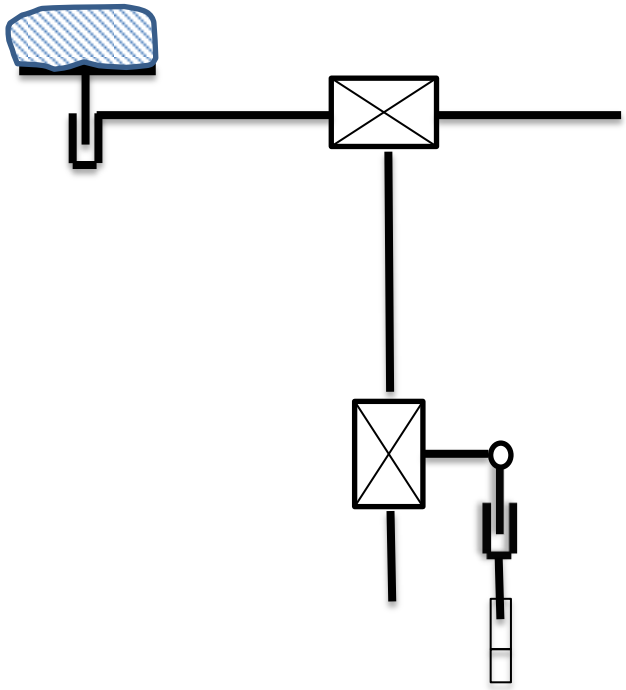
1. Structure RPPRR



Link No.	θ	d	a	α	Motion range in joints
1					
2					
3					
4					
5					

Values of the model constants

Geometrical model of a manipulator

Schedule of the project class

During the class:

1. The kinematic diagram of the manipulator presented on the opposite page should be sketched on a separate sheet of paper. The coordinate frames should be drawn and the table of the geometrical model parameters should be prepared and filled.
2. The elaborated geometrical model should be presented to the tutor for acceptance.
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4. Prepare and run a script that produces matrices 0T3, 3Te and pa vector in a symbolic, simplified form (study the instruction: Geometrical manipulator modelling).
5. Write down the above-mentioned matrices below.

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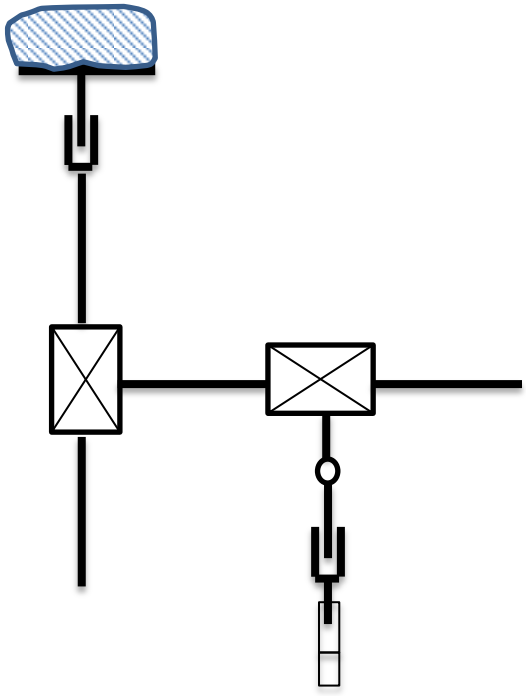
Geometrical model matrices: ${}^{0}\underline{\mathbf{T}}_{3}$, ${}^{3}\underline{\mathbf{T}}_{e}$

2. Structure RPPRR



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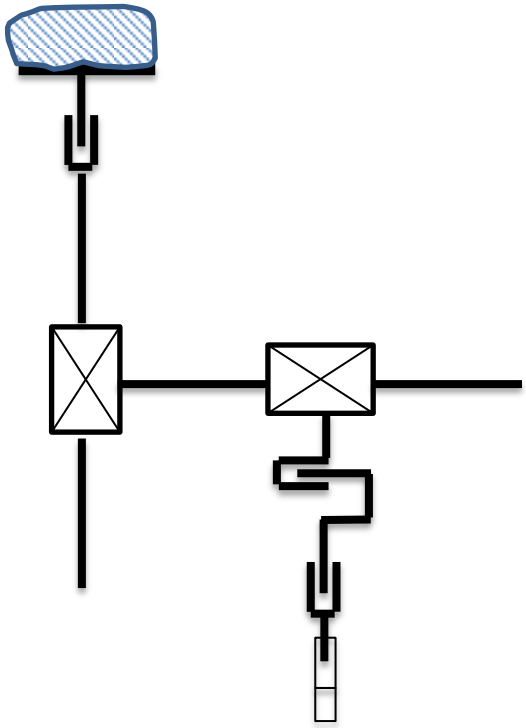
Geometrical model matrices: ${}^{0}\underline{T}_{3}$, ${}^{3}\underline{T}_{e}$

3. Structure RPPRR



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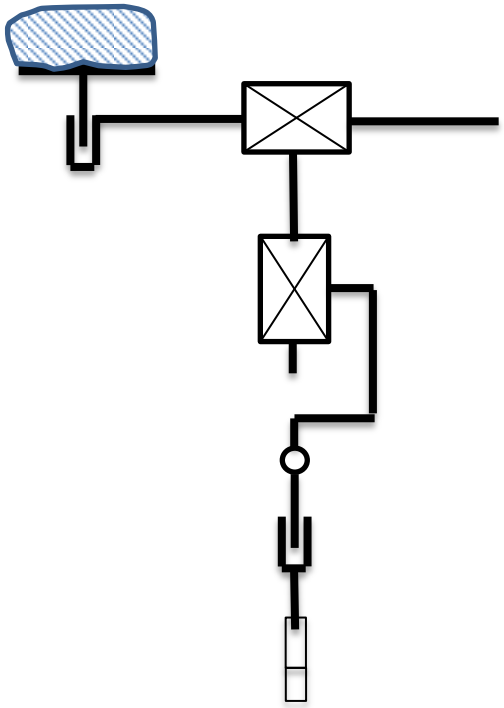
4. Structure RPPRR



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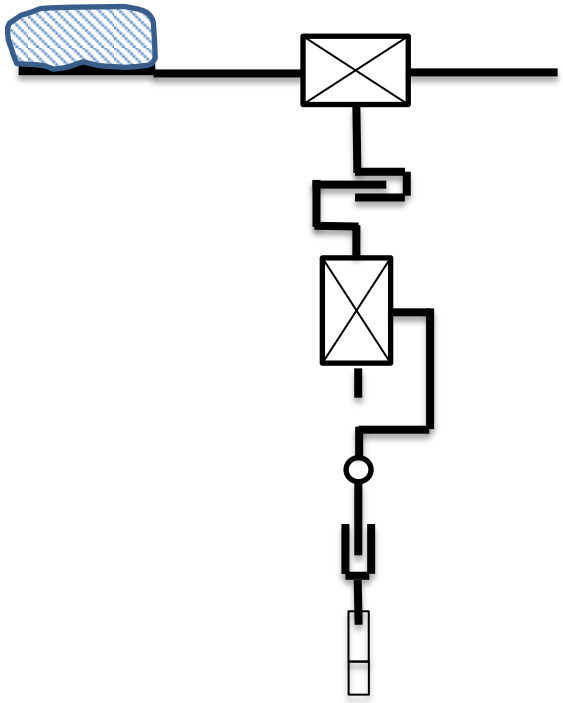
5. Structure PRPRR



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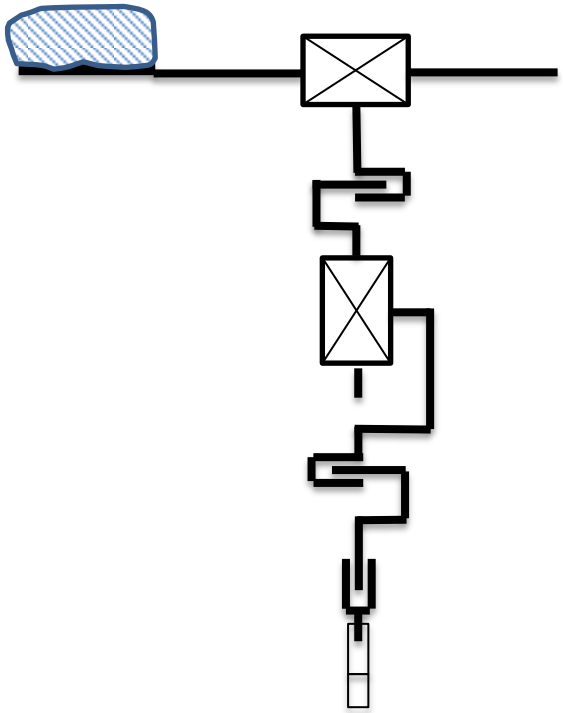
6. Structure PRPRR



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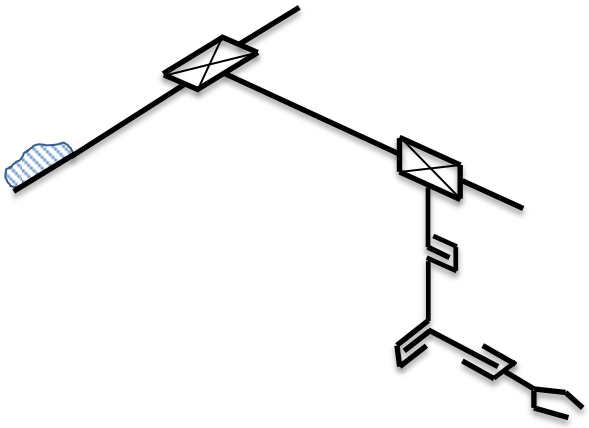
7. Structure PPRRR



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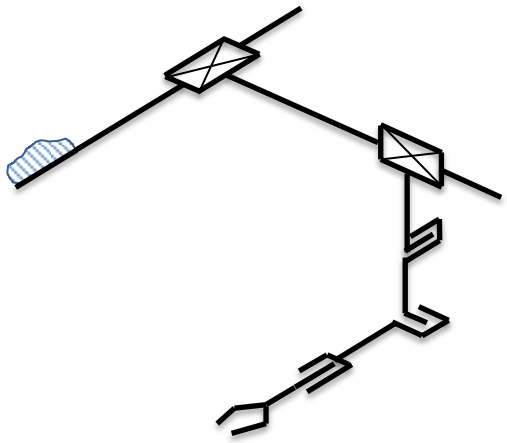
8. Structure PPRRR



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