KINEMATICS, STATICs AND STIFFNESS
ANALYSIS OF $n(4$-SPS+SP$)$ S-PM

Bo Hu,* Shan Zhuang,* Yi Lu,* Chunping Sui,** Jianda Han,** and Jingjing Yu*

Abstract

A novel $n(4$-SPS+SP$)$ serial-parallel manipulator (S-PM) formed by $n$ 4-SPS+SP PMs with four degrees of freedom (DOF) connected in series is proposed in this paper. The kinematics, statics and stiffness model of this series-PM is established. First, the forward kinematics of 4-SPS+SP (spherical joint-prismatic joint-revolute-spherical joint-prismatic joint) PM is derived and the kinematics of $n(4$-SPS+SP$)$ S-PM is studied combined with the kinematics result of single 4-SPS+SP PM. Second, the statics, deformation and stiffness of $n(4$-SPS+SP$)$ S-PM are studied. Finally, an analytically solved example is given for 3(4-SPS+SP) formed by three 4-SPS+SP PMs. The method for this mechanism is fit for other S-PMs.

Key Words

Kinematics, serial-parallel manipulators, statics, deformation, stiffness

1. Introduction

Serial-parallel manipulators (S-PMs) have higher stiffness than serial robots and possess the advantages of larger workspace than PMs. This class of mechanisms has good research and application prospect. In this aspect, Romdhane [1] designed and analysed a hybrid S-PM formed by a pure translational PM that has a PPP-type passive leg and a pure rotational PM that has an S-type passive leg. Jaime et al. [2] studied the dynamic of 2(3-RPS) (revolute joint-prismatic joint-spherical joint) S-PM by using screw theory and principle of virtual work. Lu and Hu [3] solved driving forces of 2(3-SPR) (spherical joint-prismatic joint-revolute) S-PM by CAD variation geometry approach and solved the velocity, acceleration and statics by analytical method subsequently [4]. Zheng et al. [5] studied the kinematics of a hybrid S-PM formed by a pure translational 3-UPU (universal joint-prismatic joint-universal joint) PM and a pure rotational 3-UPU PM. The previous research of these type of mechanisms focused on the S-PMs formed by two PMs. The S-PMs formed by $n$ PMs were seldom studied. However, establishing theory of this kind of S-PMs is significant.

4-DOF PMs have attracted a lot of attention because of their merits such as larger workspace, simple structure and easy controllability. Many 4-DOF PMs have been systemically synthesized by different methods [6]–[9]. The kinematics, singularity, stiffness and dynamics of this class of PMs have been deeply investigated [10]–[12]. This paper proposes a novel $n(4$-SPS+SP$)$ serial-PM formed by $n$ 4-SPS+SP PMs connected in series. The 4-SPS+SP PM was proposed and studied by Lu and Hu [13], which has some merits and potential application prospects [14]. The inverse kinematics, velocity, acceleration and stiffness of this PM have been solved. However, the forward kinematics of this PM has not been studied [13], [14]. In this paper, the forward kinematics of 4-SPS+SP is solved in close form. Furthermore, the kinematics, statics and stiffness of $n(4$-SPS+SP$)$ S-PM are established based on the results of 4-SPS+SP PM.

The $n(4$-SPS+SP$)$ has some merits such as large workspace and high stiffness. It has some potential applications for the robot arms and the serial-PM machine tools. The kinematics, statics and stiffness model established for $n(4$-SPS+SP$)$ serial-PM is fit for other serial-PMs.

2. Kinematics of the $n(4$-SPS+SP$)$ S-PM

The $n(4$-SPS+SP$)$ S-PM is formed by $n$ identical 4-SPS+SP PMs connected in series. Let PM $i$ be the $i$th 4-SPS+SP PM form bottom to top in $n(4$-SPS+SP$)$ S-PM. The $i$th 4-SPS+SP PM includes a upper platform $n_{i1}$, a lower platform $n_{i0}$, four SPS active limbs $r_{ij}$ ($i = 1, 2, \ldots , n; j = 1, 2, 3, 4$) with linear actuators, and one SP passive limb $r_{i0}$ (see Fig. 1(a)). $n_{i1}$ is a rectangle quaternary with a length sideline $l_{i1}$, a width sideline $l_{i2}$, and $n_{i0}$ is a square with sideline $l_{i4}$. Each of the driving limbs $r_{ij}$ connects $n_{i1}$ with $n_{i0}$ by using a spherical joint $S$ at $B_{ij}$ ($i = 1, 2, \ldots , n; j = 1, 2, 3, 4$) on $n_{i1}$, a prismatic joint $P$ along $r_{ij}$, and a spherical joint $S$ at $A_{ij}$ ($i = 1, 2, \ldots , n; j = 1, 2, 3, 4$) on $n_{i0}$. The passive limb $r_{i0}$ is perpendicular with $n_{i1}$ and connects $n_{i1}$ with $n_{i0}$ by using a prismatic joint $P$ on $n_{i1}$ and spherical joint $S$ at $a_{i-1}$ on $n_{i0}$. The lower platform $n_{i0}$ of PM $i$ ($i = 2, \ldots , n$) and the upper platform $n_{i-1}$ of PM $i-1$ are coplanar, fixed connected and have common centre.

* Robotics Research Center, Yanshan University, Qinhuangdao, Hebei 066004, PR China; e-mail: {hubo, zhuangshan, luyi}@ysu.edu.cn, yujingjing_725@126.com
** State Key Laboratory of Robotics, Shenyang Institute of Automation, Chinese Academy of Sciences, Shenyang, Liaoning 110016, PR China; e-mail: {cpsui, jdhuan}@sia.cn

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5. A Sketch of 4SPS+SPPM.

Figure 1. Sketch of 4SPS+SP PM.

Figure 2. Relation between \(n_{1\alpha}\) and \(n_{(i-1)\lambda}\).

An angle between \(n_{(i-1)\lambda}\) and \(n_{1\alpha}\) being \(\theta = 45^\circ \times (-1)^i\) is satisfied (see Fig. 2). Based on the defined notation, \(n_{1\alpha}\) and \(n_{1\lambda}\) represents the base and terminal platform of whole n(4-SPS+SP) S-PM, respectively.

2.1 Forward Position Modelling of \(n(4\text{-SPS+SP})\) S-PM

The forward position kinematics problem solves the position and orientation of the terminal platform \(n_{1\lambda}\) from a given set of actuated inputs \(r_{ij}\) \((i = 1, 2, \ldots, n; j = 1, 2, 3, 4)\). Let \(\{n_{1\alpha}\}\) be a coordinate system \(o_{1-1}-X_{1}Y_{1}Z_{1}\) \((i = 1, 2, \ldots, n)\) fixed on the centre of lower platform of ith PM with some conditions \((X_{i} \perp A_{i1}, A_{i2}, Y \parallel A_{i1}A_{i2}, Z \perp X_{i}, Z_{i}Y_{i})\) for its coordinate axes being satisfied. Here \(o_{0}\) is the centre of base. Let \(\{n_{0}\}\) be a coordinate system \(o_{1-1}-x_{1}y_{1}z_{1}\) fixed on the centre of upper platform of PM i with some conditions \((x_{i} \perp B_{i1}B_{i2}, y \parallel B_{i1}B_{i2}, z \perp x_{1}, z_{i}y_{i})\) for its coordinate axes being satisfied.

To solve the forward kinematics of \(n(4\text{-SPS+SP})\) S-PM, the forward kinematics of 4-SPS+SP PM must be solved first. The Sylvester dialytic elimination method is applied to solve the forward position problem.

The position vector of \(A_{ij}\) \((i = 1, 2, \ldots, n; j = 1, 2, 3, 4)\) and \(o_{i}\) in \(\{n_{i0}\}\) can be expressed as follows:

\[
\begin{align*}
n_{\alpha0}A_{i1} &= \begin{bmatrix} L_{i} \\ -L_{i} \\ 0 \end{bmatrix}, &
n_{\alpha0}A_{i2} &= \begin{bmatrix} L_{i} \\ 0 \\ 0 \end{bmatrix}, &
n_{\alpha0}A_{i3} &= \begin{bmatrix} -L_{i} \\ 0 \\ 0 \end{bmatrix}, \\
n_{\alpha0}A_{i4} &= \begin{bmatrix} -L_{i} \\ -L_{i} \\ 0 \end{bmatrix}, &
n_{\alpha0}o_{i} &= \begin{bmatrix} X_{i0} \\ Y_{i0} \\ Z_{i0} \end{bmatrix}.
\end{align*}
\]

(1a)

The position vectors of \(B_{ij}\) \((i = 1, 2, 3, 4)\) in \(\{n_{i0}\}\) can be expressed as follows:

\[
\begin{align*}
n_{\alpha1}B_{i1} &= \begin{bmatrix} l_{i1} \\ -l_{i2} \\ 0 \end{bmatrix}, &
n_{\alpha1}B_{i2} &= \begin{bmatrix} l_{i1} \\ l_{i2} \\ 0 \end{bmatrix}, &
n_{\alpha1}B_{i3} &= \begin{bmatrix} -l_{i1} \\ l_{i2} \\ 0 \end{bmatrix}.
\end{align*}
\]

(1b)

The position vectors of \(B_{ij}\) \((i = 1, 2, 3, 4)\) in \(\{n_{10}\}\) can be expressed as follows:

\[
n_{\alpha0}B_{ij} = n_{\alpha1}R n_{\alpha1}B_{ij} + n_{\alpha0}o_{i} \quad (i = 1, 2, 3, 4)
\]

(2a)

where \(n_{\alpha0}o_{i}\) is the position vectors for the centre of upper platform of PM i relative to its lower platform. \(n_{\alpha1}R\) is the rotational matrix from upper platform to lower platform for PM i. \(n_{\alpha1}R\) and \(n_{\alpha0}o_{i}\) have been solved in Ref. [14] as follows:

\[
n_{\alpha1}R = \begin{bmatrix}
c_{\alpha_{i1}}c_{\beta_{i}}c_{\lambda_{i}} - s_{\alpha_{i1}}s_{\lambda_{i}} - c_{\alpha_{i1}}c_{\beta_{i}}s_{\lambda_{i}} - s_{\alpha_{i1}}c_{\lambda_{i}} & c_{\alpha_{i1}}s_{\lambda_{i}} & s_{\alpha_{i1}}c_{\beta_{i}} - s_{\alpha_{i1}}s_{\beta_{i}} \\
c_{\alpha_{i1}}s_{\beta_{i}}c_{\lambda_{i}} + c_{\alpha_{i1}}s_{\lambda_{i}} & s_{\alpha_{i1}}c_{\beta_{i}}s_{\lambda_{i}} - s_{\alpha_{i1}}c_{\lambda_{i}} & s_{\alpha_{i1}}c_{\lambda_{i}} - c_{\alpha_{i1}}s_{\beta_{i}} \\
-s_{\alpha_{i1}}c_{\lambda_{i}}c_{\beta_{i}} & s_{\alpha_{i1}}c_{\beta_{i}}s_{\lambda_{i}} - c_{\alpha_{i1}}c_{\lambda_{i}} & s_{\alpha_{i1}}s_{\beta_{i}}
\end{bmatrix}
\]

(2b)

where \(X_{i0}, Y_{i0}, Z_{i0}\) are three components of position vector of \(o_{i}\) in \(\{n_{10}\}\) and \(\alpha_{i1}, \beta_{i}, \lambda_{i}\) are three Euler angles that are used for representing the orientation of \(n_{1i}\) to \(n_{10}\).

The inverse kinematics of ith 4SPS+SP PM has been solved as follows [14]:

\[
\begin{align*}
r_{11}^2 &= Q_{i} + r_{10}^2 - [c_{\beta_{i}}(c_{\alpha_{i}} - s_{\alpha_{i}})l_{11}c_{\lambda_{i}} + l_{12}s_{\lambda_{i}}] \\
&\quad - (s_{\alpha_{i}} - c_{\alpha_{i}})(l_{11}s_{\lambda_{i}} - l_{12}c_{\lambda_{i}}) \\
&\quad + 2r_{10}s_{\beta_{i}}(c_{\alpha_{i}} - s_{\alpha_{i}})L_{i}/2, \\
r_{12}^2 &= Q_{i} + r_{10}^2 - [c_{\beta_{i}}(c_{\alpha_{i}} + s_{\alpha_{i}})l_{11}c_{\lambda_{i}} - l_{12}s_{\lambda_{i}}] \\
&\quad - (s_{\alpha_{i}} + c_{\alpha_{i}})(l_{11}s_{\lambda_{i}} + l_{12}c_{\lambda_{i}}) \\
&\quad + 2r_{10}s_{\beta_{i}}(c_{\alpha_{i}} + s_{\alpha_{i}})L_{i}/2.
\end{align*}
\]
\[ r_{13}^2 = Q_i + r_{10}^2 - [c_\beta(c_{a_i} - s_{a_i})(l_{i1}c_{a_i} + l_{i2}s_{a_i}) - (s_{a_i} + c_{a_i})(l_{i1}s_{a_i} - l_{i2}c_{a_i}) - 2s_{a_i}s_{\beta}(c_{a_i} - s_{a_i})]/L_i/2 \]
\[ r_{14}^2 = Q_i + r_{10}^2 - [c_\beta(c_{a_i} + s_{a_i})(l_{i1}c_{a_i} - l_{i2}s_{a_i}) - (s_{a_i} - c_{a_i})(l_{i1}s_{a_i} + l_{i2}c_{a_i}) - 2s_{a_i}s_{\beta}(c_{a_i} + s_{a_i})]/L_i/2 \]

Equation (3) leads to:
\[ r_{13}^2 + r_{14}^2 - r_{11}^2 - r_{12}^2 = 4L_iX_{10}, \quad X_{10} = \frac{r_{13}^2 + r_{14}^2 - r_{11}^2 - r_{12}^2}{4L_i} \tag{4a} \]
\[ r_{12}^2 + r_{13}^2 - r_{11}^2 - r_{14}^2 = -4L_iY_{10}, \quad Y_{10} = \frac{r_{12}^2 + r_{13}^2 - r_{11}^2 - r_{14}^2}{4L_i} \tag{4b} \]

Equations (4a) and (4b) lead to:
\[ t_{g_{a_i}} = \frac{Y_{10}}{X_{10}} = \frac{r_{11}^2 - r_{12}^2 - r_{13}^2 - r_{14}^2}{r_{13}^2 + r_{14}^2 - r_{11}^2 - r_{12}^2} \]
\[ \alpha_i = \arctan\left(\frac{r_{11}^2 + r_{14}^2 - r_{12}^2 - r_{13}^2}{r_{13}^2 + r_{14}^2 - r_{11}^2 - r_{12}^2}\right) \tag{5} \]

Equation (3) leads to:
\[ 2L_i[(s_{a_i}c_{\beta}, c_{a_i} + c_{a_i}s_{\lambda_i}) - l_{i2}(c_{a_i}, c_{\beta}, s_{\lambda_i} + s_{a_i}c_{a_i})] = r_{11}^2 - r_{12}^2 + r_{13}^2 - r_{14}^2 \tag{6a} \]

Equations (3) and (2b) lead to:
\[ 2[(c_{a_i}, c_{\beta}, c_{a_i} + s_{a_i}s_{\lambda_i}) + l_{i2}(-s_{a_i}c_{a_i}, s_{\lambda_i} + c_{a_i}c_{a_i})]/L_i + r_{11}^2 + r_{12}^2 + r_{13}^2 + r_{14}^2 = 4Q_1 + 4(X_{10}/c_{\beta})^2/s_{\beta} \tag{6b} \]

Let \( t_{11} = t_{g\beta}, t_{12} = t_{g\lambda}, \) there must be:
\[ s_{a_i} = \frac{2t_{11}}{1 + t_{11}^2}, \quad c_{a_i} = \frac{1 - t_{11}^2}{1 + t_{11}^2}, \quad s_{\lambda_i} = \frac{2t_{12}}{1 + t_{12}^2}, \quad c_{\lambda_i} = \frac{1 - t_{12}^2}{1 + t_{12}^2} \tag{7} \]

Substituting (7) into (6a) leads to:
\[ s_{115}t_{11}^2t_{12}^2 + s_{114}t_{11}t_{12}^2t_{11}^2 + s_{113}t_{11}^2 + s_{112}t_{12}^2 + s_{111}t_{12} + s_{110} = 0 \tag{8} \]

where,
\[ s_{115} = s_{115}t_{11}^2 + s_{112}, \]
\[ s_{114} = s_{114}t_{11} + s_{111}, \]
\[ s_{113} = s_{113}t_{11} + s_{110}, \]
\[ s_{112} = s_{112}t_{11} + s_{111}t_{12}, \]
\[ s_{111} = s_{111}t_{12} + s_{112}, \]
\[ s_{110} = s_{110}t_{12} + s_{111} \]

Substituting (7) into (6b) leads to:
\[ s_{120}t_{11}^2 + s_{121}t_{11}^2 + s_{120}t_{12}^2 + s_{121}t_{12} + s_{120}t_{11}^2 + s_{121}t_{12}^2 + s_{120}t_{11}t_{12} + s_{120}t_{11} + s_{120}t_{12} = 0 \tag{9} \]

where,
\[ s_{120} = -4(X_{10}/c_{\beta})^2, \]
\[ s_{121} = -16Q_1 - 4(X_{10}/c_{\beta})^2 + 4r_{11}^2 + r_{12}^2 + r_{13}^2 + r_{14}^2 \]
\[ + 8s_{a_i}L_i(l_{i1} - l_{i2}), \]
\[ s_{120} = -16Q_1 - 4(X_{10}/c_{\beta})^2 + 4r_{11}^2 + r_{12}^2 + r_{13}^2 + r_{14}^2 \]
\[ + 8s_{a_i}L_i(l_{i1} + l_{i2}), \]
\[ s_{123} = -16s_{a_i}(l_{i1} + l_{i2}), \]
\[ s_{122} = -16Q_1 - 4(X_{10}/c_{\beta})^2 + 4r_{11}^2 + r_{12}^2 + r_{13}^2 + r_{14}^2 \]
\[ + 8s_{a_i}L_i(l_{i1} + l_{i2}), \]
\[ s_{121} = -4(X_{10}/c_{\beta})^2, \]
\[ s_{120} = -4(X_{10}/c_{\beta})^2 \]

Equations (8) and (9) can be expressed as follows:
\[ p_{112}t_{12}^2 + p_{111}t_{12} + p_{110} = 0 \tag{10a} \]
\[ p_{122}t_{12}^2 + p_{121}t_{12} + p_{120} = 0 \tag{10b} \]

where,
\[ p_{112} = s_{112}t_{12}^2 + s_{112}, \]
\[ p_{111} = s_{111}t_{11} + s_{111}, \]
\[ p_{110} = s_{110}t_{12} + s_{110}, \]
\[ p_{122} = s_{122}t_{12}^2 + s_{224}t_{12}^2 + s_{225} + s_{121}, \]
\[ p_{212} = s_{212}t_{12}^2 + s_{213}t_{12}^2 + s_{214}t_{12} + s_{210}t_{12} + s_{210}, \]

Multiplying \( t_{12} \) on both sides of (10a) and (10b) lead to:
\[ p_{112}t_{12}^3 + p_{111}t_{12}^2 + p_{110}t_{12} = 0 \tag{11a} \]
\[ p_{122}t_{12}^3 + p_{121}t_{12}^2 + p_{120}t_{12} = 0 \tag{11b} \]

Equations (10a), (10b), (11a) and (11b) lead to:
\[
\begin{bmatrix}
  t_{12}^3 \\
  t_{12}^2 \\
  t_{12} \\
  1
\end{bmatrix} = \begin{bmatrix}
  p_{112} & p_{111} & p_{110} & 0 \\
  p_{122} & p_{121} & p_{120} & 0 \\
  0 & p_{112} & p_{111} & p_{110} \\
  0 & p_{122} & p_{121} & p_{120}
\end{bmatrix}
\tag{12}
\]
The necessary condition for (12) to have non-trivial solutions is:

\[ |D_i| = 0 \] (13)

Equation (13) is a non-linear equation with regard to \( t_{i1} \), \( t_{i2} \) can be solved from (13), then \( t_{i2} \) can be solved from (10a), \( \beta_i \) and \( \lambda_i \) can be solved by (7) and \( \theta_i \) can be solved from (2) subsequently.

As the lower platform of PM \( i \) \((i = 2, \ldots, n)\) rotates anticlockwise with its perpendicular by \( 45\times(-1)^i \) degrees relative to the upper platform of PM \( i - 1 \), it leads to:

\[
\mathbf{R}_{n_1(i-1)}^{n_0} = \begin{bmatrix}
\cos[45^\circ \times (-1)^i] & -\sin[45^\circ \times (-1)^i] & 0 \\
\sin[45^\circ \times (-1)^i] & \cos[45^\circ \times (-1)^i] & 0 \\
0 & 0 & 1
\end{bmatrix}
\] (14)

where \( \mathbf{R}_{n_1(i-1)}^{n_0} \) is the rotational matrix from \( \{n_0\} \) to \( \{n_{i-1}\} \).

The centre of the terminal platform \( n^{10}_0\mathbf{o}_n \) can be expressed as follows:

\[
n^{10}_0\mathbf{o}_n = \sum_{i=1}^{n} n^{10}_{1i}\mathbf{R}_{n_1(i-1)}^{n_0} n_{0i}
\]

\[
n^{10}_{10} \mathbf{R} = n^{10}_{11} \mathbf{R}(n^{10}_{12} \mathbf{R} n^{10}_{22} \mathbf{R}) \cdots (n^{10}_{(i-1)} \mathbf{R} n^{10}_{i-1} \mathbf{R}) \quad \cdots \quad (n^{10}_{(i-1)} \mathbf{R} n^{10}_{i-1} \mathbf{R})
\] (15)

where \( \mathbf{E}_{3x3} \) is a \( 3 \times 3 \) form identity matrix.

A composite rotational matrix \( n^{10}_{0i} \mathbf{R} \) from \( \{n_{1i}\} \) to \( \{n_{10}\} \) can be expressed as follows:

\[
n^{10}_{11} \mathbf{R} = n^{10}_{11} \mathbf{R}(n^{10}_{12} \mathbf{R} n^{10}_{22} \mathbf{R}) \cdots (n^{10}_{(i-1)} \mathbf{R} n^{10}_{(i-1)} \mathbf{R}) n^{10}_{01} \mathbf{R}
\] (16)

When given the extension of active limbs \( r_{ij} \) \((i = 1, 2, \ldots, n; j = 1, 2, 3, 4)\), the position vector \( n^{10}_0\mathbf{o}_n \) and \( n^{10}_i\mathbf{R} \) can be solved from (2b), (7), (10a) and (13), and the position and orientation of terminal platform can be solved from (14), (15) and (16) subsequently.

### 2.2 Velocity and Acceleration Modelling of the \( n(4\text{-SPS+SP}) \) S-PM

The objective of the forward velocity and acceleration analysis of the \( n(4\text{-SPS+SP}) \) S-PM is to determine the velocity and acceleration of the terminal platform from a given set of velocities and accelerations of the actuators in a given pose.

Let \( t = [t_x \ t_y \ t_z]^T, \ s = [s_x \ s_y \ s_z]^T \) be two arbitrary vectors, \( S(t) \) be a skew-symmetric matrix. There must be:

\[
S(t) = \begin{bmatrix}
0 & -t_z & t_y \\
t_z & 0 & -t_x \\
-t_y & t_x & 0
\end{bmatrix}, \ S(t) = -S(t)^T, \ t \times s = S(t)s
\]

(17)

The velocity of \( 4\text{-SPS+SP} \) PM has been solved in Ref. [13] as follows:

\[
\mathbf{v}_{ri} = \mathbf{J}_i \begin{bmatrix}
n^{0\omega}_{ri} n^{0\omega}_{oi} \\
n^{0\omega}_{ri} n^{0\omega}_{oi}
\end{bmatrix} = \mathbf{J}_i^{-1} \mathbf{v}_{ri}, \ \mathbf{v}_{ri} = \begin{bmatrix}
\mathbf{v}_{r1i} \\
\mathbf{v}_{r2i} \\
\mathbf{v}_{r3i} \\
\mathbf{v}_{r4i}
\end{bmatrix}
\]

(18)

\[
\mathbf{J}_i = \begin{bmatrix}
\delta_{i1}^T (e_{i1} \times \delta_{i1})^T \\
\delta_{i2}^T (e_{i2} \times \delta_{i2})^T \\
\delta_{i3}^T (e_{i3} \times \delta_{i3})^T \\
\delta_{i4}^T (e_{i4} \times \delta_{i4})^T \\
f_{i1}^T (d_{i1} \times f_{i1})^T \\
f_{i2}^T (d_{i2} \times f_{i2})^T
\end{bmatrix}
\]

(19)

\[
\delta_{ij} = \frac{B_i - A_i}{|B_i - A_i|}, \ \epsilon_i = B_{ij} - \omega_i, \ \ d_{ij} = A_{ij} - \omega_i
\]

where \( n^{0\omega}_{ri} \) and \( n^{0\omega}_{oi} \) are the linear velocity and angular velocity of upper platform relative to lower platform for PM \( i \), respectively. \( \mathbf{v}_{rij} \) \((i = 1, 2, \ldots, n; j = 1, 2, 3, 4)\) is the velocity of \( r_{ij} \) and \( \mathbf{J}_i \) is the inverse Jacobian matrix of PM \( i \).

Let \( n^{0\omega}_{n1} \) and \( n^{10}_\omega \) be the angular velocity and linear velocity of terminal platform \( n_{10} \) relative to \( \{n_{10}\} \).

\[
n^{10}_n\mathbf{R} \] can be expressed as follows:

\[
n^{10}_1 \mathbf{R} = \sum_{i=1}^{k} n^{10}_{1i} \mathbf{R}(n^{10}_{1j} \mathbf{R} n^{10}_{1j} \mathbf{R}) \cdots (n^{10}_{(i-1)} \mathbf{R} n^{10}_{(i-1)} \mathbf{R}) n^{10}_{01} \mathbf{R}
\]

(16)

By differentiating both sides of (15), \( n^{10}_1\mathbf{v}_{n0} \) can be expressed as follows:

\[
n^{10}_1\mathbf{v}_{n0} = \sum_{i=1}^{n} n^{10}_{1i} \mathbf{R}(n^{10}_0 \mathbf{v}_{oi} + (n^{10}_0 \mathbf{R} n^{10}_{1i} \mathbf{v}_{oi}) \mathbf{H} n^{10}_0 \mathbf{R} n^{10}_{1i} \mathbf{v}_{i0})
\]

(20)

The acceleration of \( i \)-th \( 4\text{-SPS+SP} \) PM has been solved in Ref. [13] as follows:

\[
\mathbf{a}_{ri} = \mathbf{J}_i^{-1} \left(S_{ri} - \mathbf{v}_{ri} \mathbf{H} n^{0\omega}_{ri} n^{0\omega}_{ri} \right)
\]

(21)
where \( \alpha_{rij} \) (\( i = 1, 2, \ldots, n; j = 1, 2, 3, 4 \)) is the acceleration along \( r_{ij} \), and \( H_i \) is a \( 6 \times 6 \) Hessian matrix of PM \( i \).

Let \( \omega_{n10} \) and \( \alpha_{n10} \) be the angular acceleration and linear acceleration of terminal platform relative to \( \{n_{10}\} \). By differentiating both sides of (19), \( \omega_{n10} \) can be expressed as follows:

\[
\omega_{n10} = \sum_{i=1}^{n} \left( \omega_{n10} R_{n10} \omega_{n10} + \frac{\omega_{n10} R_{n10} \omega_{n10}}{n_{10}} \right)
\]

By differentiating both sides of (20), \( \alpha_{n10} \) can be expressed as follows:

\[
\alpha_{n10} = \sum_{i=1}^{n} \left( \alpha_{n10} R_{n10} \alpha_{n10} + \frac{\alpha_{n10} R_{n10} \alpha_{n10}}{n_{10}} \right)
\]

From the analytical model above, the kinematics of an \( n \) (4-SPS+SP) S-PM built with an optional number of 4-SPS+SP PMs assembled in series connection can be solved directly.

3. Statics and Stiffness of the \( n \)(4-SPS+SP) S-PM

The objective of statics analysis of the \( n \)(4-SPS+SP) S-PM is to determine the active forces applied on actuators when given external force and torque applied on terminal platform in a given pose. The objective of stiffness model is to determine a mapping matrix, which reveals the relation between compliant deformations of the terminal platform and the given external wrench applied on terminal platform.

Let \( F \) and \( T \) be external force and torque applied on terminal platform \( n_{11} \), respectively.

Equation (20) leads to:

\[
\omega_{n10} = \sum_{i=1}^{n} \left[ \omega_{n10} R_{n10} \omega_{n10} + \frac{\omega_{n10} R_{n10} \omega_{n10}}{n_{10}} \right]
\]

By combining (19) and (24), the velocity of terminal platform can be expressed as:

\[
\omega_{n10} = \sum_{i=1}^{n} \left[ \omega_{n10} R_{n10} \omega_{n10} + \frac{\omega_{n10} R_{n10} \omega_{n10}}{n_{10}} \right]
\]

Based on the forces situations of the 4SPS+SP PM [14], it is known that there are four active force along SPS legs and two constrained forces in SP leg. The two constrained forces are exerted on \( r_{10} \) at \( S \) joint and parallel with \( x_i \) and \( y_i \) axes, respectively.

Let \( \omega_{10} F \) and \( \omega_{10} T \) be the external force and torque applied on terminal platform relative to base \( \{n_{10}\} \). Let \( F_{rij} (i = 1, 2, \ldots, n; j = 1, 2, 3, 4) \) be the active forces and \( F_{bij} (i = 1, 2, \ldots, n; j = 1, 2) \) be the constrained forces of
PM \( i \) for \( n(4\text{-}SPS+\text{SP}) \) S-PM. From (25) and the principle of virtual work, we obtain,

\[
F_{s1}^T v_{r1} + F_{s2}^T v_{r2} + \cdots + F_{sn}^T v_{rn} = -\begin{bmatrix} n_{io} F \\ n_{io} T \end{bmatrix}^T \begin{bmatrix} n_{io} \phi_{oni} \\ n_{io} \omega_{oni} \end{bmatrix}
\]

\[
= -\begin{bmatrix} n_{io} F \\ n_{io} T \end{bmatrix} \sum_{i=1}^{k} J_{Ri} \begin{bmatrix} n_{io} \phi_{ori} \\ n_{io} \omega_{ori} \end{bmatrix} - \begin{bmatrix} n_{io} F \\ n_{io} T \end{bmatrix} \sum_{i=1}^{k} J_{Ri} J_i^{-1} v_{ri}
\]

\[
F_{si} = \begin{bmatrix} F_{ri1} \\ F_{ri2} \\ F_{ri3} \\ F_{ri4} \\ F_{pil} \\ F_{pi2} \end{bmatrix}^T (26)
\]

where \( F_{si} \) \( (i = 1, 2, \ldots, n) \) is the six-dimensional vector formed by active and constrained forces/torques of PM \( i \).

Equation (26) leads to:

\[
\begin{bmatrix} v_{r1} \\ \vdots \\ v_{rn} \end{bmatrix} = -\begin{bmatrix} n_{io} F \\ n_{io} T \end{bmatrix} \begin{bmatrix} n_{io} \phi_{oni} \\ n_{io} \omega_{oni} \end{bmatrix} \times \begin{bmatrix} J_{R1} J_1^{-1} \\ \vdots \\ J_{Rn} J_n^{-1} \end{bmatrix} \begin{bmatrix} v_{r1} \\ \vdots \\ v_{rn} \end{bmatrix} (27a)
\]

Equation (27a) leads to:

\[
F_{si} = -(J_{Ri} J_i^{-1})^T \begin{bmatrix} n_{io} F \\ n_{io} T \end{bmatrix} (27b)
\]

From (27b), \( F_{rij} \) and \( F_{pij} \) \( (i = 1, 2, \ldots, n; j = 1, 2, 3, 4) \) can be solved when \( n_{io} F \) and \( n_{io} T \) are given.

For SPS legs, the active force \( F_{rij} \) \( (i = 1, 2, \ldots, n; j = 1, 2, 3, 4) \) produce tension deformation along \( r_i \). Let \( \delta d_{rij} \) be the tension deformation along \( r_{ij} \) due to the active forces \( F_{rij} \), then,

\[
F_{rij} = k_{rij} \delta d_{rij}, \quad k_{rij} = \frac{ES_{ij}}{r_{ij}} (28)
\]

where \( E \) is the modulus of elasticity and \( S_{ij} \) is the \( j \)-th SPS leg’s cross section of PM \( i \).

For SP legs, the constrained forces \( F_{pij} \) \( (i = 1, 2, \ldots, n; j = 1, 2) \) at \( S \) joint in \( r_{io} \) can be equivalent to one force \( F_{tij} \) at \( o \), which is parallel with \( F_{pij} \) and one torque \( T_{tij} \) which is perpendicular with \( F_{pij} \) and \( r_{io} \). It leads to:

\[
F_{tij} = F_{pij} (29a)
\]

\[
T_{tij} = r_{io} \times F_{pij} = F_{pij} r_{io}(z_i \times x_i) = F_{pij} r_{io} y_i,
\]

\[
T_{tij} = F_{pij} r_{io}
\]

\[
T_{s1} = r_{io} \times F_{pi2} = F_{pi2} r_{io}(z_i \times y_i) = -F_{pi2} r_{io} x_i,
\]

\[
T_{s2} = -F_{pi2} r_{io}
\]

\[
F_{tij} \) produces flexibility deformation and \( T_{tij} \) produces bending deformation in \( r_{io} \). Let \( \delta d_{tij} \) be the flexibility deformation of \( r_{io} \) due to \( F_{tij} \). Let \( \delta \theta_{tij} \) be the bending deformation of \( r_{io} \) due to the constrained torques \( T_{pij} \).

\[
F_{tij} \) produces flexibility deformation \( \delta d_{tij} \), thus we obtain:

\[
F_{tij} = k_{tij} \delta d_{tij}, \quad k_{tij} = \frac{3EI}{r_{ij}^3} (30a)
\]

where \( I \) is the moment inertia.

\( T_{tij} \) produces bending deformation \( \delta \theta_{tij} \), thus we obtain:

\[
T_{tij} = s_{tij} \delta \theta_{tij}, \quad s_{tij} = \frac{EI}{r_{ij}} (30b)
\]

Equations (29a) and (29b) lead to:

\[
F_{mi} = G_i F_{si}, \quad F_{mi} = \begin{bmatrix} F_{ri1} \\ F_{ri2} \\ F_{ri3} \\ F_{ri4} \\ F_{pil} \\ F_{pi2} \end{bmatrix}
\]

\[
G_i = \begin{bmatrix} 1 & 0 & 0 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 & 0 & 0 \\ 0 & 0 & 1 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 0 & 0 & -r_{io} \end{bmatrix} (31)
\]

Equations (29a) and (29b) lead to:

\[
F_{mi} = K_{mi} \delta d_{mi}, \quad \delta d_{mi} = C_{mi} F_{mi}, \quad C_{mi} = K_{mi}^{-1}
\]

\[
\delta d_{mi} = \begin{bmatrix} d_{r11} & d_{r12} & d_{r13} & d_{r14} & d_{rs1} & d_{rs2} & \theta_{s1} & \theta_{s2} \end{bmatrix}
\]

\[
K_{mi} = \text{diag}\begin{bmatrix} k_{r11} & k_{r12} & k_{r13} & k_{r14} & k_{rs1} & k_{rs2} & s_{s1} & s_{s2} \end{bmatrix} (32)
\]

Equations (27b) and (31) lead to:

\[
F_{mi} = F_{st} G_i^T = \begin{bmatrix} n_{io} F \\ n_{io} T \end{bmatrix} (J_{Ri} J_i^{-1}) G_i^T (33)
\]
Based on the principle of virtual work and (33),

\[ F_{m1}^T \delta d_{m1} + F_{m2}^T \delta d_{m2} + \cdots + F_{mn}^T \delta d_{mn} = - \begin{bmatrix} n_{10} F \end{bmatrix}_T \]

where \( \delta \rho \) is the deformation of terminal platform. Equation (34) leads to:

\[ \delta \rho = - \sum_{i=1}^{n} (J_{Ri} J_{i}^{-1}) G_i^T \delta d_{mi} \quad (35) \]

Equations (31), (32) and (35) lead to:

\[ \delta d_{mi} = C_{mi} G_i F_{si} = -C_{mi} G_i (J_{Ri} J_{i}^{-1})^T \begin{bmatrix} n_{10} F \end{bmatrix}_T \]

\[ \delta \rho = - \sum_{i=1}^{n} (J_{Ri} J_{i}^{-1}) G_i^T C_{mi} G_i (J_{Ri} J_{i}^{-1})^T \begin{bmatrix} n_{10} F \end{bmatrix}_T \quad (36) \]

Equations (35) and (36) lead to:

\[ \begin{bmatrix} n_{10} F \\ n_{10} T \end{bmatrix} = K \delta \rho, \]

\[ K = - \sum_{i=1}^{n} (J_{Ri} J_{i}^{-1}) G_i^T C_{mi} G_i (J_{Ri} J_{i}^{-1})^T \]

Here \( K \) is a 6 x 6 stiffness matrix of \( n(4-\text{SPS+SP}) \) S-PM. The elastic deformation can be solved from (36) when external force and torque applied on terminal platform are given. The stiffness matrix \( K \) of the \( n(4-\text{SPS+SP}) \) S-PM can be solved from (37).

For this \( n(4-\text{SPS+SP}) \) S-PM, the active forces produce 4n longitudinal deformations along SPS active legs, while the constrained force produces 2n flexibility deformation and 2n bending deformation in SP legs. The 8n deformations that are present in SPS and SP legs affect the deformation and stiffness.

4. Analytically Solved Example

In this part, the \( 3(4-\text{SPS+SP}) \) S-PM is analysed to illustrate the kinematics, statics and stiffness model.

Figure 3 is a \( 3(4-\text{SPS+SP}) \) S-PM formed by three \( 4-\text{SPS+SP} \) PMs connected in series. Set \( E = 2.11 \times 10^{11} \) Pa, \( EI = 26.502 \) N m^2, \( S_i = 0.0013 \) m^2, \( G = 80 \times 10^9 \) Pa, \( I_p = 2.5120 \times 10^{-7} \) m^4. The dimension parameters of the serial-PM and the length, velocity and acceleration of \( r_{ij} \) (i = 1, 2, 3; j = 1, 2, 3, 4) are given in Table 1.

The pose of PM i (i = 1, 2, 3, 4) is solved as follows.

The results show that the single \( 4-\text{SPS+SP} \) PM have 16 solutions (Table 2). From (7), (10a) and (2b), the corresponding pose parameters can be obtained. To determine the acceptable analytic solutions from multisolutions, the simulation mechanism is created [15] using CAD software and the forward kinematics can be solved by the simulation mechanism. By comparing, it is known that the simulation solution coincides with the first solution solved by the analytic method for PM i. Using this solution, the reasonable pose of the upper platform PM i is solved in Table 3.

The position, velocity and acceleration of terminal platform of \( 3(4-\text{SPS+SP}) \) S-PM are solved in Table 4.

When the workloads applied at \( \sigma_k \) is given as \( n_o F_o = (-20 -30 -60)^T \) N, \( n_o T_o = (0 0 0)^T \) N m, the active forces and constrained forces in \( r_{ij} \) and \( r_{oi} \) for PM i can be solved in Table 5.

The tension, flexibility, bending deformations of \( r_{ij} \) can be solved in Table 6.

The deformation of the terminal platform of \( 3(4-\text{SPS+SP}) \) S-PM is derived as:

\[ \delta \rho = (0.0031 -0.0002 0.0063 -0.0101 -0.0241 -0.0164)^T \]

The stiffness matrix of \( 3(4-\text{SPS+SP}) \) S-PM is derived as follows:

\[ K = 10^4 \begin{bmatrix} -0.5420 & -0.1218 & -0.7521 & -0.0512 & -0.1134 & -0.0659 \\ -0.1218 & -0.6972 & -0.4363 & 0.6850 & -0.5036 & 0.3216 \\ -0.7521 & -0.4363 & -2.0434 & -0.5091 & -0.0497 & -0.1609 \\ -0.0512 & 0.6850 & -0.5091 & -3.3027 & 2.0427 & -1.1804 \\ -0.1134 & -0.5036 & -0.0497 & 2.0427 & -1.4824 & 0.8866 \\ -0.0659 & 0.3216 & -0.1609 & -1.1804 & 0.8866 & -0.6532 \end{bmatrix} \]
Table 1
The Dimension Parameters, Length, Velocity and Acceleration of $r_{ij}$

<table>
<thead>
<tr>
<th></th>
<th>$L$ (m)</th>
<th>$l_1$ (m)</th>
<th>$l_2$ (m)</th>
<th>$r_1$ (m)</th>
<th>$r_2$ (m)</th>
<th>$r_3$ (m)</th>
<th>$r_4$ (m)</th>
<th>$v_{r_1}$ (m/s)</th>
<th>$v_{r_2}$ (m/s)</th>
<th>$v_{r_3}$ (m/s)</th>
<th>$v_{r_4}$ (m/s)</th>
<th>$a_{r_1}$ (m/s²)</th>
<th>$a_{r_2}$ (m/s²)</th>
<th>$a_{r_3}$ (m/s²)</th>
<th>$a_{r_4}$ (m/s²)</th>
</tr>
</thead>
<tbody>
<tr>
<td>PM 1</td>
<td>0.5</td>
<td>0.45</td>
<td>0.4</td>
<td>0.70</td>
<td>0.66</td>
<td>0.76</td>
<td>0.80</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
</tr>
<tr>
<td>PM 2</td>
<td>0.4257</td>
<td>0.4</td>
<td>0.35</td>
<td>0.62</td>
<td>0.58</td>
<td>0.70</td>
<td>0.75</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
</tr>
<tr>
<td>PM 3</td>
<td>0.3758</td>
<td>0.35</td>
<td>0.3</td>
<td>0.75</td>
<td>0.61</td>
<td>0.65</td>
<td>0.78</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
<td>0.1</td>
</tr>
</tbody>
</table>

Table 2
The 16 Solutions of $t_{11}$, $t_{21}$ and $t_{31}$

<table>
<thead>
<tr>
<th></th>
<th>$t_{11}$</th>
<th>$t_{21}$</th>
<th>$t_{31}$</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>0.10928</td>
<td>-0.10928</td>
<td>0.2222</td>
</tr>
<tr>
<td></td>
<td>6.95</td>
<td>-6.95</td>
<td>7.1614</td>
</tr>
<tr>
<td></td>
<td>0.079 - 0.218i</td>
<td>-0.079 + 0.218i</td>
<td>-0.73266i</td>
</tr>
<tr>
<td></td>
<td>-1.236i</td>
<td>1.236i</td>
<td>0.079 + 0.218i</td>
</tr>
<tr>
<td></td>
<td>0.16182</td>
<td>-0.16182</td>
<td>0.2718</td>
</tr>
<tr>
<td></td>
<td>4.8737</td>
<td>-4.8737</td>
<td>4.9752</td>
</tr>
<tr>
<td></td>
<td>0.064 - 0.253i</td>
<td>0.064 + 0.253i</td>
<td>-0.754i</td>
</tr>
<tr>
<td></td>
<td>-1.217i</td>
<td>1.2168i</td>
<td>0.064 + 0.253i</td>
</tr>
<tr>
<td></td>
<td>0.19711</td>
<td>-0.19711</td>
<td>0.25784</td>
</tr>
<tr>
<td></td>
<td>4.3722</td>
<td>-4.3722</td>
<td>4.5613</td>
</tr>
<tr>
<td></td>
<td>0.273 - 0.069i</td>
<td>-0.273 + 0.069i</td>
<td>-0.849i</td>
</tr>
<tr>
<td></td>
<td>-1.1236i</td>
<td>1.1236i</td>
<td>0.273 + 0.069i</td>
</tr>
</tbody>
</table>

Table 3
The Pose of Single 4-SPS+SP PM

<table>
<thead>
<tr>
<th></th>
<th>$\alpha$ (°)</th>
<th>$\beta$ (°)</th>
<th>$\lambda$ (°)</th>
<th>$X_o$ (m)</th>
<th>$Y_o$ (m)</th>
<th>$Z_o$ (m)</th>
</tr>
</thead>
<tbody>
<tr>
<td>PM 1</td>
<td>21.8014</td>
<td>12.4736</td>
<td>-22.8961</td>
<td>0.1460</td>
<td>0.0584</td>
<td>0.7108</td>
</tr>
<tr>
<td>PM 2</td>
<td>19.9651</td>
<td>18.3838</td>
<td>-35.4613</td>
<td>0.1948</td>
<td>0.0708</td>
<td>0.6236</td>
</tr>
<tr>
<td>PM 3</td>
<td>75.6454</td>
<td>22.3011</td>
<td>-40.2939</td>
<td>0.0641</td>
<td>0.2503</td>
<td>0.6300</td>
</tr>
</tbody>
</table>

Table 4
The Position, Velocity and Acceleration of Terminal Platform of 3(4-SPS+SP) S-PM

<table>
<thead>
<tr>
<th>$n^0\omega_k$ (m)</th>
<th>$n^0\nu_k$ (m/s)</th>
<th>$n^0\omega_k$ (rad/s)</th>
<th>$n^0\nu_k$ (m/s²)</th>
<th>$n^0\nu_k$ (rad/s²)</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.6896</td>
<td>0.1060</td>
<td>0.0296</td>
<td>0.1086</td>
<td>0.0313</td>
</tr>
<tr>
<td>0.7198</td>
<td>0.0988</td>
<td>0.0438</td>
<td>0.0968</td>
<td>0.0439</td>
</tr>
<tr>
<td>1.7168</td>
<td>0.2460</td>
<td>0.0225</td>
<td>0.2457</td>
<td>0.0231</td>
</tr>
</tbody>
</table>

Table 5
Active Forces and Constrained Forces in $r_{ij}$ and $r_{oi}$

<table>
<thead>
<tr>
<th></th>
<th>$F_{a1}$</th>
<th>$F_{a2}$</th>
<th>$F_{a3}$</th>
<th>$F_{a4}$</th>
<th>$F_{p1}$</th>
<th>$F_{p2}$</th>
</tr>
</thead>
<tbody>
<tr>
<td>PM 1</td>
<td>122.7</td>
<td>-77.592</td>
<td>94.002</td>
<td>-73.932</td>
<td>7.8668</td>
<td>21.363</td>
</tr>
<tr>
<td>PM 2</td>
<td>128.99</td>
<td>-62.19</td>
<td>95.754</td>
<td>-93.604</td>
<td>3.4628</td>
<td>8.8176</td>
</tr>
<tr>
<td>PM 3</td>
<td>-298.21</td>
<td>330.93</td>
<td>-226.3</td>
<td>257.91</td>
<td>0.90207</td>
<td>-30.954</td>
</tr>
</tbody>
</table>
Table 6
Deformations in $r_{ij}$ and $r_{oi}$

<table>
<thead>
<tr>
<th></th>
<th>$\delta r_1$ (10^{-7} m)</th>
<th>$\delta r_2$ (10^{-7} m)</th>
<th>$\delta r_3$ (10^{-7} m)</th>
<th>$\delta r_4$ (10^{-7} m)</th>
<th>$\delta d_1$ (10^{-5} m)</th>
<th>$\delta d_2$ (10^{-3} m)</th>
<th>$\delta \theta_1$ (10^{-4} rad)</th>
<th>$\delta \theta_2$ (10^{-9} rad)</th>
</tr>
</thead>
<tbody>
<tr>
<td>PM 1</td>
<td>12.96</td>
<td>-7.73</td>
<td>10.78</td>
<td>-8.93</td>
<td>61.25</td>
<td>16.59</td>
<td>25.2</td>
<td>6.84</td>
</tr>
<tr>
<td>PM 2</td>
<td>12.07</td>
<td>-5.44</td>
<td>10.12</td>
<td>-10.60</td>
<td>19.78</td>
<td>50.36</td>
<td>9.03</td>
<td>2.30</td>
</tr>
<tr>
<td>PM 3</td>
<td>-3.38</td>
<td>3.05</td>
<td>-22.20</td>
<td>-40.36</td>
<td>-5.73</td>
<td>1.97</td>
<td>2.52</td>
<td>8.67</td>
</tr>
</tbody>
</table>

Figure 4. Solved results of elastic deformations of FE model of 3(4-SPS+SP) S-PM: (a) the created FE model of 3(4-SPS+SP) S-PM and (b) the simulated results of 3(4-SPS+SP) S-PM.

The results show that the constrained forces produce large deformations compared with the active forces. The constrained forces have a great influence on the elastic deformation and stiffness of the 3(4-SPS+SP) S-PM. When establishing the stiffness matrix and solving the elastic deformation of this S-PM, the constrained forces must be considered based on its geometric constraints. The stiffness matrix is a symmetrical 6 x 6 form matrix.

In this section, a 3D assembly mechanism and a finite-element (FE) model of 3(4-SPS+SP) S-PM is established in FE software (see Fig. 4(a)) according to dimension and material parameters described above.

In the FE model, the spherical joint is replaced by three revolute joints. The linear active leg with prismatic joint is formed using the elastic linear rod. The simulated results based on FE model for the deformation of the terminal platform are solved as shown in Fig. 4(b) and Table 7.

It is well known that the FE analysis is a numerical technique for finding approximate solutions. The solved results of FE model built in FE software depend on some key factors such as material parameter, FE dimension and type, reasonable boundary constraints and connection constraints. The results in Table 7 shows that the elastic deformation of FE model of 3(4-SPS+SP) S-PM is basically coincident with that of analytical ones in this section.

Table 7
The Simulated Result Based on FE Model and the Calculated Result Based on Stiffness Model for the Deformation of Terminal Platform

<table>
<thead>
<tr>
<th>Elastic Deformation of o (mm)</th>
<th>FE Model</th>
<th>Analytics</th>
</tr>
</thead>
<tbody>
<tr>
<td>$\delta x$</td>
<td>-5.63</td>
<td>-3.1</td>
</tr>
<tr>
<td>$\delta y$</td>
<td>-2.225</td>
<td>-2</td>
</tr>
<tr>
<td>$\delta z$</td>
<td>-7.0141</td>
<td>-6.3</td>
</tr>
</tbody>
</table>

5. Conclusion

The kinematics, statics and stiffness of a novel $n(4$-SPS+SP) S-PM is analysed in this paper. This S-PM has $n$ 4-SPS+SP PM. The forward displacement of 4-SPS+SP PM is derived in close form, and the result shows that the 4-SPS+SP PM has 16 solutions forward displacements. The kinematics of $n(4$-SPS+SP) serial-PM is solved based on the kinematical result of 4-SPS+SP PM.

The formula for solving the statics of $n(4$-SPS+SP) S-PM is derived. From this formula, the active and
constrained forces in SPS active and SP constrained legs are solved, respectively. The deformations in SPS and SP legs are analysed in detail with both active and constrained forces being considered. Based on the principle of virtual work, the deformation of the terminal platform of n(4-SPS+SP) and the 6 x 6 stiffness matrix are derived.

The kinematics, statics, elastic deformations and stiffness of 3(4-SPS+SP) are computed. The analytical results are verified by CAD software. The simulation solution of constrained forces in SPS active and SP constrained legs are analysed in detail with both active and constrained forces. Based on the principle of virtual work, the deformation of the terminal platform of n(4-SPS+SP) and the 6 x 6 stiffness matrix are derived.

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References


Biographies

Bo Hu was born in 1982 in Hubei, People’s Republic of China. He got his B.S. degree at Hubei University of Technology in Wuhan, People’s Republic of China, in 2004. and a Ph.D. at the School of Mechanical Engineering, Yanshan University in Qinhuangdao, People’s Republic of China, in 2010. His major research focuses on kinematics and dynamics of robotic systems. He has authored/co-authored more than 30 regular papers published in several journals approaching these topics.

Shan Zhuang was born in 1985 in Heilongjiang, People’s Republic of China. She got her B.S. degree and M.S. degree at China Agricultural University of Technology in Beijing in 2004 and 2009, respectively. She is currently a teaching assistant at the School of Mechanical Engineering, Yanshan University.

Yi Lu got his B.S. and M.S. (engineering) degrees at Northeast Heavy Machinery Institute in Qiqihar, P.R. China, and Dr. Sc. Tech. degree in 1997 at the University of Oulu, Finland. He was a researcher at the University of Oulu during 1993–2001, and completed his post-doctoral research in 2000. Dr. Yi Lu has been a Professor of the College of Mechanical Engineering since 1998, and a supervisor of doctoral candidates since 2004 at Yanshan University in Qinhuangdao, P.R. China. He has published more than 180 papers.
Chunping Sui was born in 1974 in Liaoning, P.R. China. He got his B.S. degree and M.S. degrees at Northeastern University in Shenyang, People’s Republic of China, in 1997 and 2000 respectively, and Ph.D. at State Key Laboratory of Robotics, Shenyang Institute of Automation, Shenyang, P.R. China in 2004. He has been an Associated Professor at State Key Laboratory of Robotics, Shenyang Institute of Automation. His major research focuses on dynamics and control of robotic systems.

Jianda Han got his Ph.D at Harbin Institute of Technology in Harbin, P.R. China, in 1998. He served as a Visiting Scholar at Chinese University of Hong Kong during 1998–1999 and Michigan State University during 2001–2002. Dr. Han has been a supervisor of doctoral candidates since 2002 at State Key Laboratory of Robotics, Shenyang Institute of Automation. His major research focuses on robotics and control.

Jingjing Yu was born in 1981 in Hebei, P.R. China. She got her B.S. degree at Yanshan University of in Qinhuangdao, P.R. China, in 2004, and M.E. degree at School of Mechanical Engineering, Yanshan University in Qinhuangdao, P.R. China, in 2007. Her major research focuses on kinematics and dynamics of robotic systems. She has authored/co-authored more than 10 regular papers published in several journals approaching these topics.