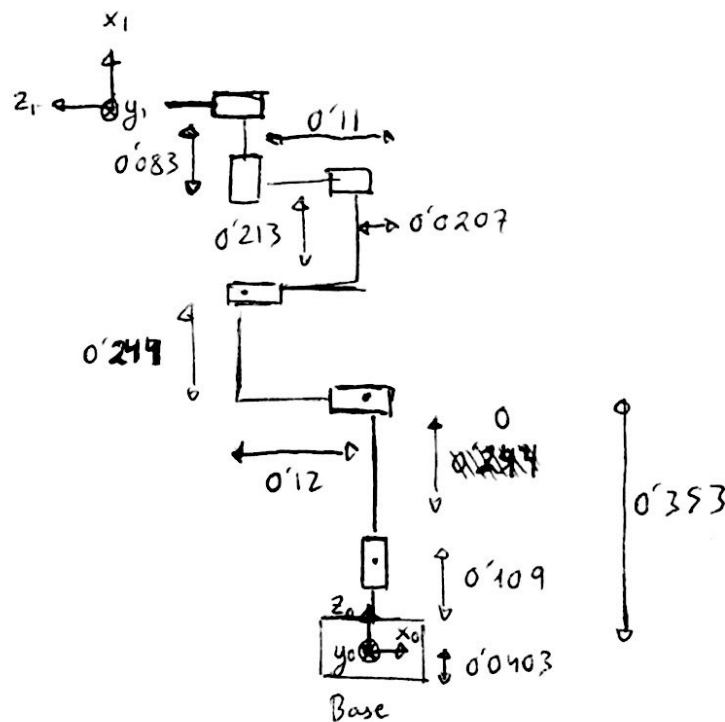# Forward Kynematics

1- Step: Get the axis and position of each joint $(a \& q)$.

2- Step: Get the screw axis for each joint.

     → If prismatic : $S = [0, 0, 0, axis]$

     → If revolute: $S = [axis, -[axis] \cdot q]$



3- Step: Get Pose

$$T_1^0 = e^{[S_1] \theta_1} \cdot e^{[S_2] \theta_2} \cdot e^{[S_3] \theta_3} \cdot e^{[S_4] \theta_4} \cdot e^{[S_5] \theta_5} \cdot e^{[S_6] \theta_6} \cdot M$$