```
%init the robot 3R
clear
mdl_3link3d
R3
```

```
R3 =

3link 3D:: 3 axis, RRR, stdDH, slowRNE
 - Spong p106;
+---+-----------+-----------+-----------+-----------+-----------+
| j |     theta |         d |         a |     alpha |    offset |
+---+-----------+-----------+-----------+-----------+-----------+
|  1|        q1|          1|          0|     1.5708|          0|
|  2|        q2|          0|          2|          0|          0|
|  3|        q3|          0|          3|          0|          0|
+---+-----------+-----------+-----------+-----------+-----------+
```

```
%result of joint angles
R3.plot([0,0,0])
```
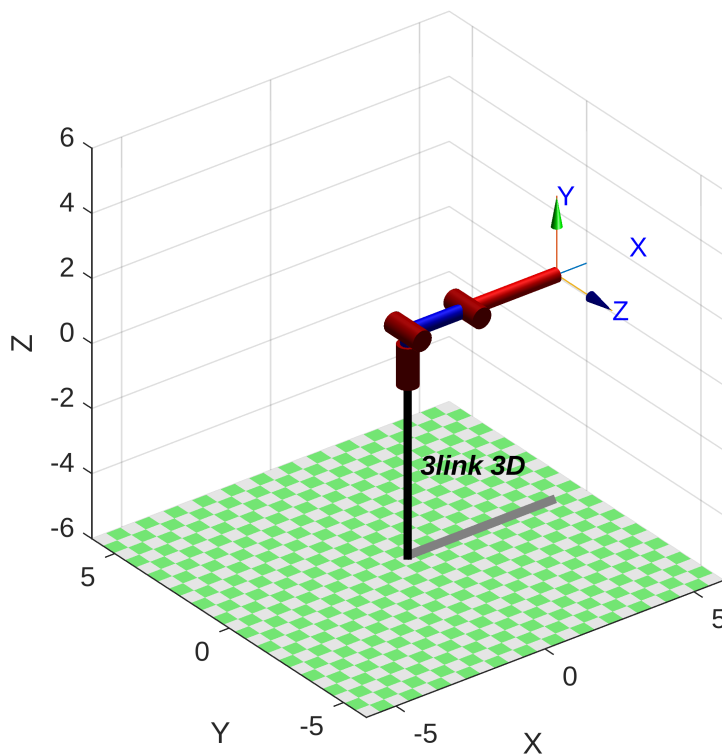


```
R3.fkine([0,0,0])
```

```
ans =
         1         0         0         5
         0         0        -1         0
```
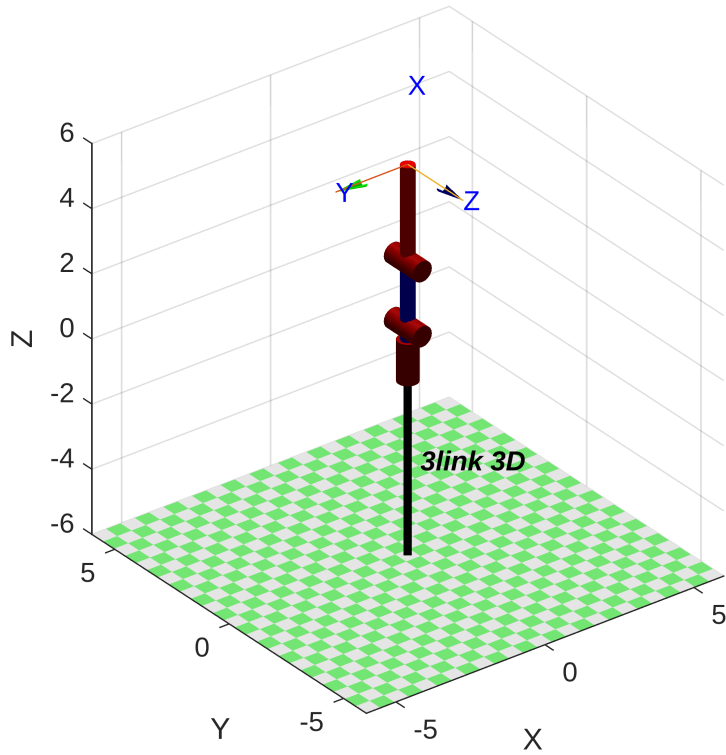
```
        0        1        0        1
        0        0        0        1
```

```
%result of joint angles
R3.plot([0,pi/2,0])
```



```
R3.fkine([0,pi/2,0])
```

```
ans =
        0       -1        0        0
        0        0       -1        0
        1        0        0        6
        0        0        0        1
```
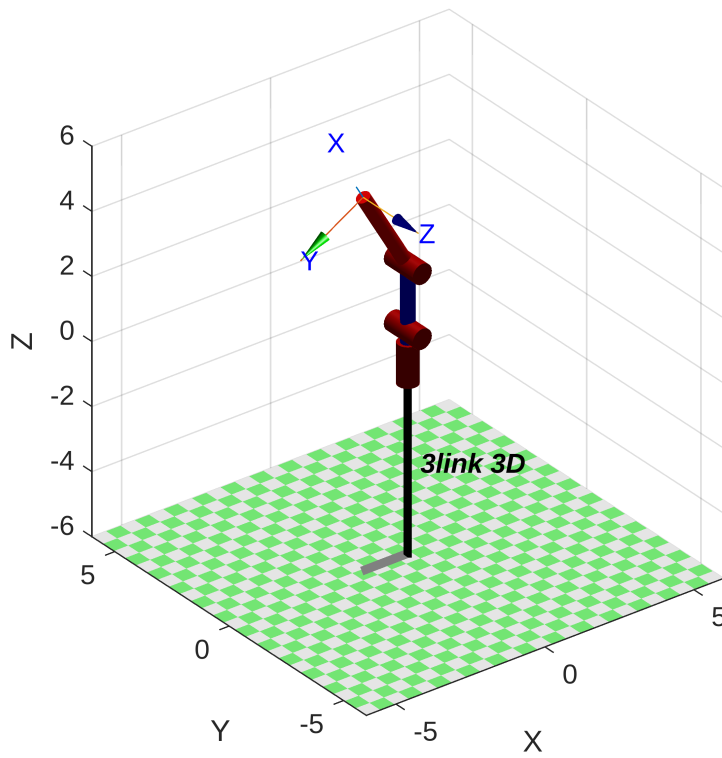
```
%result of joint angles
R3.plot([0,pi/2,pi/6])
```

3link 3D

```
R3.fkine([0,pi/2,pi/6])
```

```
ans =
   -0.5000   -0.8660        0     -1.5
        0        0       -1        0
    0.8660   -0.5000        0    5.598
        0        0        0        1
```