

# Chapter 2

## Robot Kinematics: Position Analysis

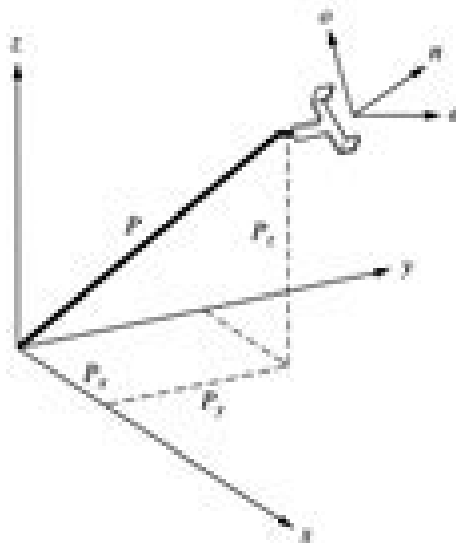
### 2.7 FORWARD AND INVERSE KINEMATICS OF ROBOTS

#### 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

**Thomas Griffiths**



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