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Estimated student time to complete: 20 minutes Prerequisite knowledge required: Text Section(s) 3.10
Solution: The robot has 6 revolute joints. From Equation 3.26: $T_6^J1i = (- nx p y + n y px)$ where for $i=6$ we use $5T_6 = A_6$ given in Equation 2.57.

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Solution: The robot has 6 revolute joints. From Equation 3.26: $() 6 2 T i x y y x J o p o p = +$ where for $i=1$ we use $6 1 2 3 4 5 6 o T A A A A A A =$ given in Equation 2.59.

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