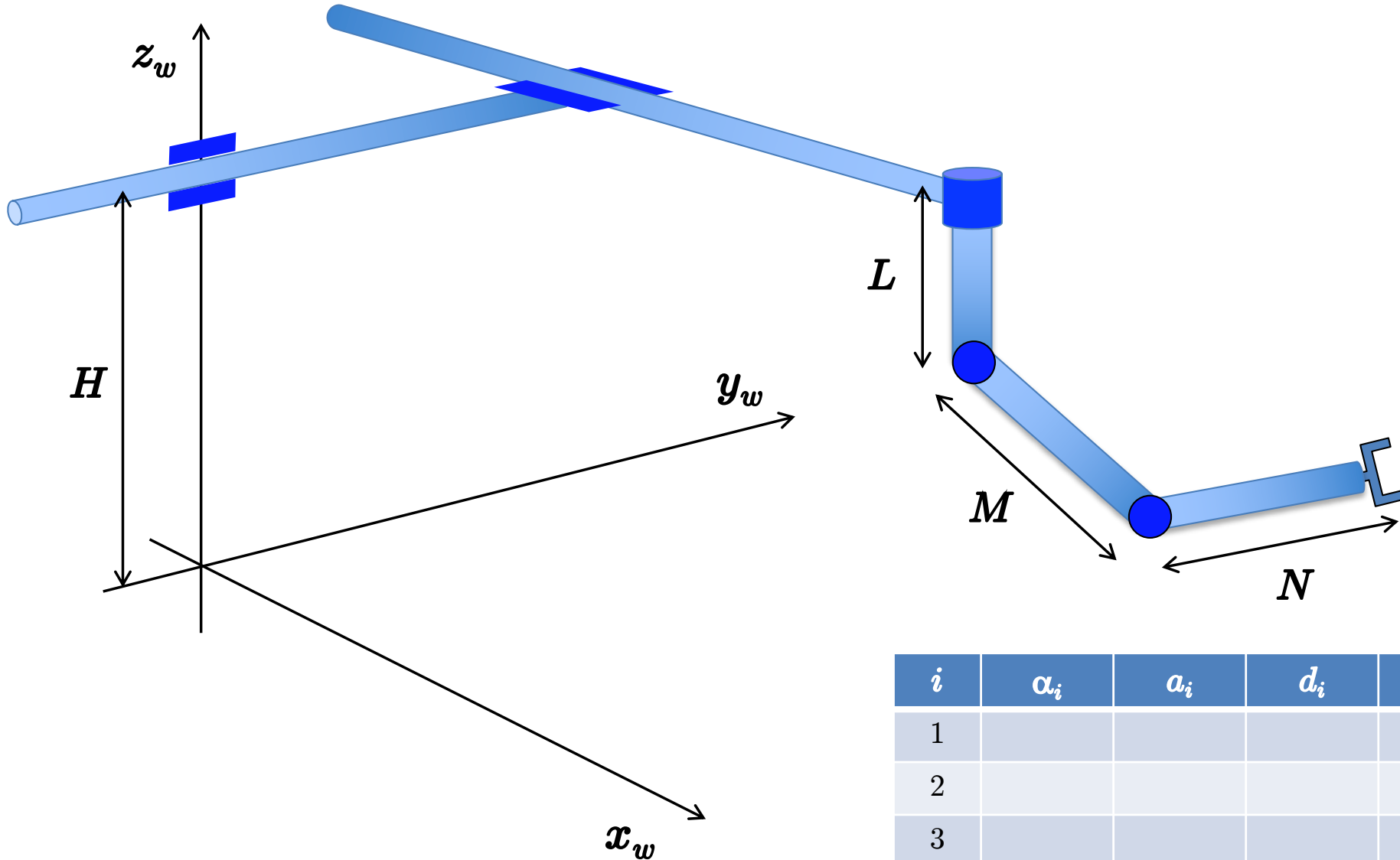


DH frames assignment and table for a 2P3R spatial robot



i	α_i	a_i	d_i	θ_i
1				
2				
3				
4				
5				