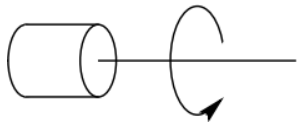
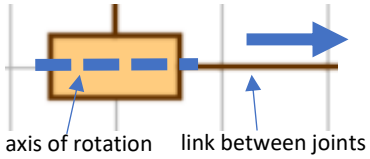
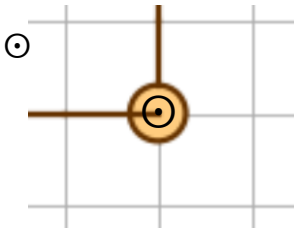
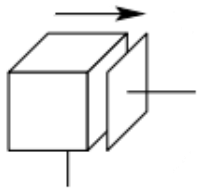
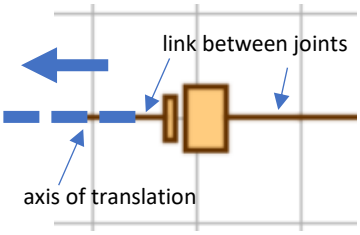
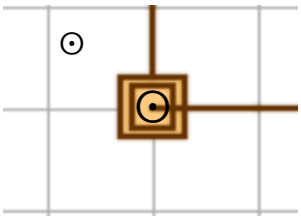
Joint Type	Explanation	Graph
Revolute	The revolute joints are usually represented as cylinders in 3D robot schematic graphs. The arrow indicates the positive direction of rotation.	
	In 2D robot schematic graphs, revolute joints can be represented as rectangles with the axis of rotation parallel to the longer rectangle sides and centered in the rectangle. The positive direction of rotation is decided by the direction of the arrow according to the right-hand rule. This arrow points towards the side that has link.	
	In 2D robot schematic graphs, revolute joints can be represented as a circle with the axis of rotation passing through the center of the circle. The positive direction of rotation is decided by the direction of the arrow according to the right-hand rule. This arrow points outwards from the screen.	
Prismatic	The prismatic joints are usually represented as a cube with a plane in 3D robot schematic graphs. The arrow indicates the positive direction of translation.	
	In 2D robot schematic graphs, prismatic joints are represented as two rectangles separated by a small gap with the axis of translation along the link. The positive direction of translation is decided by the direction of the arrow. This arrow points towards the side of the smaller rectangle.	
	In 2D robot schematic graphs, prismatic joints can be represented as one small square bounded by another bigger square with the axis of translation passing through the center of the square. The positive direction of translation is decided by the direction of the arrow. This arrow points outwards from the screen.