



Hexapod Kinematics  
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The diagram illustrates the kinematics of a hexapod system. A central platform is supported by six legs, each consisting of two links and three joints (two revolute joints, A and B, and one prismatic joint, P). The joints are labeled A0 through A5, B0 through B5, and P0 through P5. The platform is defined by a dashed circle with radius  $P\_RAD$ . The legs are defined by a dashed circle with radius  $B\_RAD$ . The distance between the base of the legs is labeled  $ARM\_LENGTH$ . The diagram shows the platform's orientation relative to the  $X$ ,  $Y$ , and  $Z$  axes. The platform's orientation is defined by the angles  $THETA\_P$ ,  $THETA\_B$ , and  $THETA\_S$ . The platform's position is defined by the angles  $AXIS1$ ,  $AXIS2$ , and  $AXIS3$ .