

Fig. 2.6 *A SCARA Robot designed for assembly.*

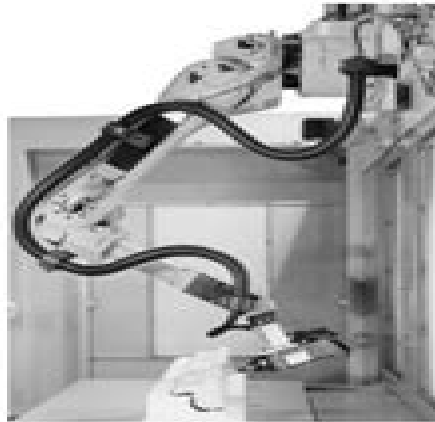


Fig. 2.7 *Articulated robots used in machining, spray painting, welding etc.*

2.1.3 Joint Notation Scheme

The physical configuration of the robot manipulator can be described by means of a joint notation scheme, using the joint types defined earlier in this section (*L*, *R*, *T*, and *P*). Considering the arm and body joints first, the letters can be used to designate the particular robot configuration starting with the joint closest to the base and proceeding to the joint that connects to the wrist. Accordingly, a jointed-arm robot (excluding the wrist assembly) would have three rotational joints and would be

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Mikell P. Groover



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