Appendix (A)

Computer program main interface

Forward Kinematic Modeling

Links Parameters Table

link i	a i	αi	di	θi
1				
2				
3				
4				

OK

nks transformations matri

$^0T1=(θ1)$ $^1T2=(θ2)$ $^2T3=(θ3)$ $^2T4=(θ4)$

final position and Orientation

TE=

Clear all Data

EXIT

Preview Report