



	1	2	3	4	5	6
θ z 축회전	0	-90°	0	-90°	0	0
d z 축이동	d_1	0	0	d_4	d_5	d_6
a x 축이동	0	$-a_2$	$-a_3$	0	0	0
α x 축회전	90°	0	0	90°	-90°	0