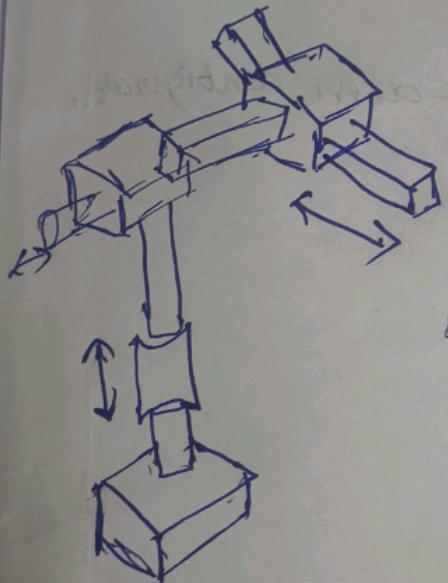
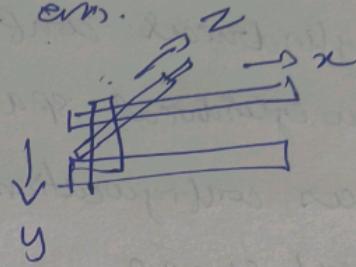


Robot classification.

Cartesian config, cylindrical config, Polar config, joint arm config.

Cartesian x-y-z arm.

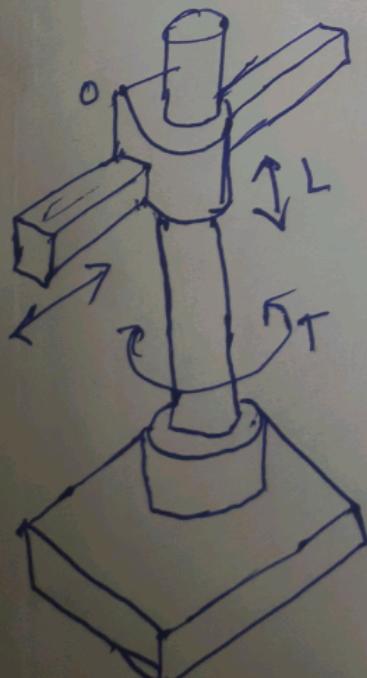


ability to do straight line motion
requiring large operating volume

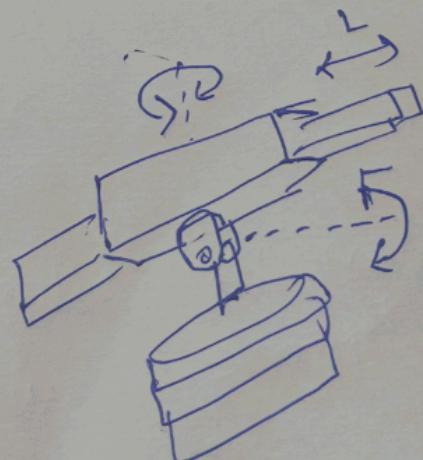
adv

disadv

Cylindrical configuration -



Polar configuration

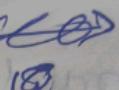


Purismatic L

Revolute R



Linear movement



Rotation.

Linear joints - Type C joint \Rightarrow parallel to each other

Orthogonal joints - Type O joints \Rightarrow \perp to each other

Rotational joints - Type R joints \perp to joining line

Twisting joint - Type T joint \parallel to body axis

Revolving joint - Type V joint.

Robot Reach

- For a cartesian configuration the reach is a rectangle-type space.
- For a cylindrical configuration the reach is a hollow cylindrical space
- For a polar configuration the reach is part of a hollow spherical shape
- Robot reach for a jointed-arm configuration does not have a specific shape