50   LINK 1 O_1 LINK 2 O_2

z_1 z_2 LINK 3

x_1 x_2 20

Y_1 Y_2 d3=136

50   30   14

180   150   100

z_3 x_3 FLANGE

Z_0 Ø30

O_0 X_0

Y_0 BASE   Ø120

θ2=46°   θ3=43°   θ1=45°

y_1 x_1 Y_2 x_3 x_2 y_3 z_2 Y_0 X_0 Z_0

Example Position

1:4

Overview

Denavit-Hartenberg Parameters

LINK	d (mm)	θ (°)	a (mm)	α (°)
LINK 1	180	θ1	150	0
LINK 2	0	θ2	100	0
LINK 3	d3	θ3	0	180

Joint Limits

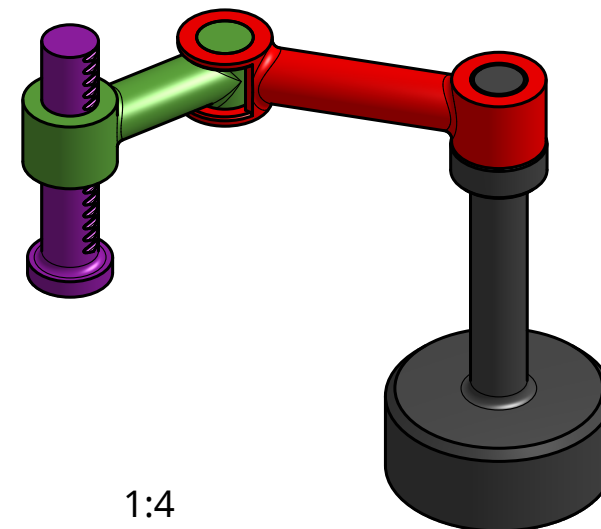| LINK	Min	Max
θ1	- 180 °	180 °
θ2	- 90 °	90 °
θ3	- 180 °	180 °
d3	0 mm	136 mm

UNLESS OTHERWISE SPECIFIED,
DIMENSIONS ARE IN MILLIMETERS

ANGULAR = ± 0 °

SURFACE FINISH

DO NOT SCALE DRAWING

BREAK ALL SHARP EDGES AND REMOVE BURRS

FIRST ANGLE PROJECTION

ROBOCLUB DTU

ROS2 Workshop

DTU Roboclub

TITLE

Simple SCARA robot model

SIZE A4	DWG NO. DTURC-SP-24-SCARA	REV. 1
SCALE 1:3	WEIGHT	SHEET 1 of 1