

```

clc;
clear;

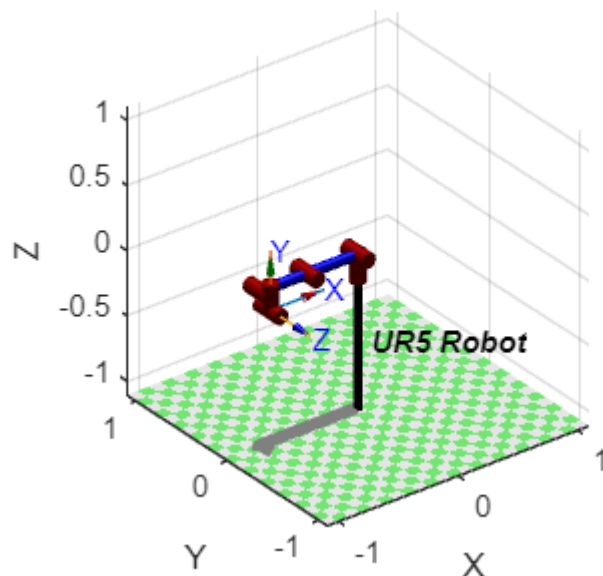
syms theta1 theta2 theta3 theta4 theta5 theta6
%theta1=pi/2; theta2=0; theta3=0; theta4=pi/2; theta5=-pi/2; theta6=0;

a1=0; a2 = -0.425; a3 = -0.3922; a4=0; a5=0; a6=0;
d1=0.08946 ; d2=0; d3=0; d4=0.1091; d5=0.09465 ; d6=0.0823;

RigidBody(1) = Link([0 d1 a1 pi/2]);
RigidBody(2) = Link([0 0 a2 0]);
RigidBody(3) = Link([0 d3 a3 0]);
RigidBody(4) = Link([0 d4 0 pi/2]);
RigidBody(5) = Link([0 d5 a5 -pi/2]);
RigidBody(6) = Link([0 0 0 0]);

UR5Robot = SerialLink(RigidBody);
UR5Robot.name = 'UR5 Robot';
UR5Robot.plot([0 0 0 0 0 0])

```



```

% DH parameters of the UR5 robot
fprintf(' DH table of parameters \n')

```

DH table of parameters

```
UR5Robot.display()
```

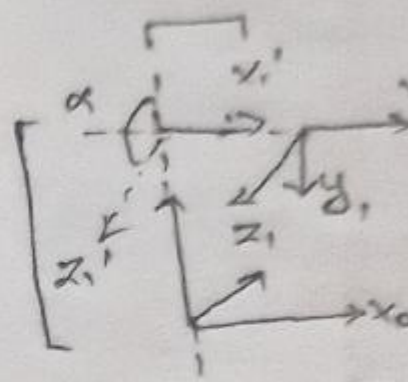
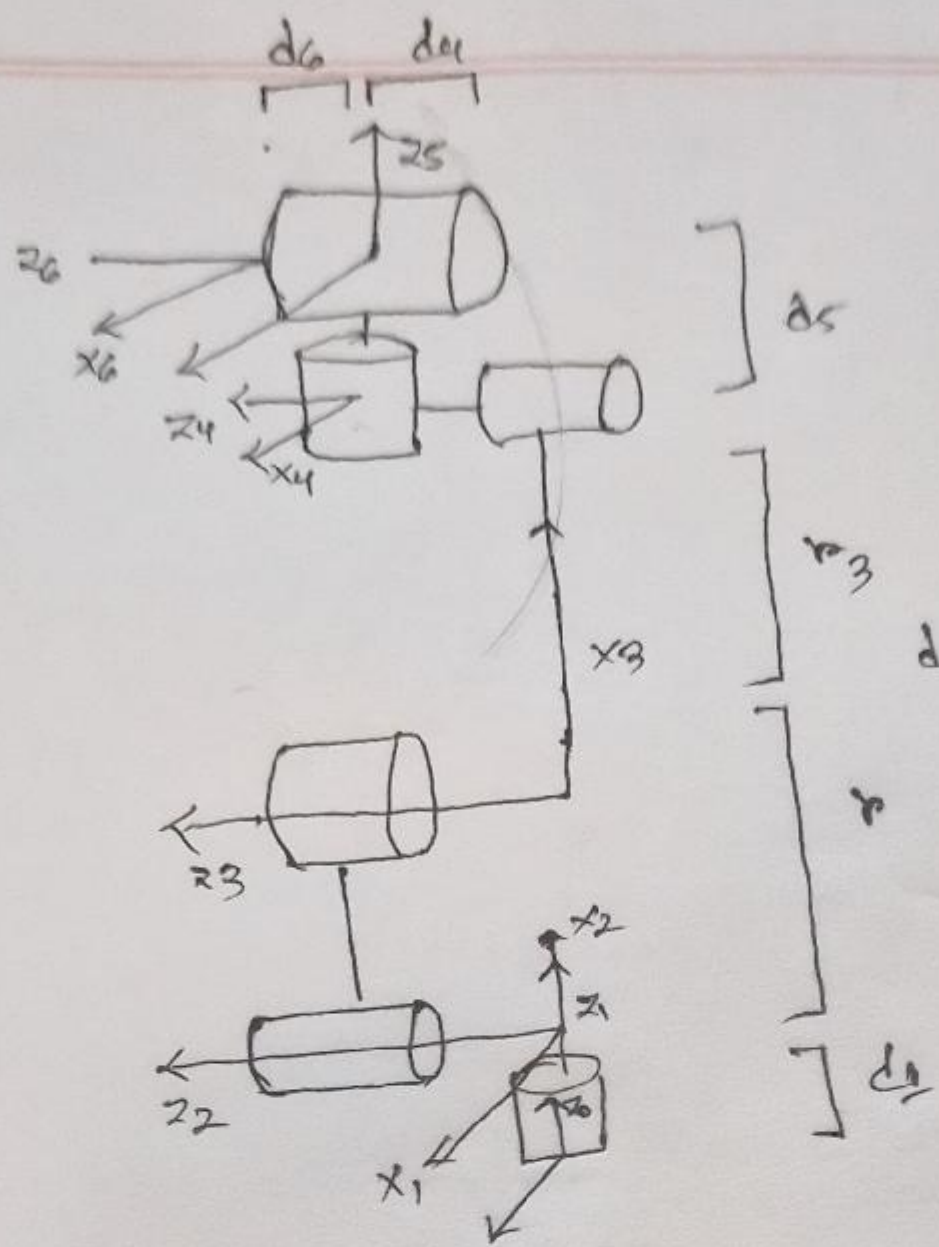
UR5Robot =

UR5 Robot:: 6 axis, RRRRRR, stdDH, slowRNE

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j	theta	d	a	alpha	offset
1	q1	0.08946	0	1.5708	0
2	q2	0	-0.425	0	0
3	q3	0	-0.3922	0	0
4	q4	0.1091	0	1.5708	0
5	q5	0.09465	0	-1.5708	0
6	q6	0	0	0	0

{(4)}



DH Parameters

i	θ_i	ϕ_i	d_i	θ_i^0
0	0	0	-	-
1	0	$\pi/2$	0.089	θ_1
2	0.425	0	0	θ_2