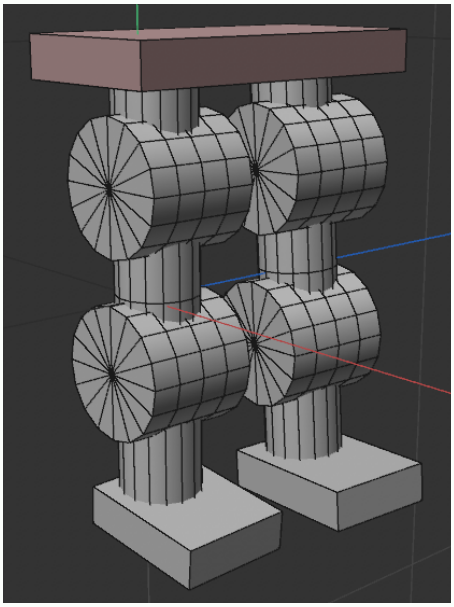
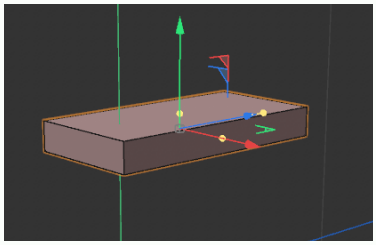
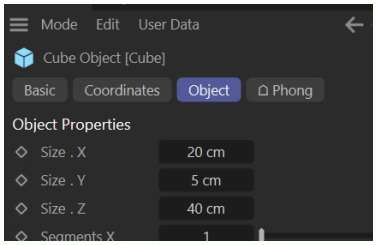
CALCULATE THE MAXIMUM ANGLE OF MOVEMENT OF THE ROBOT'S FOOT

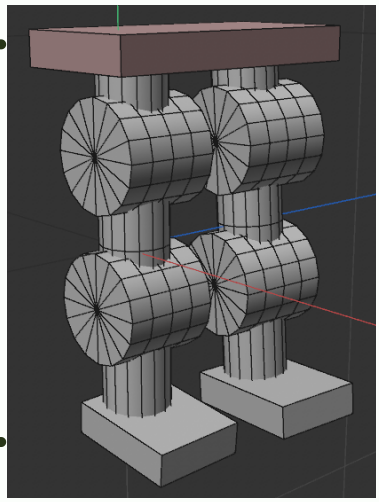


Stick model

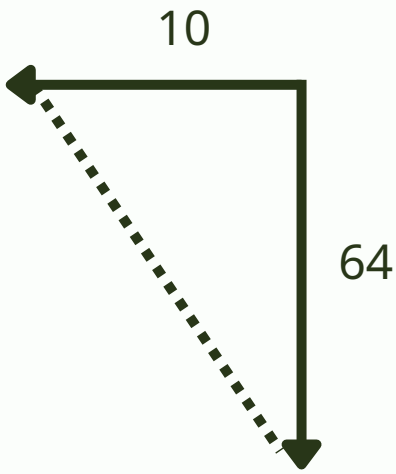
Depending on the base measurements







64



θ=

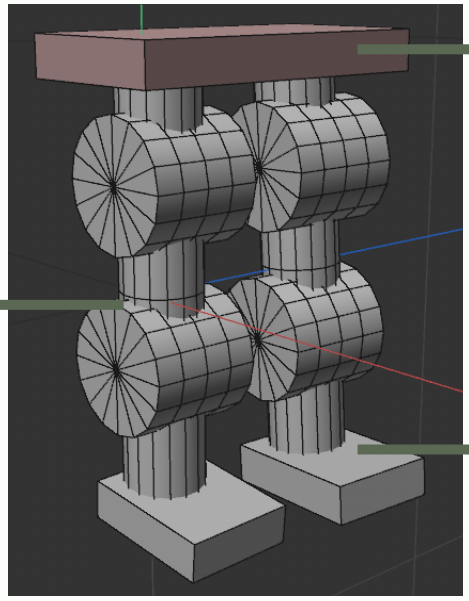
degrees =8.99

Decimal=0.15689

THE NUMBER OF LINKS AND JOINTS

The robot has
1-Base
2-manipulator
3-End Effects

Select this part in the stick model



L1-1=L0 — J1 — L2-1=L1 — J2 — L3-1=L2 — J3 — L3