ECE 555 HW#4
Due: March 22nd (10:00 pm)

1. The Figure below is a RRPR robot. For this robot system:

   - Assign link frames [50 points]
   - Complete the Denavit-Hartenberg parameters [40 points]
   - Use the link parameters to compute the individual link transformation matrices for each joint and compute the individual transformation matrices [10 points]

2. Write a MATLAB script using the Robotics Toolbox to determine the location and orientation of the manipulator's end-effector where:
   a. Theta1, Theta2, and Theta 3 are 0
   b. All links are 1 unit [100 points]