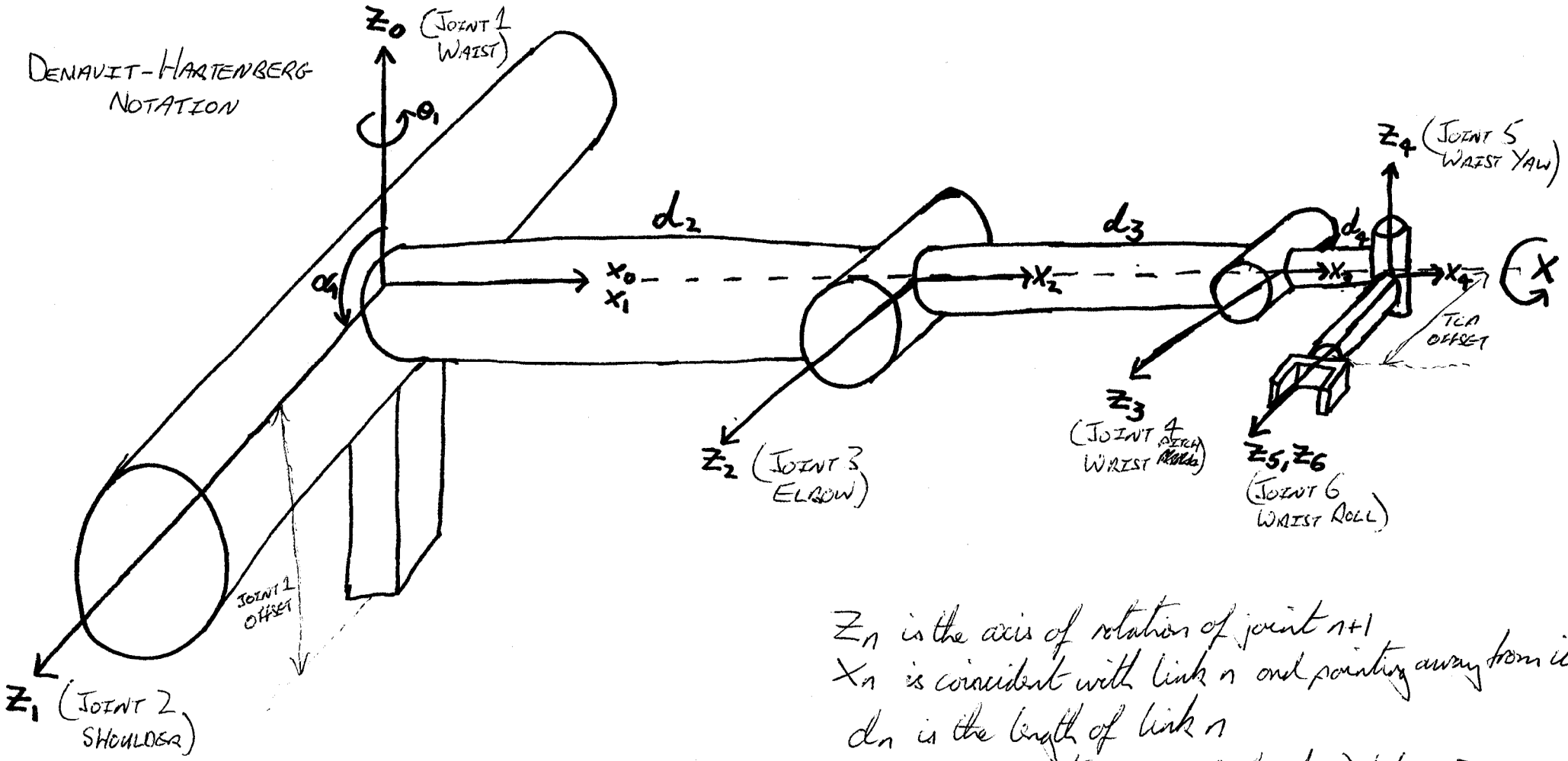
An Articulated Manipulator With 6 Joints



Z_n is the axis of rotation of joint $n+1$

X_n is coincident with link n and pointing away from it

d_n is the length of link n

α_n is the rotation required (about X) to line Z_n up

θ_n is the required rotation for joint n.

$d_1 = d_5 = 0$ since joints 1 & 2 and 5 & 6 have coincident origins.