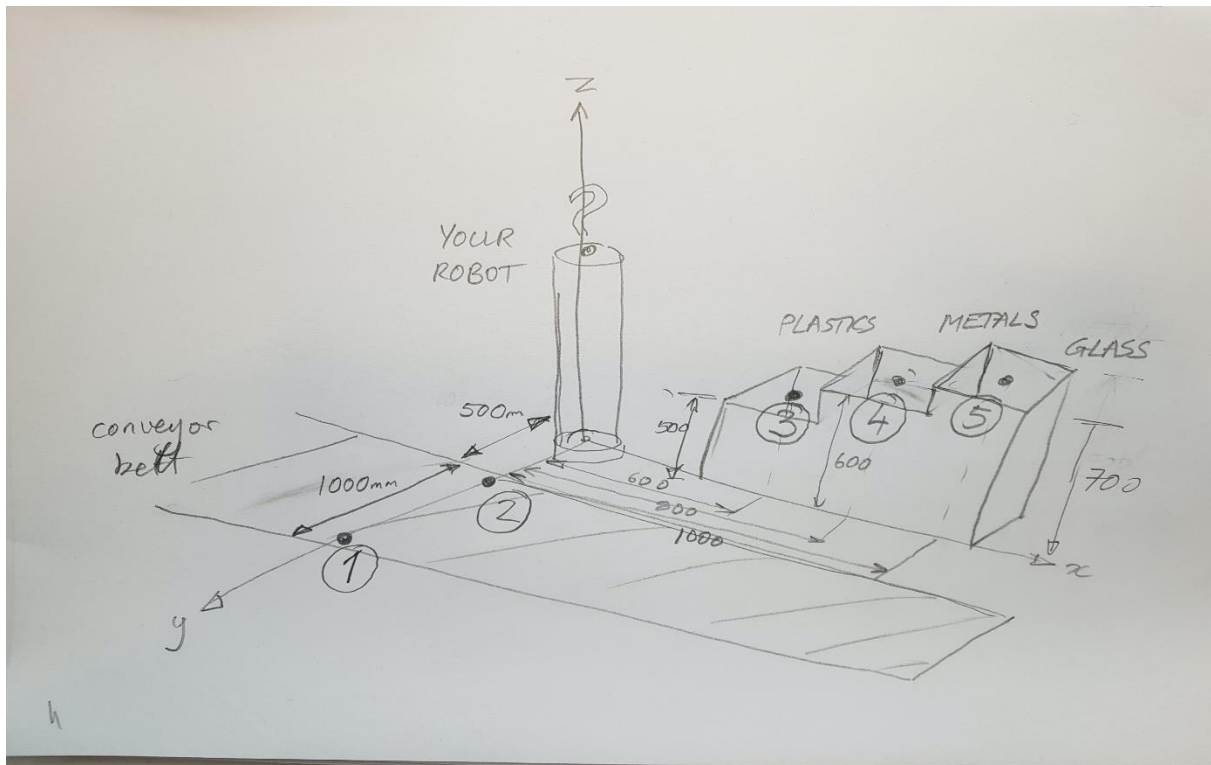


MODELLING A ROBOT MANIPULATOR

Solomon Ayansola M00881460

Video Link: <https://www.youtube.com/watch?v=IoMPpkF0tuU&t=28s>

TASK

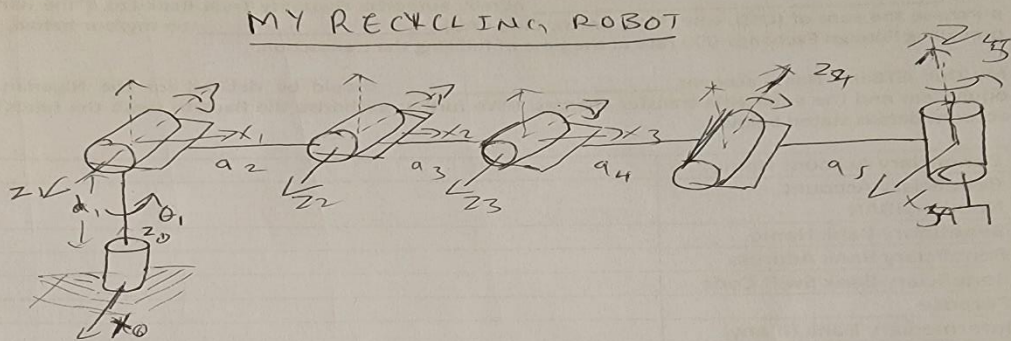


DH PARAMETER

DH Parameter.

| Link | d_i | a_i | α_i | θ_i |
|-------|-------|-------|------------|------------|
| L_1 | 0.1 | 0 | $\pi/2$ | θ_1 |
| L_2 | 0 | 0.3 | 0 | θ_2 |
| L_3 | 0 | 0.2 | 0 | θ_3 |
| L_4 | 0 | 0.35 | 0 | θ_4 |
| L_5 | 0 | 0.6 | $-\pi/2$ | θ_5 |
| L_6 | 0 | 0 | 0 | θ_6 |

MODEL AND JOINT LIMITS



Joint Limits (radians)

Joint 1 $\Rightarrow -\pi/2$ and $\pi/2$

Joint 2 $\Rightarrow 0$ and 0.7π

Joint 3 $\Rightarrow -\pi/2$ and 0

Joint 4 $\Rightarrow -\pi$ and 0

Joint 5 $\Rightarrow -\pi$ and 0

Joint 6 $\Rightarrow -\pi/2$ and $\pi/2$