



i	link twist α_{i-1}	link length a_{i-1}	link offset d_i	joint angle θ_i
1	0	0	0	θ_1
2	90°	l_1	0	$\theta_2 + 90^\circ$
3	90°	0	d_3	90°
4	0	0	0	θ_4
5	90°	0	0	$\theta_5 + 90^\circ$
6	90°	l_5	0	θ_6
7	0°	0	0	0°)

not a lot
of 0's

redundant,
ignoring
manipulator
complexity















