

KR60-3 Kinematics in DH notation

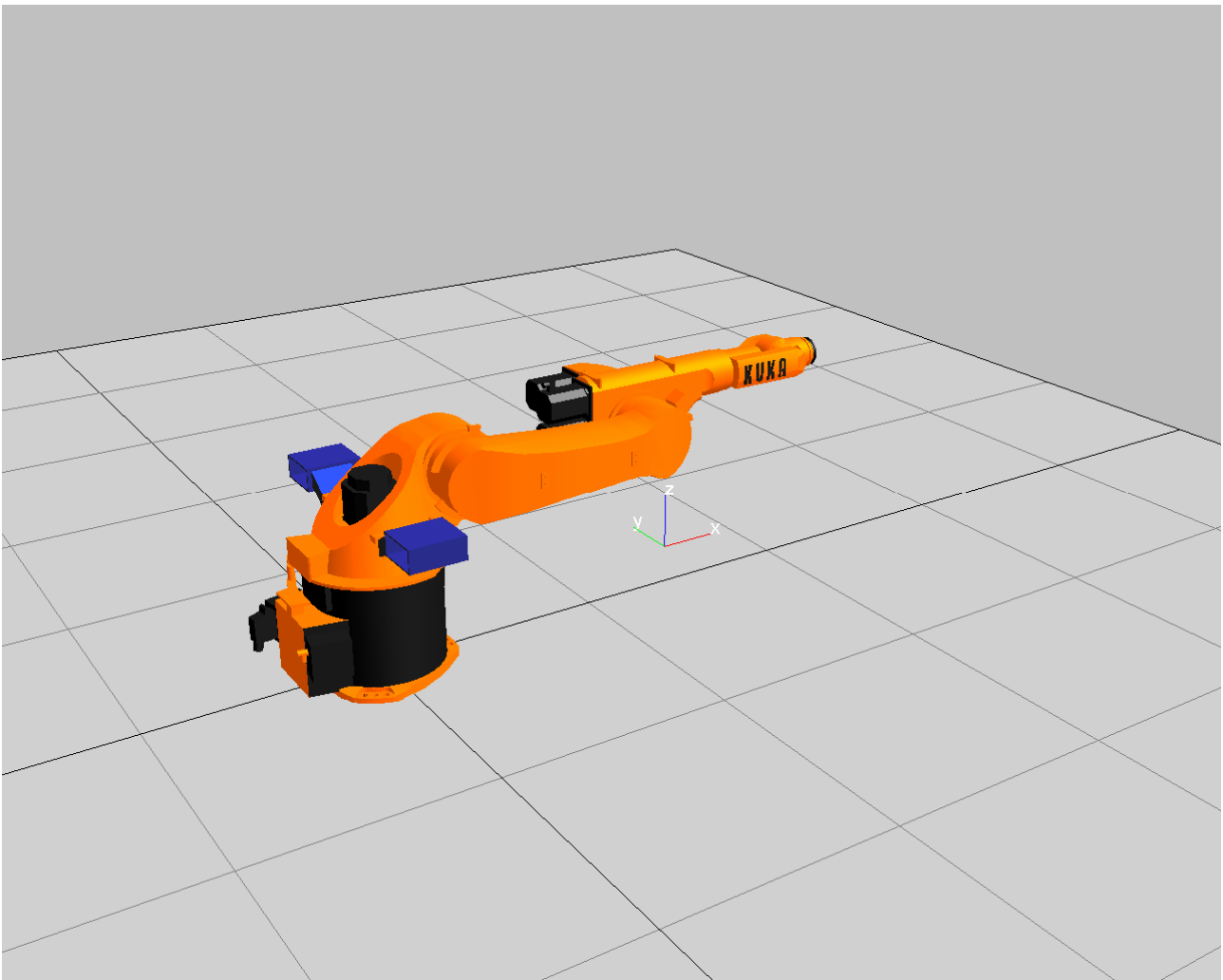


Figure 1: Position of the robot with all joints set to zero

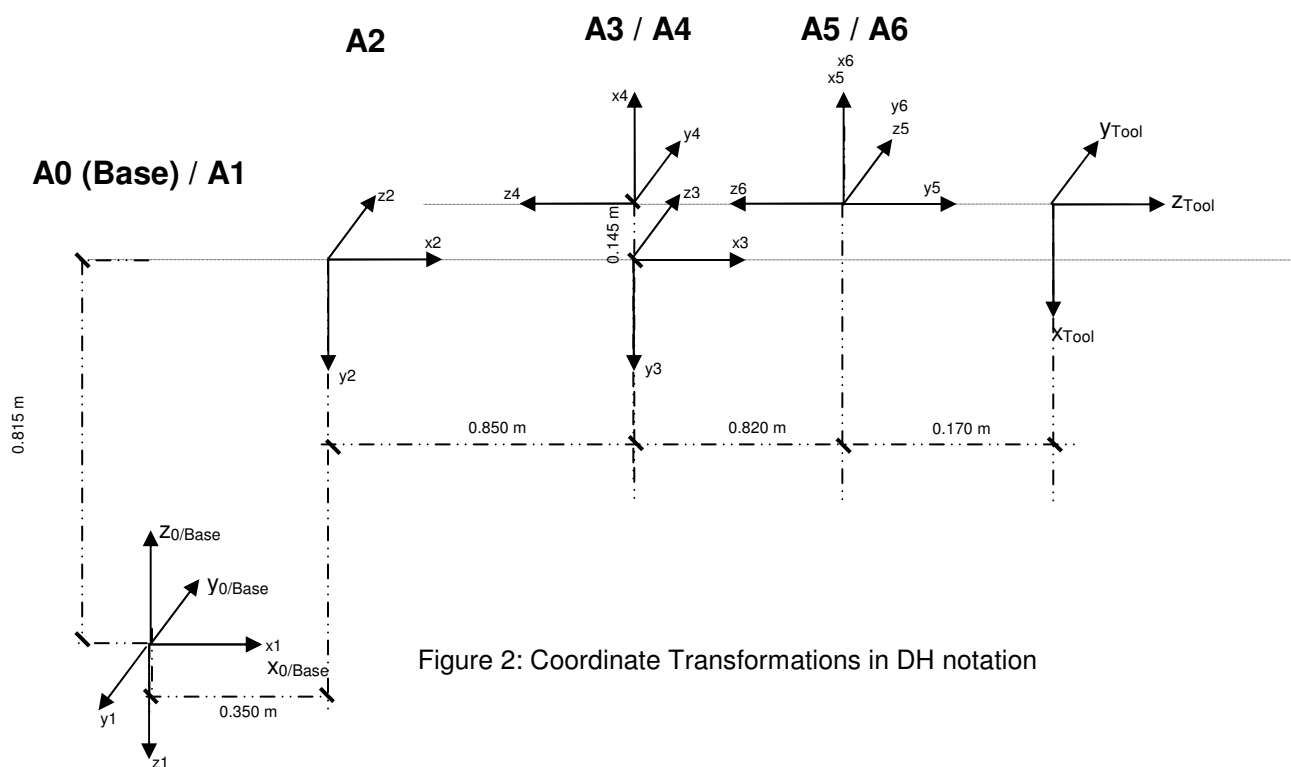


Figure 2: Coordinate Transformations in DH notation

Frames	θ_n (Rotation θ_n about z_{n-1} -Axis to align x_{n-1} -Axis with x_n -Axis)	d_n (Translation d_n along z_{n-1} - Axis, so that z_{n-1} and x_n intersect at origin)	a_n (Translation a_n along x_n -Axis, to align the origins of both frames)	α_n (Rotation α_n about x_n -Axis to align z_{n-1} -Axis and z_n -Axis)
0 (Base) to 1	0°	0	0	180°
1 to 2	0°	-0.815 m	0.350 m	90°
2 to 3	0°	0	0.850 m	0°
3 to 4	-90°	0	0.145 m	90°
4 to 5	0°	-0.820 m	0	-90°
5 to 6	0°	0	0	90°
6 zu Tool	180°	-0.170 m	0	180°

Figure 3: Overview DH Parameter, additionally transformation from Base to Link 1 (first row) and transformation from Link 6 to Tool Coordinate System (last row)