



Kinematic scheme of the robot

- Transformation matrix for the direct kinematic of the robot is $H = T(z, l_1)R(z, q_1)T(y, l_2)R(x, q_2)T(z, l_3)R(x, q_3)T(z, l_4)T(y, l_5)R(y, q_4)R(x, q_5)R(y, q_6)T(y, l_6)$ where T - translation matrix along one of axis on the defined length, R - rotation matrix around one of axis on defined angle