

# Chapter 2

## Robot Kinematics: Position Analysis

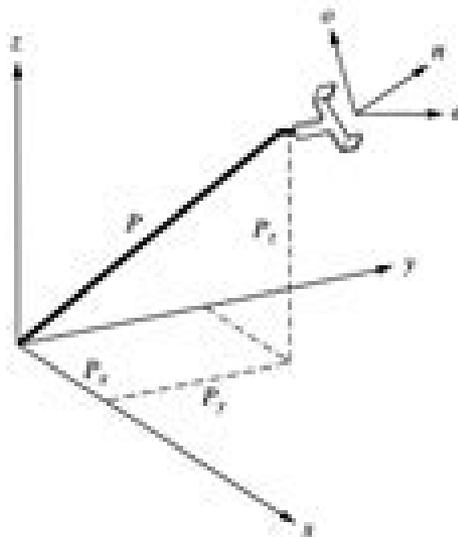
### 2.7 FORWARD AND INVERSE KINEMATICS OF ROBOTS

#### 2.7.1 Forward and Inverse Kinematics Equations for Position

##### 2.7.1(a) Cartesian (Gantry, Rectangular) Coordinates

###### ◆ IBM 7565 robot

- All actuator is linear.
- A gantry robot is a Cartesian robot.



$${}^R T_P = T_{cart} = \begin{bmatrix} 1 & 0 & 0 & P_x \\ 0 & 1 & 0 & P_y \\ 0 & 0 & 1 & P_z \\ 0 & 0 & 0 & 1 \end{bmatrix}$$

Fig. 2.18 Cartesian Coordinates.

# Chapter 2 Robot Kinematics And Dynamics Modeling

**L Reisser**



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## **Table of Contents Chapter 2 Robot Kinematics And Dynamics Modeling**

1. Understanding the eBook Chapter 2 Robot Kinematics And Dynamics Modeling
  - The Rise of Digital Reading Chapter 2 Robot Kinematics And Dynamics Modeling
  - Advantages of eBooks Over Traditional Books
2. Identifying Chapter 2 Robot Kinematics And Dynamics Modeling
  - Exploring Different Genres
  - Considering Fiction vs. Non-Fiction
  - Determining Your Reading Goals
3. Choosing the Right eBook Platform
  - Popular eBook Platforms
  - Features to Look for in an Chapter 2 Robot Kinematics And Dynamics Modeling
  - User-Friendly Interface
4. Exploring eBook Recommendations from Chapter 2 Robot Kinematics And Dynamics Modeling
  - Personalized Recommendations
  - Chapter 2 Robot Kinematics And Dynamics Modeling User Reviews and Ratings
  - Chapter 2 Robot Kinematics And Dynamics Modeling and Bestseller Lists
5. Accessing Chapter 2 Robot Kinematics And Dynamics Modeling Free and Paid eBooks

- Chapter 2 Robot Kinematics And Dynamics Modeling Public Domain eBooks
  - Chapter 2 Robot Kinematics And Dynamics Modeling eBook Subscription Services
  - Chapter 2 Robot Kinematics And Dynamics Modeling Budget-Friendly Options
6. Navigating Chapter 2 Robot Kinematics And Dynamics Modeling eBook Formats
    - ePub, PDF, MOBI, and More
    - Chapter 2 Robot Kinematics And Dynamics Modeling Compatibility with Devices
    - Chapter 2 Robot Kinematics And Dynamics Modeling Enhanced eBook Features
  7. Enhancing Your Reading Experience
    - Adjustable Fonts and Text Sizes of Chapter 2 Robot Kinematics And Dynamics Modeling
    - Highlighting and Note-Taking Chapter 2 Robot Kinematics And Dynamics Modeling
    - Interactive Elements Chapter 2 Robot Kinematics And Dynamics Modeling
  8. Staying Engaged with Chapter 2 Robot Kinematics And Dynamics Modeling
    - Joining Online Reading Communities
    - Participating in Virtual Book Clubs
    - Following Authors and Publishers Chapter 2 Robot Kinematics And Dynamics Modeling
  9. Balancing eBooks and Physical Books Chapter 2 Robot Kinematics And Dynamics Modeling
    - Benefits of a Digital Library
    - Creating a Diverse Reading Collection Chapter 2 Robot Kinematics And Dynamics Modeling
  10. Overcoming Reading Challenges
    - Dealing with Digital Eye Strain
    - Minimizing Distractions
    - Managing Screen Time
  11. Cultivating a Reading Routine Chapter 2 Robot Kinematics And Dynamics Modeling
    - Setting Reading Goals Chapter 2 Robot Kinematics And Dynamics Modeling
    - Carving Out Dedicated Reading Time
  12. Sourcing Reliable Information of Chapter 2 Robot Kinematics And Dynamics Modeling
    - Fact-Checking eBook Content of Chapter 2 Robot Kinematics And Dynamics Modeling
    - Distinguishing Credible Sources
  13. Promoting Lifelong Learning
    - Utilizing eBooks for Skill Development

- Exploring Educational eBooks
14. Embracing eBook Trends
- Integration of Multimedia Elements
  - Interactive and Gamified eBooks

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