
KINEMATIC SCHEME DESIGNING OF HEXAPOD WALKING ROBOT TREE ACTUATOR

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Abstract

The article focuses on the existing hexapod walking robots and kinematic scheme of their actuator. We examine Denavit—Hartenberg parameters and reachability matrix. The popularity of such robots is largely due to the fact that the problem of static stability of moving hexapod machines is solved simply compared to other structures

Keywords

Hexapod walking robots, synthesis of kinematic structure, modified Denavit—Hartenberg coordinate system, reachability matrix

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