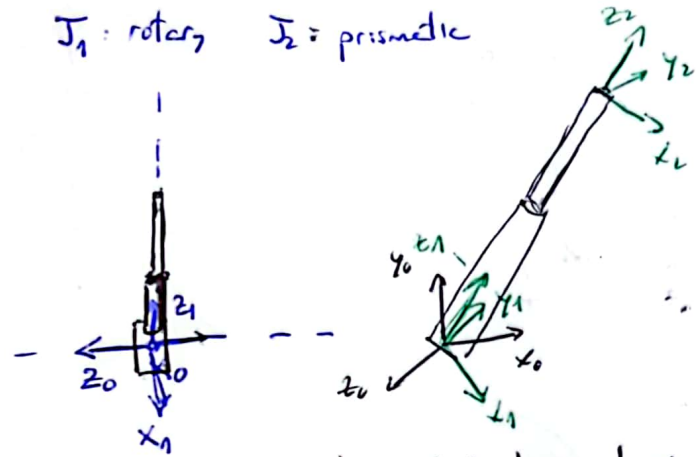


ASSISTIVE ROBOTICS

$${}^{i-1}T_i = \text{Rot}_{z_i}(\theta_i) \text{Trans}_{z_i}(d_i) \text{Trans}_{x_i}(a_i) \text{Rot}_{x_i}(\alpha_i)$$

J_1 : rotary J_2 : prismatic



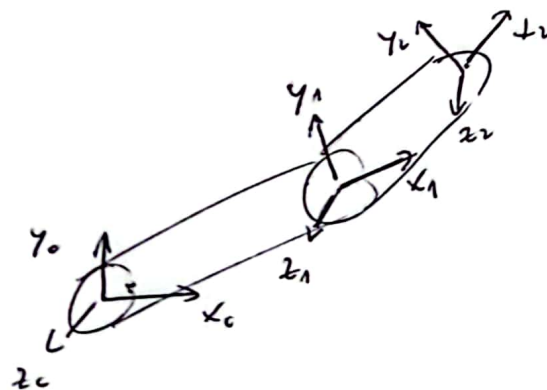
	θ_i	d_i	a_i	α_i
1	-60°	0	0	-90°
2	0		0	0

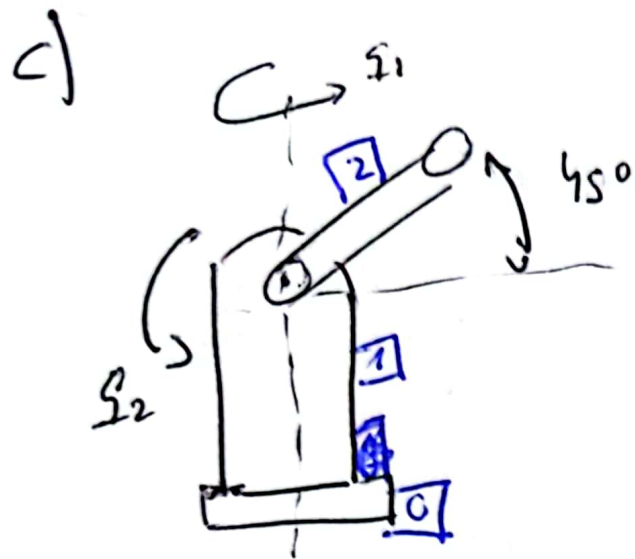
$l_1 + l_2 + q_2$

$l_1 + q_2$

J_1 : rotary J_2 : rotary

	θ_i	d_i	a_i	α_i
1	$q_1 + 20^\circ$	0	l_1	0
2	$q_2 + 40^\circ$	0	l_2	0





	θ_i	d_i	a_i	α_i
1	q_1	l_1	0	90°
2	$45 + q_2$	0	l_2	0

