



Analyses

Time (s)

1.00

No of Steps

100

FKin

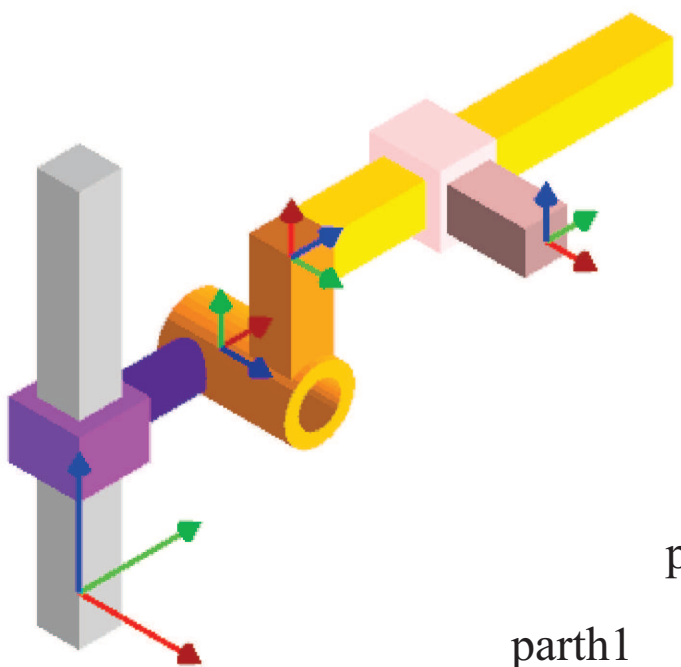
IDyn

IKin

FDyn

Gravity(m/s^2)

Links



Default Robots	Joint No	Joint Type	Joint Offset (b) m	Joint Angle (theta) deg	Link Length (a) m	Twist Angle (alpha) deg	Initial Value (JV) deg or m	Final Value (JV) deg or m
3	1	Prismatic	Variable	90	0,1	90	0,1	0,2
Select Robot	2	Revolute	0,05	Variable	0,08	90	90	180
PRP	3	Prismatic	Variable	90	0,08	90	0,1	0,2

Custom Robots

Virtual Robots

kon

nko

Visualize DH

Link Config

EE Config

Joint Trajectory

Select Joint

Joint1

Speed

Slow

Fast

Joint Offset

Joint Angle

Link Length

Twist Angle

Together

None

Base Frame to End-Effector