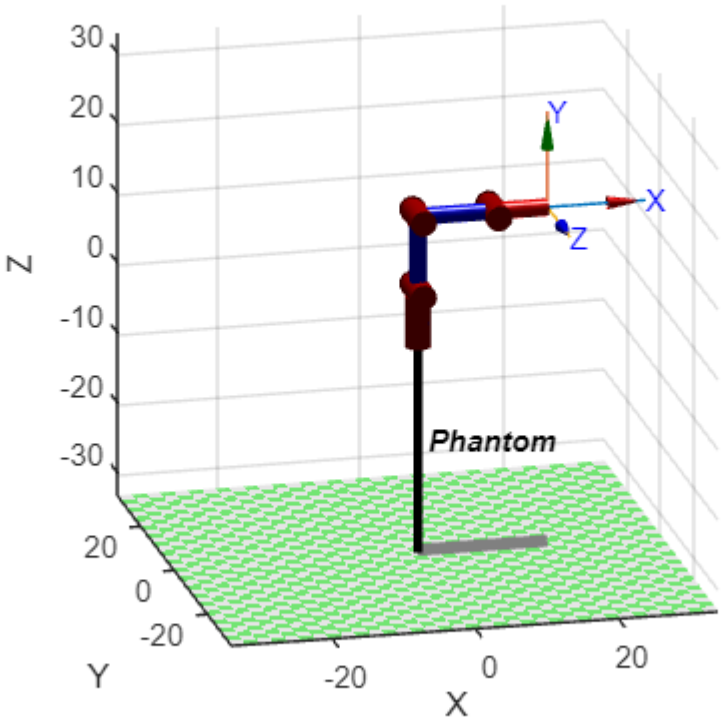
```
%Links = ([theta d a alpha sigma (tipo de articulación) mHD Offset])
L1 = Link ('revolute', 'd', 4.4, 'a', 0, 'alpha', pi/2 , 'offset', 0); %Eslabón 1
L2 = Link ('revolute', 'd', 0, 'a', 10.6, 'alpha', 0 , 'offset', pi/2);
L3 = Link ('revolute', 'd' , 0, 'a', 10.6, 'alpha', 0, 'offset', -pi/2);
L4 = Link ('revolute', 'd' , 0, 'a', 7.5, 'alpha', 0, 'offset', 0);
Phantom = SerialLink([L1 L2 L3 L4]', 'name', 'Phantom')
```

```
Phantom =

Phantom:: 4 axis, RRRR, stdDH, slowRNE
+---+-----------+-----------+-----------+-----------+-----------+
| j |     theta |         d |         a |     alpha |    offset |
+---+-----------+-----------+-----------+-----------+-----------+
|  1|         q1|        4.4|          0|     1.5708|          0|
|  2|         q2|          0|       10.6|          0|     1.5708|
|  3|         q3|          0|       10.6|          0|    -1.5708|
|  4|         q4|          0|        7.5|          0|          0|
+---+-----------+-----------+-----------+-----------+-----------+
```

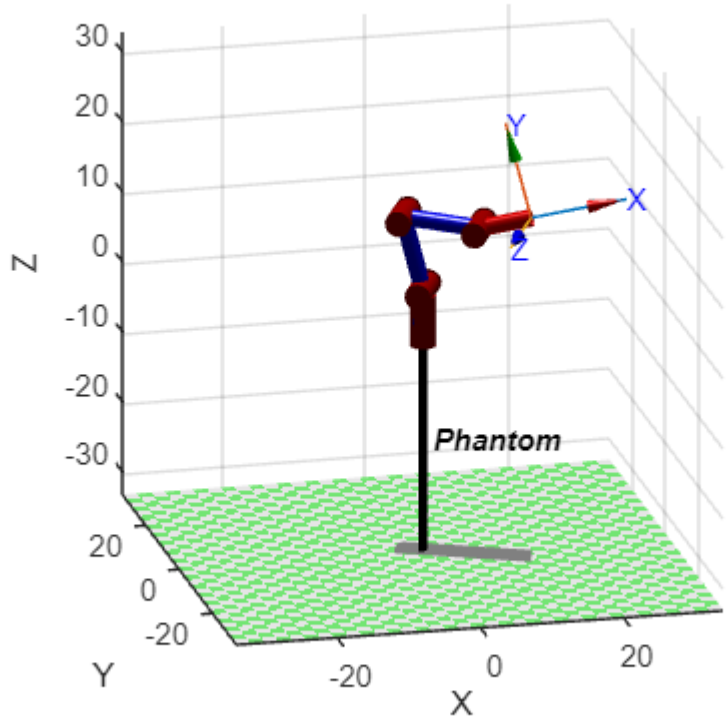
```
Phantom.plot([0 0 0 0])
view([-13.1 17.9])
```




```
help SerialLink/base
```

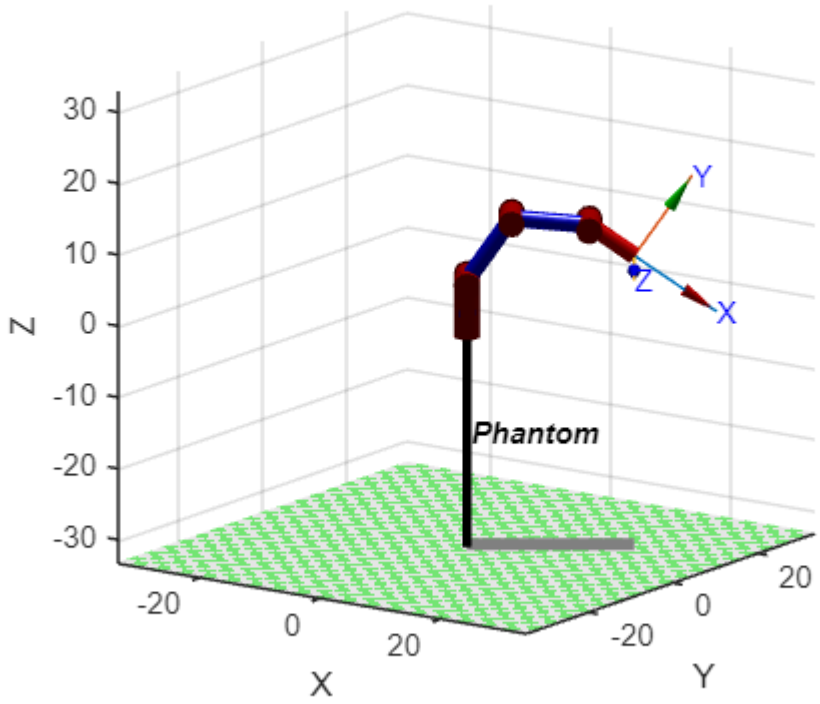
SerialLink/base is a property.

```
%primera posición
Phantom.plot([-25, 15, -20, 20]*(pi/180))
```

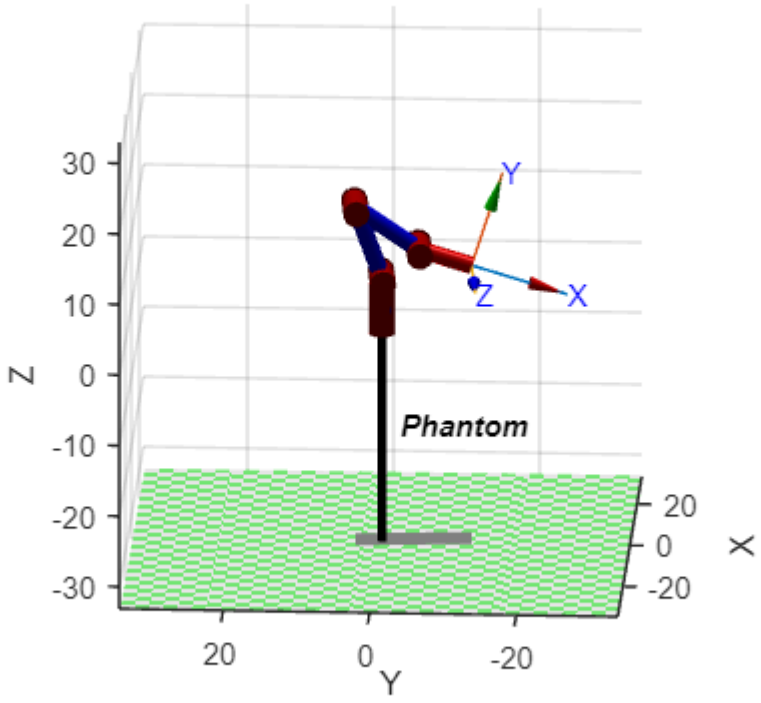



```
%Segunda posición
Phantom.plot([35,-35, 30, -30]*(pi/180))

view([35.2 14.2])
```

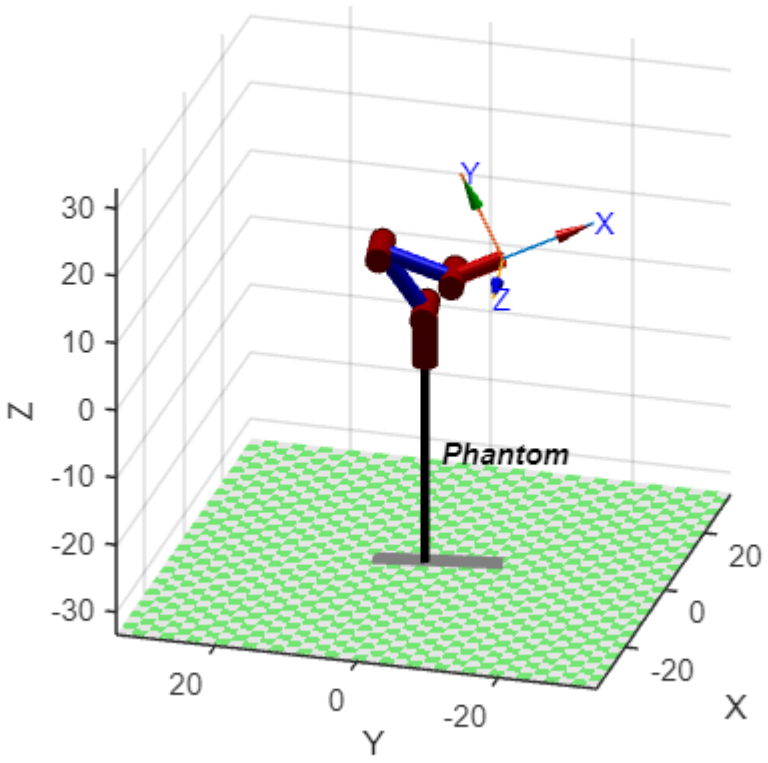



```
%Tercera posición
Phantom.plot([-85, 20, -55, 17]*(pi/180))
view([-87.2 16.3])
```




```
%Cuarta posición
Phantom.plot([-80, 35, -55, 45]*(pi/180))

view([-74.4 23.8])
```


Y
X
Z
30
20
10
0
-10
-20
-30
Z
Phantom
20
0
-20
Y
20
0
-20
X