2. Kinematic Analysis

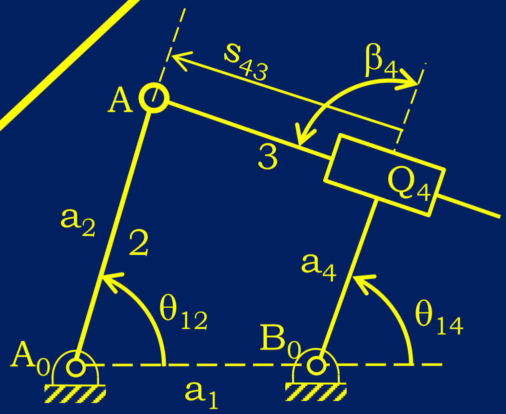
Inverted Slider-Crank

$$\overrightarrow{A_{0_1}A_{0_2}} + \overrightarrow{A_{0_2}A_2} = \overrightarrow{A_{0_1}B_{0_1}} + \overrightarrow{B_{0_1}B_{0_4}} + \overrightarrow{B_{0_4}Q_4} + \overrightarrow{Q_4A_3}$$

$$0 + a_2e^{i\theta_{12}} = a_1 + 0 + a_4e^{i\theta_{14}} + s_{43}e^{i(\theta_{14}+\beta_4)}$$

Zero Vectors

Body Vectors



Translational Joint Variable Vector ($s_{4/3}$)