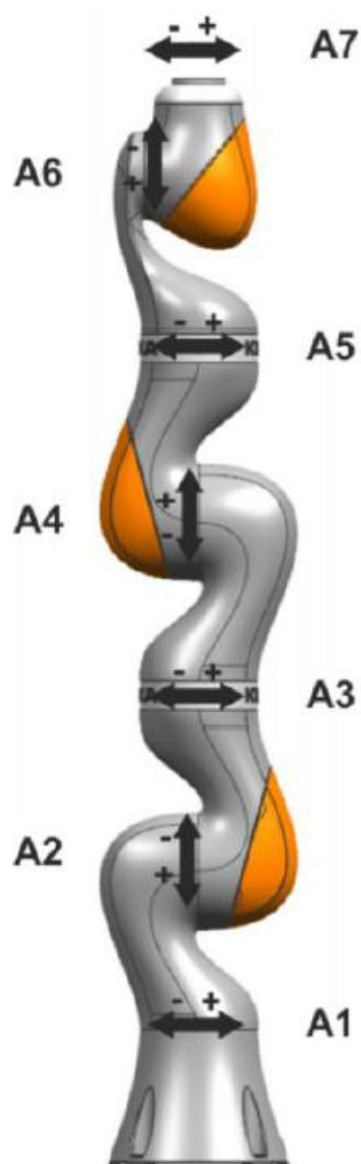
KUKA LBR iiwa 7 R800 Light Weight Robot Arm



KUKA LBR iiwa 7 R800 working envelope, side view



KUKA LBR iiwa 7 R800 working envelope, top view



Axis numbering for KUKA LBR iiwa 7 R800