

Transform	d	theta	r	alpha
0-1	Height of the servo1 rotor from surface of the rotary table (13mm)	Servo 0 angle	0, or very close	+90
1-2	0	Servo 1 angle	Length of link 1 (88mm)	0
2-3	0	Servo 2 angle	Length of link 2 (88mm)	0
3-4	Offset between the axis of the wrist rotator and the centre of the wrist flexor servo along the wrist flexor's z-axis (18mm)	Servo Angle 3 + 90	Distance between the servo 3 and 4 rotors (28mm)	+90
4-5	Length of the gripper plus the length of the wrist servo (91mm)	Servo angle 4	0	0

- **d:** offset along previous z to the common normal
- **theta:** angle about previous z, from old x to new x
- **r:** length of the common normal
- **alpha:** angle about common normal, from old z axis to new z axis

