

Day 07

Denavit-Hartenberg

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$$T_i^{i-1} = R_{z,\theta_i} T_{z,d_i} T_{x,a_i} R_{x,\alpha_i}$$
$$= \begin{bmatrix} c_{\theta_i} & -s_{\theta_i} c_{\alpha_i} & s_{\theta_i} s_{\alpha_i} & a_i c_{\theta_i} \\ s_{\theta_i} & c_{\theta_i} c_{\alpha_i} & -c_{\theta_i} s_{\alpha_i} & a_i s_{\theta_i} \\ 0 & s_{\alpha_i} & c_{\alpha_i} & d_i \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

a_i link length

α_i link twist

d_i link offset

θ_i joint angle

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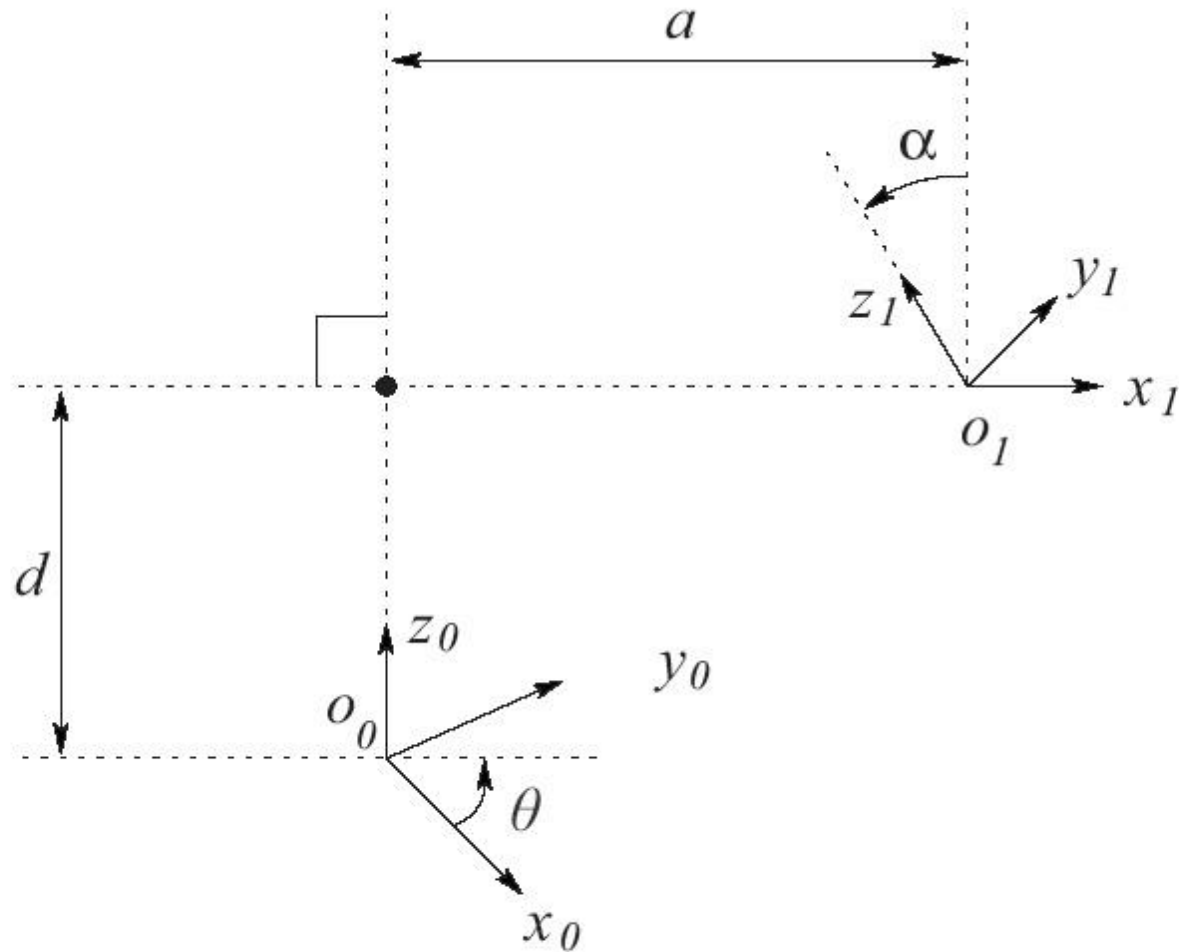


Figure 3.2: Coordinate frames satisfying assumptions DH1 and DH2.