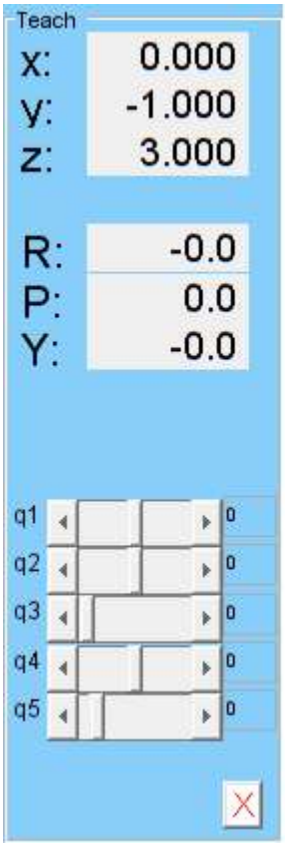
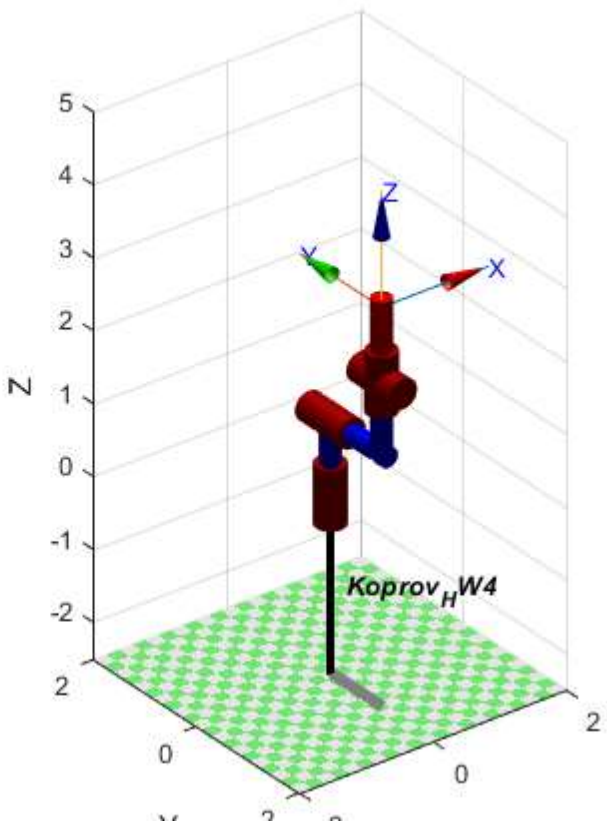
Contents


```
L(1) = Link([0 1 0 pi/2]);
L(2) = Link([0 1 0 -pi/2]);
L(3) = Link('prismatic', 'theta', 0, 'a', 0, 'alpha', pi/2,'offset', 1);
L(3).qlim = [0 1]
L(4) = Link([0 0 0 -pi/2]);
L(5) = Link([0 1 0 0]);
L(5).qlim = [0 0];


R1 = SerialLink(L, 'name', 'Koprov_HW4');
R1.plotopt = {'workspace' [-2,2,-2,2,-2.5,5]}

R1.teach
```

```
L =
Revolute(std):  theta=q1   d=1           a=0           alpha=1.571       offset=0
Revolute(std):  theta=q2   d=1           a=0           alpha=-1.571      offset=0
Prismatic(std): theta=0             d=q3 a=0           alpha=1.571       offset=1
Revolute(std):  theta=q4   d=0           a=0           alpha=-1.571      offset=0
Revolute(std):  theta=q5   d=1           a=0           alpha=0           offset=0

R1 =

Koprov_HW4:: 5 axis, RRPRR, stdDH, slowRNE
+---+-----------+-----------+-----------+-----------+-----------+
| j |     theta |         d |         a |     alpha |    offset |
+---+-----------+-----------+-----------+-----------+-----------+
|  1|         q1|          1|          0|     1.5708|          0|
|  2|         q2|          1|          0|    -1.5708|          0|
|  3|          0|         q3|          0|     1.5708|          1|
|  4|         q4|          0|          0|    -1.5708|          0|
|  5|         q5|          1|          0|          0|          0|
+---+-----------+-----------+-----------+-----------+-----------+
```





Position with all theta angles = 0

```
R1.fkine([0 0 0 0 0])
```

```
ans =
         1         0         0         0
         0         1         0        -1
         0         0         1         3
         0         0         0         1
```

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