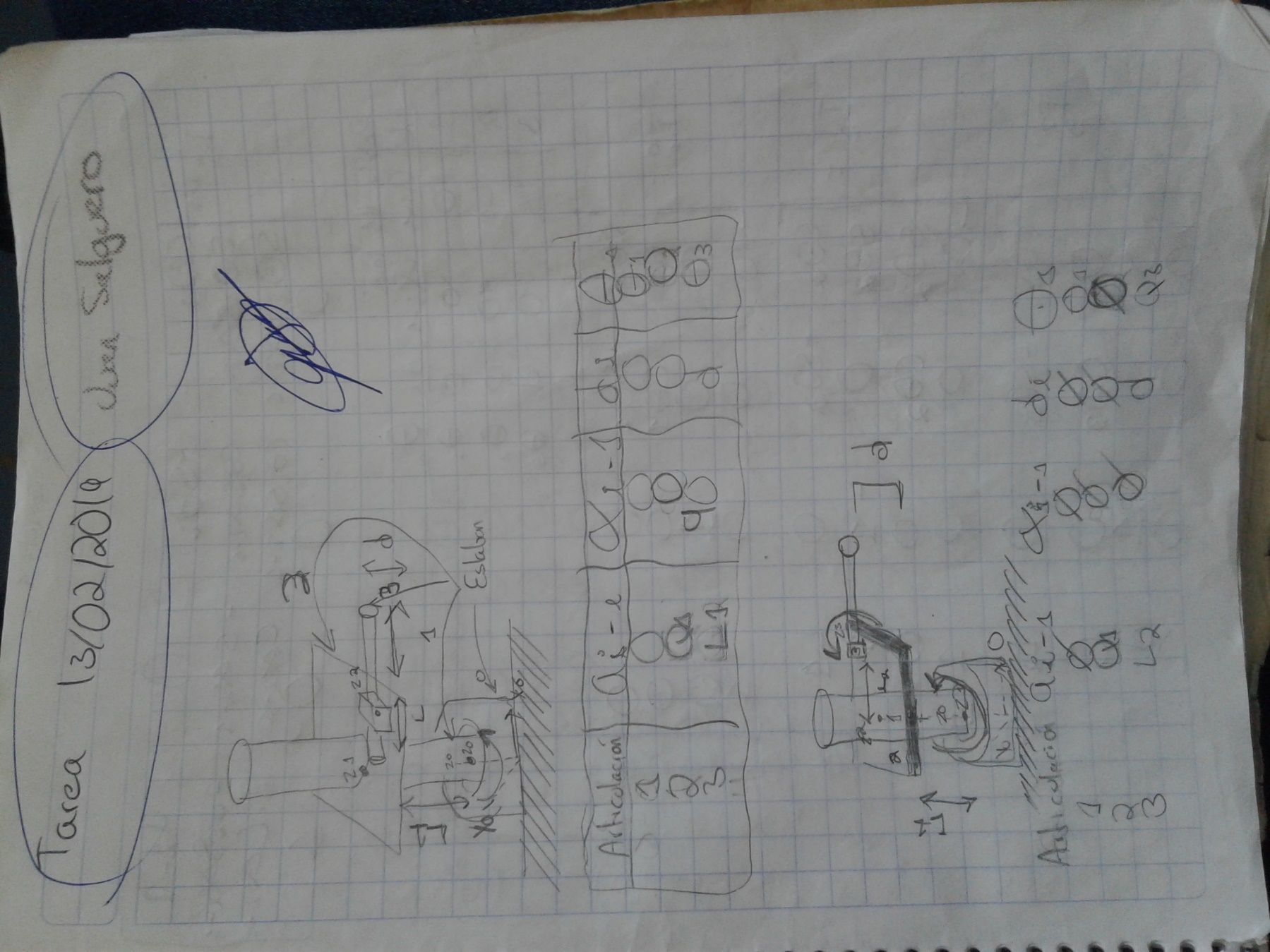
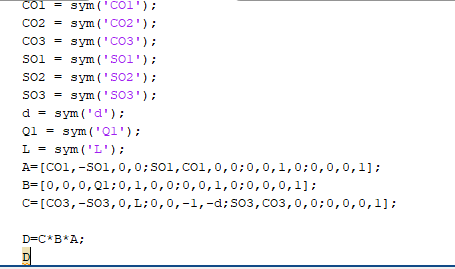
Tarea 5

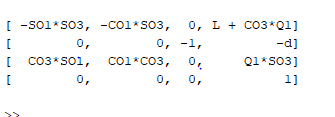
Salguero Hernández Juan Pablo

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**Obtención de la cinemática directa de Robots**





|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| Eslabón |  |  | d |  |
| 1 | **0** | **0** | **0** |  |
| 2 | **Q1** | **0** | **0** | **0** |
| 3 |  | **90** | **d** |  |

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| Eslabón |  |  | d |  |
| 1 | **0** | **0** | **0** |  |
| 2 | **Q1** | **0** | **0** | **0** |
| 3 |  | **0** | **d** |  |

