

mdl_puma560Craig Create model of Puma 560 manipulator

MDL_PUMA560AKB is a script that creates the workspace variable p560Craig which describes the kinematic of a Unimation Puma 560 manipulator modified DH conventions used in the book: Introduction to Robotics by John Craig.

Also defines the workspace vectors: qz zero joint angle configuration qr vertical 'READY' configuration qstretch arm is stretched out in the X direction

Notes:: - SI units are used

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modified by Caterina Moll & Marc Guitart

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```
clear L
%           theta      d      a      alpha
L(1) = Link([ 0      0      0      0 ], 'modified');
L(2) = Link([ 0      7      0      -pi/2 ], 'modified');
L(3) = Link([ 0      0      2      0 ], 'modified');
%
% some useful poses
%
qz = [0 0 0]; % zero angles, L shaped pose
qr = [0 0 pi/2]; % ready pose, arm up
qstretch = [0 0 pi/2 pi/6]; % horizontal along x-axis
qn=[0+pi/10 0-pi/10 -pi/2+pi/5]; % horizontal along x-axis

p560Craig = SerialLink(L, 'name', 'Puma560-Craig',...
    'manufacturer', 'Unimation',...
    'comment', 'Craig');
clear L
```