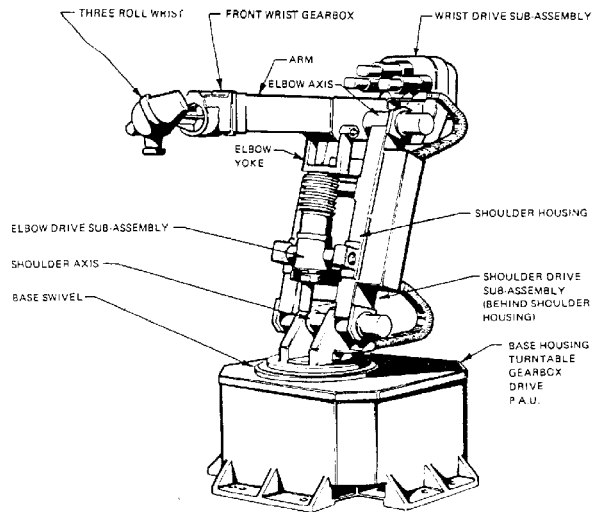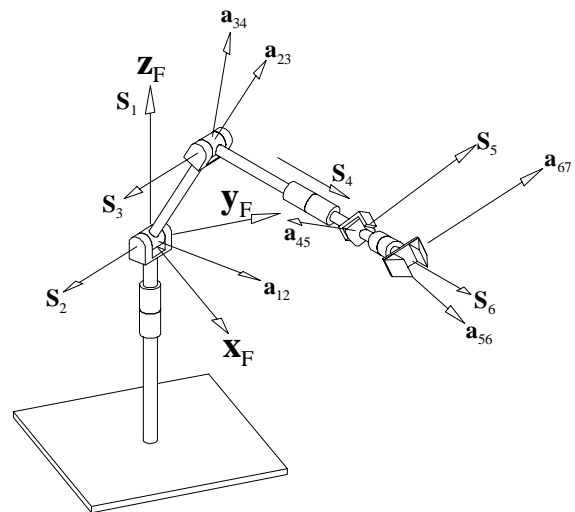## 11.4 Cincinnati Milacron T3-776 Manipulator

Figure 11.19: Cincinnati Milacron T3-776 Robot

Figure 11.20: Kinematic Model of Cincinnati Milacron T3-776 Robot

Table 11.6: Mechanism Parameters for the Cincinnati Milacron T3-776 Robot

link length, in.	twist angle, deg.	joint offset, in.	joint angle, deg.
$a_{12}= 0$	$\alpha_{12}= 90$		$\varphi_1=$ variable
$a_{23}= 44$	$\alpha_{23}= 0$	$S_2= 0$	$\theta_2=$ variable
$a_{34}= 0$	$\alpha_{34}= 90$	$S_3= 0$	$\theta_3=$ variable
$a_{45}=0$	$\alpha_{45}= 61$	$S_4= 55$	$\theta_4=$ variable
$a_{56}=0$	$\alpha_{56}= 61$	$S_5= 0$	$\theta_5=$ variable
			$\theta_6=$ variable