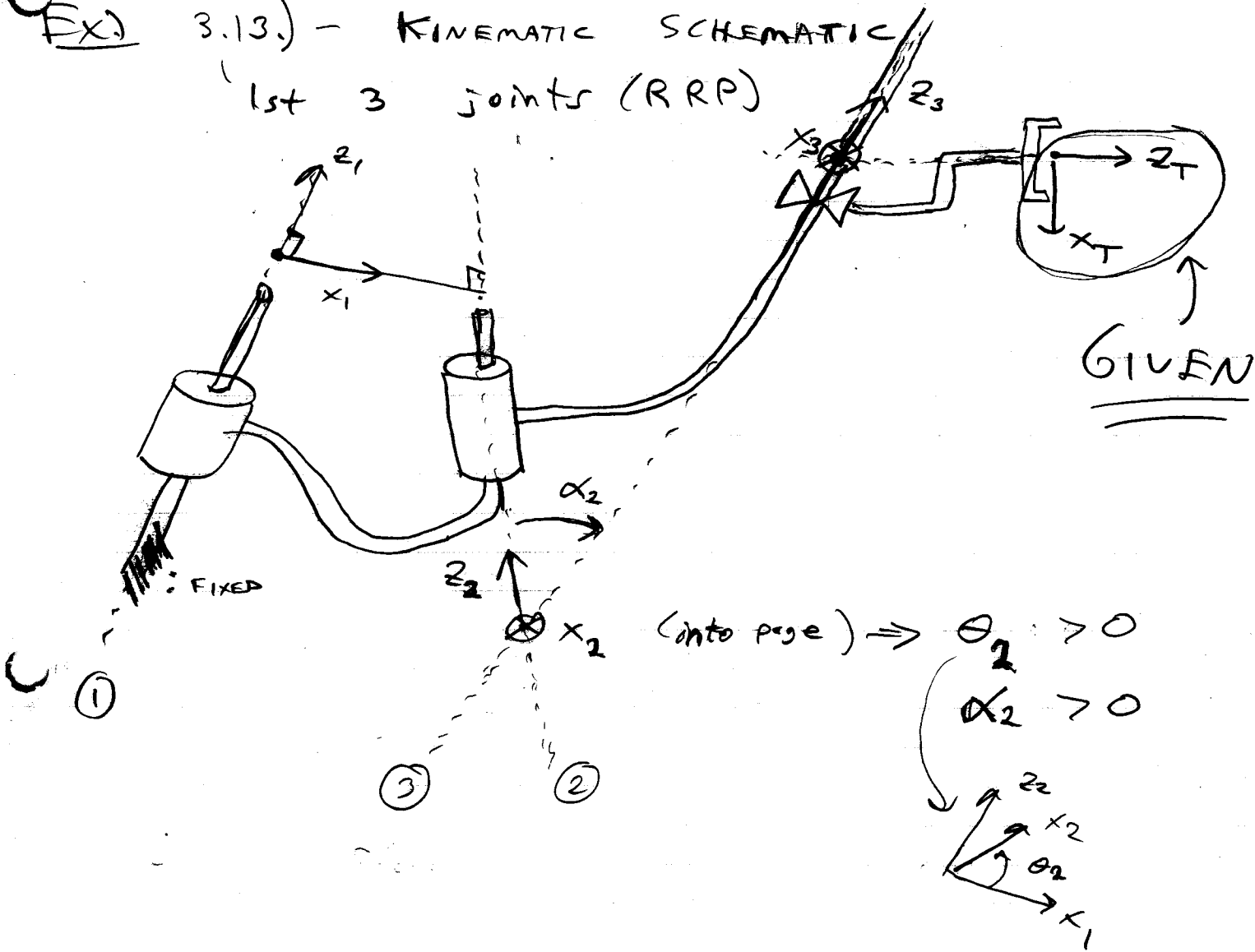
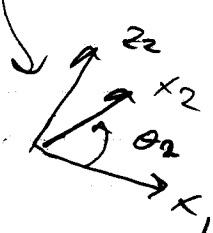


similar to 3.22

(EX) 3.13.) - KINEMATIC SCHEMATIC
1st 3 joints (RRP)



(into page) \Rightarrow $\theta_2 > 0$
 $\alpha_2 > 0$



x_3 (into page) \Rightarrow $\theta_3 = 0$
 $\alpha_3 > 0$