
```

clear;
clc;

dh_parametri = [0 0 0.08 0;% a=0m,  $\alpha=0^\circ$ , d=0,  $\theta=0$ 
                0 pi/2 0.04 0; % a=0.12m,  $\alpha=0^\circ$ , d=0,  $\theta=0$ 
                0.18 0 0 0;
                0.12 0 0 0;
                0.06 0 0 0];% a=0.06m,  $\alpha=0^\circ$ , d=0,  $\theta=0$ 

robot = rigidBodyTree('DataFormat','row');
robot.Gravity = [0 0 -9.81];

%pravim kuciste
kuciste = rigidBody('kuciste');
rotKucista = rigidBodyJoint('rotKucista', 'fixed');
setFixedTransform(rotKucista, dh_parametri(1,:), 'dh');
kuciste.Joint = rotKucista;
addBody(robot, kuciste, 'base');
kuciste.Mass = 0.16990036;
kuciste.CenterOfMass = [0 0 0];
kuciste.Inertia = [0.0001061875 0.0001061875 0.000212375 0 0 0];

%pravim rame i nosac za motor ramena
nosacMotoral = rigidBody('nosacMotoral');
rame = rigidBodyJoint('rame', 'revolute');
setFixedTransform(rame, dh_parametri(2,:), 'dh');
nosacMotoral.Joint = rame;
addBody(robot, nosacMotoral, 'kuciste');
nosacMotoral.Mass = 0;
nosacMotoral.CenterOfMass = [0 0 0];
nosacMotoral.Inertia = [0 0 0 0 0 0];

%pravim lakat i nadlakticu
nadalaktica = rigidBody('nadalaktica');
lakat = rigidBodyJoint('lakat', 'revolute');
setFixedTransform(lakat, dh_parametri(3,:), 'dh');
lakat.PositionLimits = deg2rad([0, 180]);
nadalaktica.Joint = lakat;
addBody(robot, nadalaktica, 'nosacMotoral');
nadalaktica.Mass = 0.154383751;
nadalaktica.CenterOfMass = [0.09 0 0];
nadalaktica.Inertia = [0 (nadalaktica.Mass * dh_parametri(3,1)^2)/3
(nadalaktica.Mass * dh_parametri(3,1)^2)/3 0 0 0];

%pravim zglob sake i podlakticu
podlaktica = rigidBody('podlaktica');
zglobSake = rigidBodyJoint('zglobSake', 'revolute');
setFixedTransform(zglobSake, dh_parametri(4,:), 'dh');
zglobSake.PositionLimits = deg2rad([-120, 120]);
podlaktica.Joint = zglobSake;
addBody(robot, podlaktica, 'nadalaktica');

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podlaktica.Mass = 0.13129731;
podlaktica.CenterOfMass = [0.06 0 0];
podlaktica.Inertia = [0 (podlaktica.Mass * dh_parametri(4,1)^2)/3
(podlaktica.Mass * dh_parametri(4,1)^2)/3 0 0 0];

%pravim end eff
endEff = rigidBody('endEff');
kraj = rigidBodyJoint('kraj', 'revolute');
setFixedTransform(kraj, dh_parametri(5, :), 'dh');
endEff.Joint = kraj;
addBody(robot, endEff, 'podlaktica');
endEff.Mass = 0.02216277;
endEff.CenterOfMass = [0.06 0 0];
endEff.Inertia = [0 (endEff.Mass * dh_parametri(5,1)^2)/3 (endEff.Mass *
dh_parametri(5,1)^2)/3 0 0 0];

konfigg = [0 0 pi/6 0];
show(robot, konfigg)

```

ans =

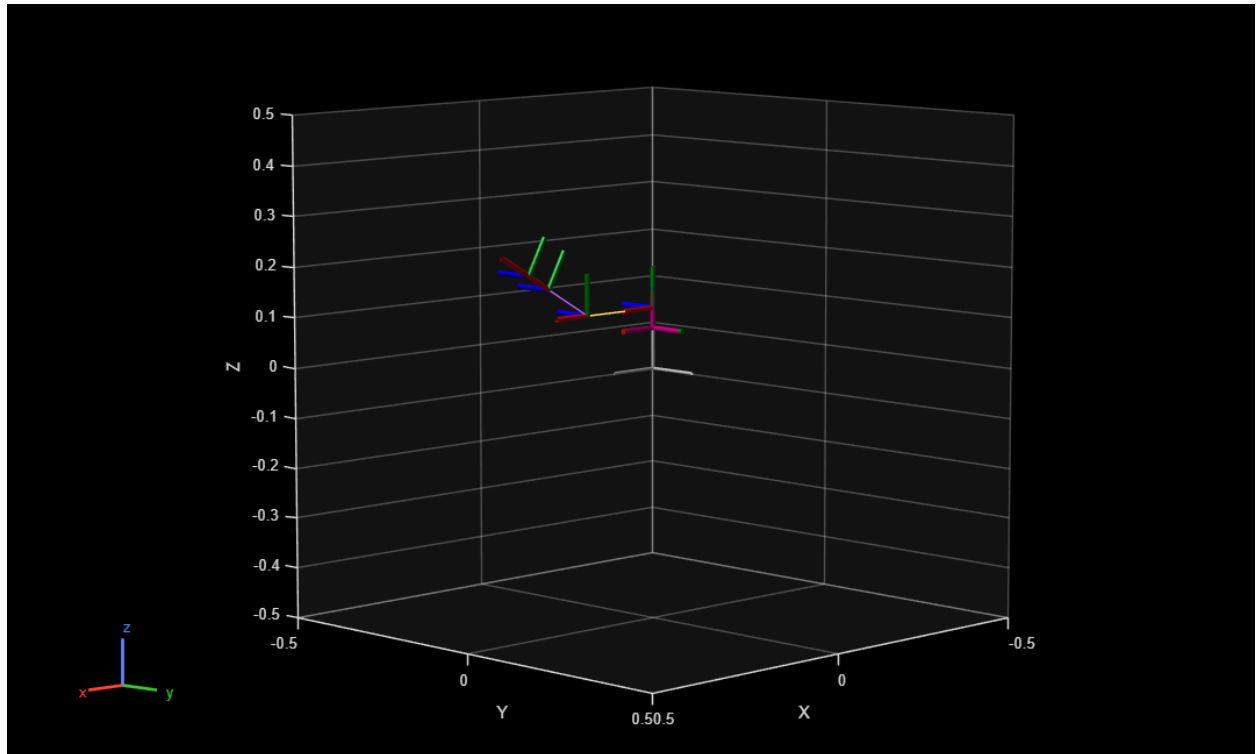
Axes (Primary) with properties:

```

        XLim: [-0.5000 0.5000]
        YLim: [-0.5000 0.5000]
        XScale: 'linear'
        YScale: 'linear'
    GridLineStyle: '-'
    Position: [0.1300 0.1100 0.7750 0.8150]
        Units: 'normalized'

```

Use GET to show all properties



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