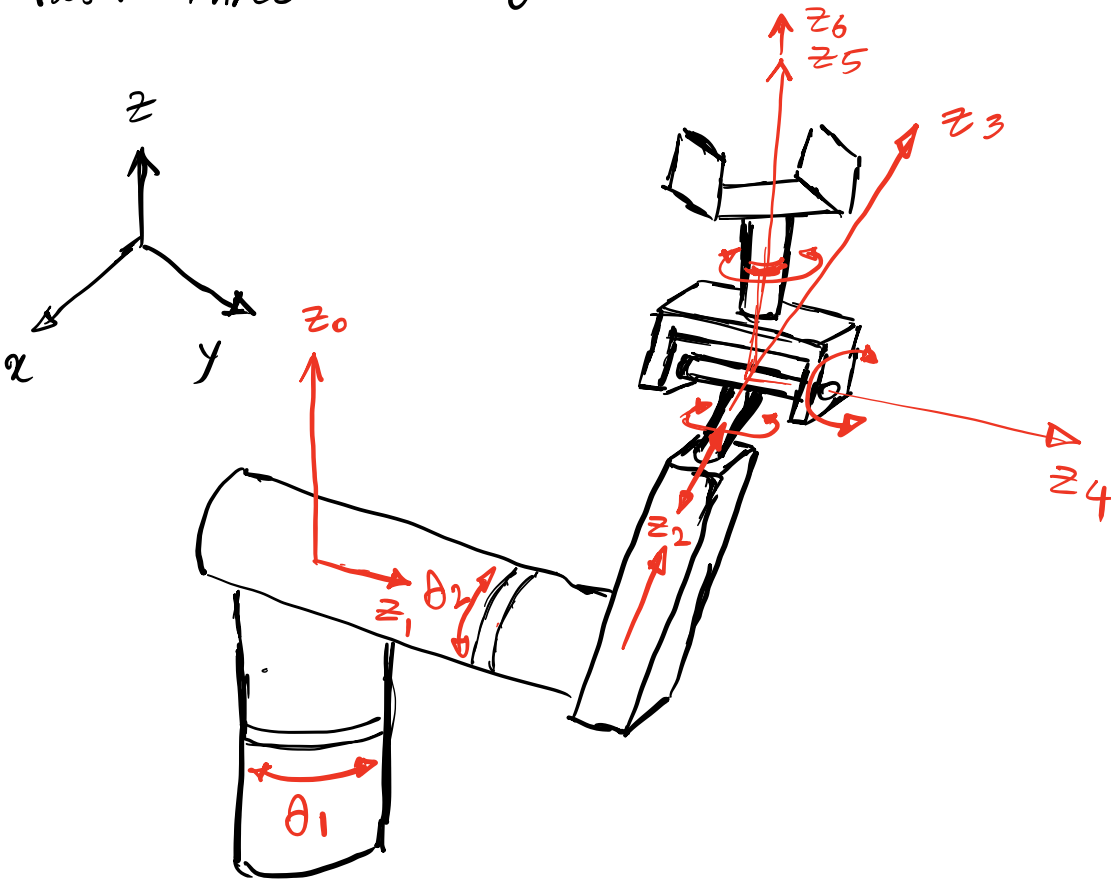
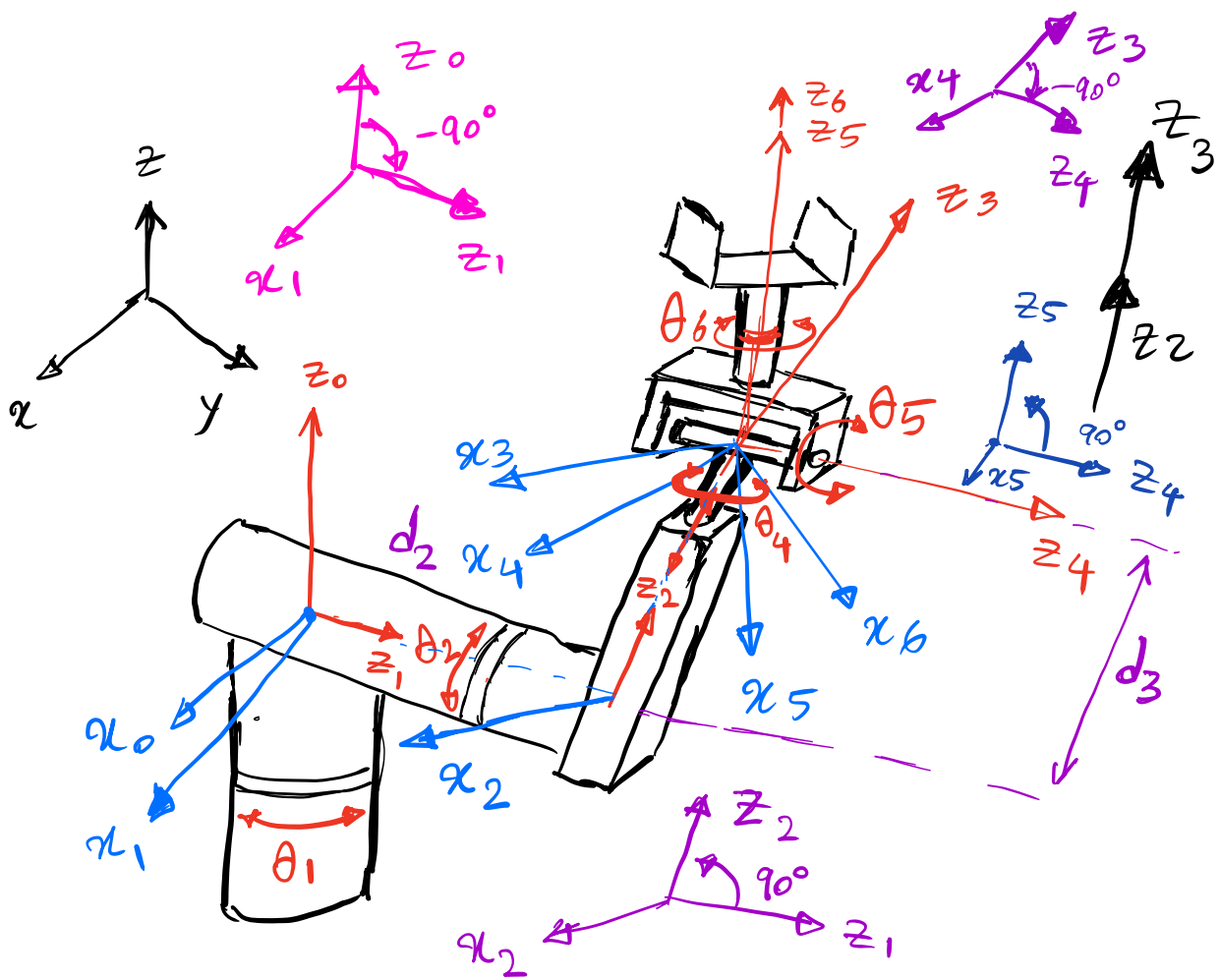


Example

The Stanford Arm: Assign coordinate frames to the Stanford Arm, and fill out the parameters table.

The Stanford Arm is spherical coordinate arm: the first two joints are revolute, and the third is prismatic, and the last three wrist joints are revolute joints.





#	θ	d	a	α
	Rotate x_n to x_{n+1} about z_n by θ_{n+1}	Translate x_n to x_{n+1} along z_n by d_{n+1}	Translate z_n to z_{n+1} along x_{n+1} by a_{n+1}	Rotate z_n to z_{n+1} about x_{n+1} by α_{n+1}
0-1	Rotate x_0 to x_1 about z_0 by θ_1	Translate x_0 to x_1 along z_0 by 0	Translate z_0 to z_1 along x_1 by 0	Rotate z_0 to z_1 about x_1 by -90°

1-2	Rotate x_1 to x_2 about z_1 by θ_2	Translate x_1 to x_2 along z_1 by d_2	Translate z_1 to z_2 along x_2 by 0	Rotate z_1 to z_2 about x_2 by 90°
2-3	Rotate x_2 to x_3 about z_2 by 0	Translate x_2 to x_3 along z_2 by d_3	Translate z_2 to z_3 along x_3 by 0	Rotate z_2 to z_3 about x_3 by 0
3-4	Rotate x_3 to x_4 about z_3 by θ_4	Translate x_3 to x_4 along z_3 by 0	Translate z_3 to z_4 along x_4 by 0	Rotate z_3 to z_4 about x_4 by -90°
4-5	Rotate x_4 to x_5 about z_4 by θ_5	Translate x_4 to x_5 along z_4 by 0	Translate z_4 to z_5 along x_5 by 0	Rotate z_4 to z_5 about x_5 by 90°
5-6	Rotate x_5 to x_6 about z_5 by θ_6	Translate x_5 to x_6 along z_5 by 0	Translate z_5 to z_6 along x_6 by 0	Rotate z_5 to z_6 about x_6 by 0

