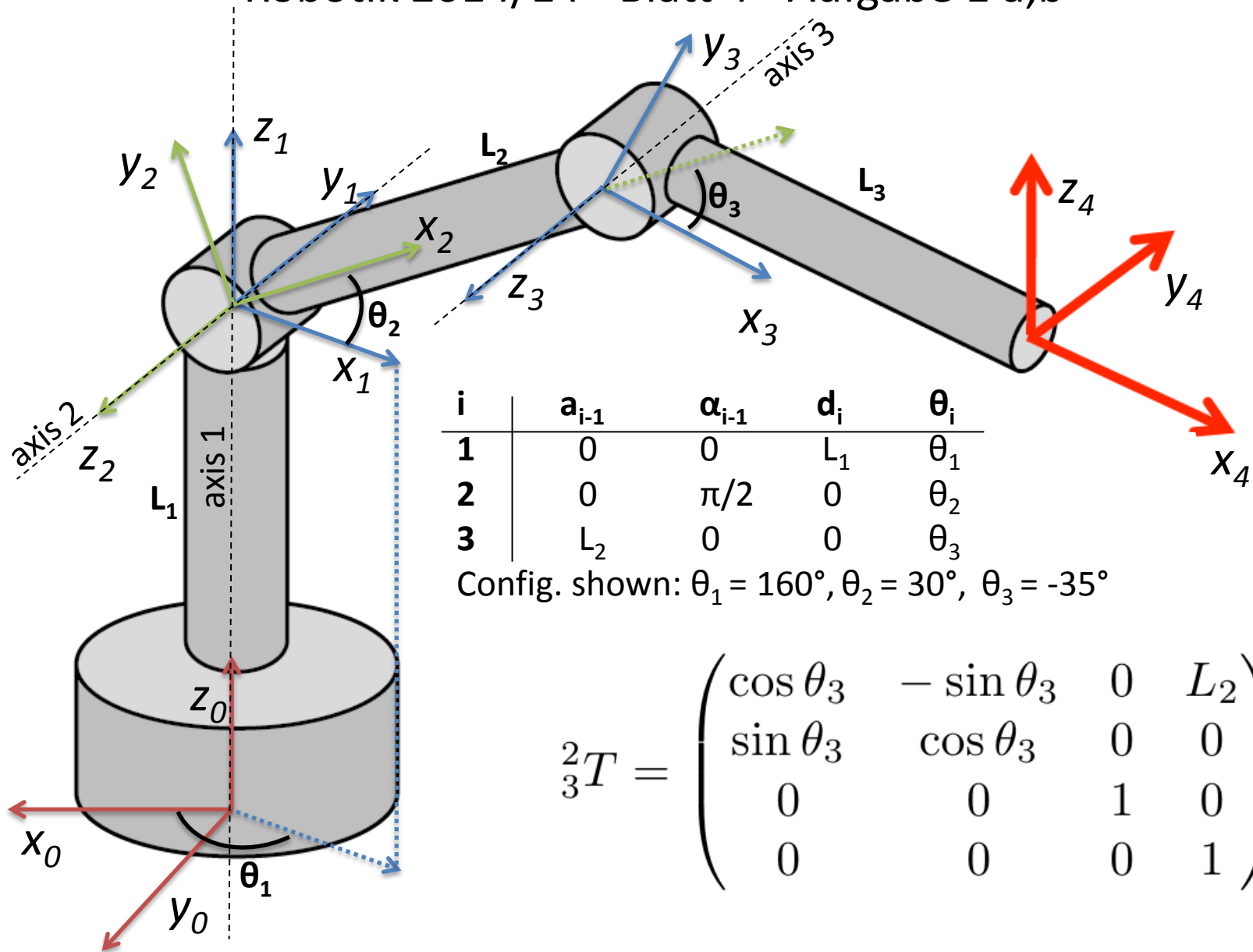


Robotik 2014/14 - Blatt 4 - Aufgabe 1 a,b



$${}^2_3T = \begin{pmatrix} \cos \theta_3 & -\sin \theta_3 & 0 & L_2 \\ \sin \theta_3 & \cos \theta_3 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}$$