4R

Denavit-Hartenberg notation

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
|  |  |  |  |  |
| 1 | 0 | 0 | 0 |  |
| 2 |  | 0 | 0 |  |
| 3 | 0 | Første arm del længde fra rotations punkt til rotations punkt | 0 |  |
| 4 |  | anden arm del længde fra rotations punkt til rotations punkt | 0 |  |

3,5cm tror jeg

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
|  |  |  |  |  |
| 1 | 0 | 0 | 0 |  |
| 2 |  | 0 | 0 |  |
| 3 |  | -15 | 0 |  |
| 4 | 0 | 3 | 0 |  |
| 5 | 0 | 15 | 0 |  |
| 6 |  | 6,5 | 0 |  |

https://dobot.dk/product/dobot-magician-lite/

<https://www.universal-robots.com/articles/ur/application-installation/dh-parameters-for-calculations-of-kinematics-and-dynamics/>

Et billede, der indeholder tekst

Automatisk genereret beskrivelse

Ifølge

Mrpt program

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
|  |  |  |  |  |
| 1 |  | 0 | 0 |  |
| 2 |  | 150 | 0 |  |
| 3 | 0 | 30 | 0 |  |
| 4 | 0 | 150 | 0 |  |
| 5 |  | 65 | 0 |  |
| 6 |  | 0 | 0 |  |

Formel 3.6 passer ikke med wikipedier

<https://en.wikipedia.org/wiki/Denavit%E2%80%93Hartenberg_parameters#Denavit%E2%80%93Hartenberg_matrix>

Final tabel tror jeg

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
|  |  |  |  |  |
| 1 | 0 | 0 | 0 |  |
| 2 |  | 0 | 0 |  |
| 3 |  | 150 | 0 |  |
| 4 | 0 | 30 | 0 |  |
| 5 | 0 | 150 | 0 |  |
| 6 |  | 65 | 0 |  |

Spørgsmål?

1. Figurtegning
2. Nok program, opfylder jeg opgavenformulering
3. Maple forward kinematik