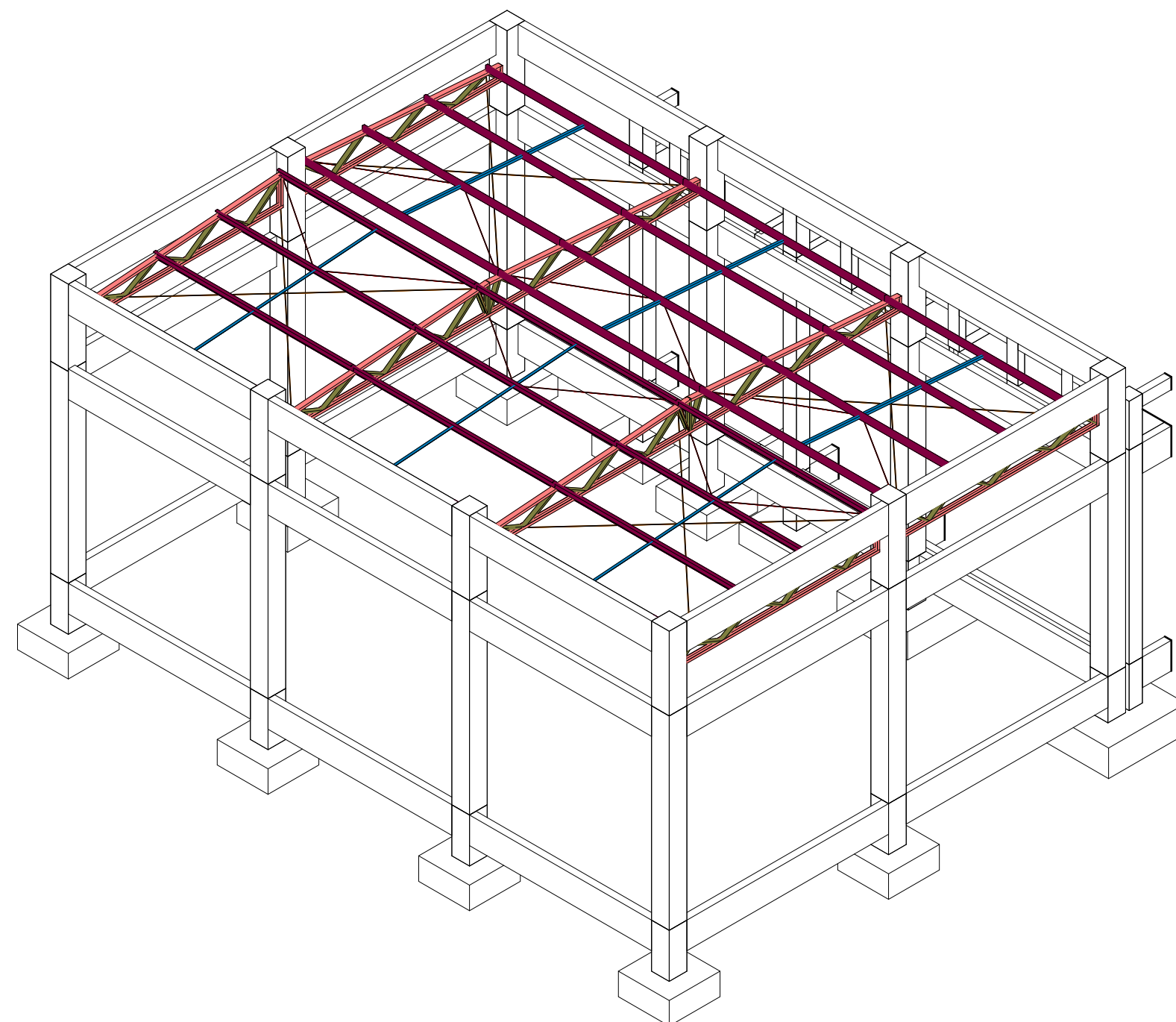
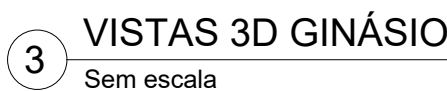
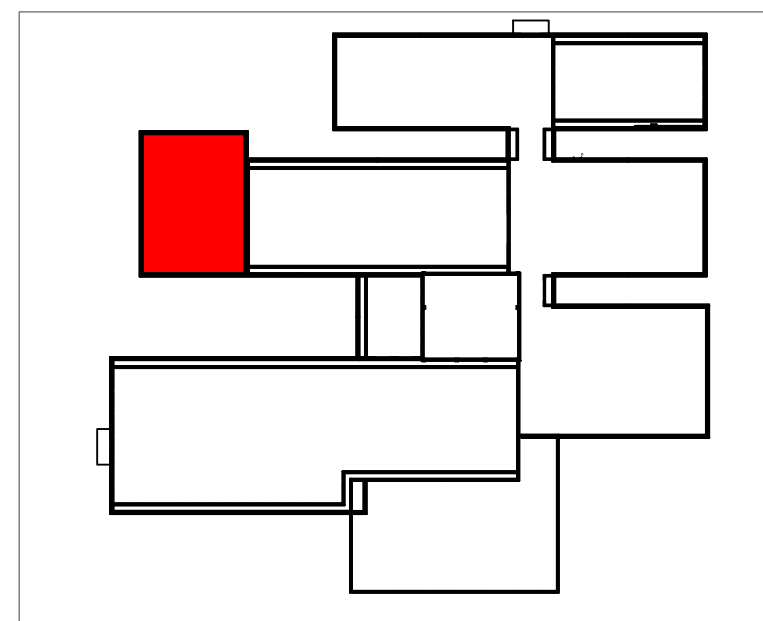




The diagram shows a mechanism with 6 links and 5 joints. Link 1 is the ground, represented by a horizontal line at the bottom. Link 2 is a horizontal link on the right. Link 3 is a vertical link in the middle. Link 4 is a horizontal link on the left. Link 5 is a vertical link at the top. Link 6 is a horizontal link at the bottom left. The joints are: a revolute joint between links 1 and 2, a revolute joint between links 2 and 3, a revolute joint between links 3 and 4, a revolute joint between links 4 and 5, and a revolute joint between links 5 and 6. The label $S_x(E)$ is placed near the joint between links 4 and 5.