



# Parallel Robots

**M Carnoy**



## **Parallel Robots:**

**Parallel Robots** J.-P. Merlet, 2012-12-06 Parallel robots are closed loop mechanisms presenting very good performances in terms of accuracy rigidity and ability to manipulate large loads Parallel robots have been used in a large number of applications ranging from astronomy to flight simulators and are becoming increasingly popular in the field of machine tool industry This book presents a complete synthesis of the latest results on the possible mechanical architectures analysis and synthesis of this type of mechanism It is intended to be used by students with over 100 exercises and numerous Internet addresses researchers with over 500 references and anonymous ftp access to the code of some algorithms presented in this book and engineers for which practical results and applications are presented **Parallel Robots** Hamid D.

Taghirad, 2013-02-20 Parallel structures are more effective than serial ones for industrial automation applications that require high precision and stiffness or a high load capacity relative to robot weight Although many industrial applications have adopted parallel structures for their design few textbooks introduce the analysis of such robots in terms of dynamics

*Parallel Robots With Unconventional Joints* Patrick Grosch, Federico Thomas, 2019-03-20 This book shows how through certain geometric transformations some of the standard joints used in parallel robots can be replaced with lockable or non holonomic joints These substitutions allow for reducing the number of legs and hence the number of actuators needed to control the robot without losing the robot's ability to bring its mobile platform to the desired configuration The kinematics of the most representative examples of these new designs are analyzed and their theoretical features verified through simulations and practical implementations **Parallel Robots** J.P. Merlet, 2005-12-27 Parallel robots are closed loop

mechanisms presenting very good performances in terms of accuracy velocity rigidity and ability to manipulate large loads They have been used in a large number of applications ranging from astronomy to flight simulators and are becoming increasingly popular in the field of machine tool industry This book presents a complete synthesis of the latest results on the possible mechanical architectures analysis and synthesis of this type of mechanism It is intended to be used by students with over 150 exercises and numerous internet addresses researchers with over 650 references and anonymous ftp access to the code of some algorithms presented in this book and engineers for which practical results mistakes to avoid and applications are presented Since the publication of the first edition 2000 there has been an impressive increase in terms of study and use of this kind of structure that are reported in this book This second edition has been completely overhauled The initial chapter on kinematics has been split into Inverse Kinematics and Direct Kinematics A new chapter on calibration was added The other chapters have also been rewritten to a large extent The reference section has been updated to include around 45% new works that appeared after the first edition **Dynamics of Parallel Robots** Sébastien Briot, Wisama Khalil, 2015-06-22 This book starts with a short recapitulation on basic concepts common to any types of robots serial tree structure parallel etc that are also necessary for computation of the dynamic models of parallel robots Then as dynamics requires the use of geometry

and kinematics the general equations of geometric and kinematic models of parallel robots are given After it is explained that parallel robot dynamic models can be obtained by decomposing the real robot into two virtual systems a tree structure robot equivalent to the robot legs for which all joints would be actuated plus a free body corresponding to the platform Thus the dynamics of rigid tree structure robots is analyzed and algorithms to obtain their dynamic models in the most compact form are given The dynamic model of the real rigid parallel robot is obtained by closing the loops through the use of the Lagrange multipliers The problem of the dynamic model degeneracy near singularities is treated and optimal trajectory planning for crossing singularities is proposed Lastly the approach is extended to flexible parallel robots and the algorithms for computing their symbolic model in the most compact form are given All theoretical developments are validated through experiments

**Cable-Driven Parallel Robots** Andreas Pott, 2018-03-27 Cable driven parallel robots are a new kind of lightweight manipulators with excellent scalability in terms of size payload and dynamics capacities For the first time a comprehensive compendium is presented of the field of cable driven parallel robots A thorough theory of cable robots is setup leading the reader from first principles to the latest results in research The main topics covered in the book are classification terminology and fields of application for cable driven parallel robots The geometric foundation of the standard cable model is introduced followed by statics force distribution and stiffness Inverse and forward kinematics are addressed by elaborating efficient algorithms Furthermore the workspace is introduced and different algorithms are detailed The book contains the dynamic equations as well as simulation models with applicable parameters Advanced cable models are described taking into account pulleys elastic cables and sagging cables For practitioner a descriptive design method is stated including methodology parameter synthesis construction design component selection and calibration Rich examples are presented by means of simulation results from sample robots as well as experimental validation on reference demonstrators The book contains a representative overview of reference demonstrator system Tables with physical parameters for geometry cable properties and robot parameterizations support case studies and are valuable references for building custom cable robots For scientist the book provides the starting point to address new scientific challenges as open problems are named and a commented review of the literature on cable robot with more than 500 references are given [Cable-Driven Parallel Robots](#)

Tobias Bruckmann, Andreas Pott, 2012-09-13 This publication presents the outcome of the First International Conference on Cable Driven Parallel Robots in 2012 This is the first conference to bring together the cable robot community and dedicate a forum for the international experts of this field It contains the Know how ideas and experiences of active researchers developing cable driven robots The book presents the state of the art including summarizing contributions and latest research results and where relevant the future outlook The book covers the essential topics for cable driven robots classification and definition kinematics workspace analysis cable modeling control and calibration design methodology hardware prototype development experimental evaluation application reports and new application concepts [Dynamics of](#)

Parallel Robots Stefan Staicu,2018-09-14 This book establishes recursive relations concerning kinematics and dynamics of constrained robotic systems It uses matrix modeling to determine the connectivity conditions on the relative velocities and accelerations in order to compare two efficient energetic ways in dynamics modeling the principle of virtual work and the formalism of Lagrange s equations First a brief fundamental theory is presented on matrix mechanics of the rigid body which is then developed in the following five chapters treating matrix kinematics of the rigid body matrix kinematics of the composed motion kinetics of the rigid body dynamics of the rigid body and analytical mechanics By using a set of successive mobile frames the geometrical properties and the kinematics of the vector system of velocities and accelerations for each element of the robot are analysed The dynamics problem is solved in two energetic ways using an approach based on the principle of virtual work and applying the formalism of Lagrange s equations of the second kind These are shown to be useful for real time control of the robot s evolution Then the recursive matrix method is applied to the kinematics and dynamics analysis of five distinct case studies planar parallel manipulators spatial parallel robots planetary gear trains mobile wheeled robots and finally two module hybrid parallel robots

*Parallel Robots* J.P. Merlet,2000-07-31 Parallel robots are closed loop mechanisms presenting very good performances in terms of accuracy rigidity and ability to manipulate large loads Parallel robots have been used in a large number of applications ranging from astronomy to flight simulators and are becoming increasingly popular in the field of machine tool industry This book presents a complete synthesis of the latest results on the possible mechanical architectures analysis and synthesis of this type of mechanism It is intended to be used by students with over 100 exercises and numerous Internet addresses researchers with over 500 references and anonymous ftp access to the code of some algorithms presented in this book and engineers for which practical results and applications are presented

Serial and Parallel Robot Manipulators Serdar Küçük,2012-03-30 The robotics is an important part of modern engineering and is related to a group of branches such as electric

Parallel Manipulators Cecilia Norton,2016 Robots are a key element in current industrial processes as they can be applied to a number of tasks increasing both quality and productivity Traditionally serial robots have been installed in factories as their wide operating space allowed them to fulfill a number of tasks However due to their high moving mass and single kinematic chain structure these robots present some disadvantages when high speed accuracy or heavy load handling tasks have to be executed Parallel robots provide an interesting alternative to these application fields as their multiple kinematic chain structure offers increased stiffness allowing reduced positioning errors lighter mechanisms and increased load weight ratios In this book Chapter One addresses a new control strategy for parallel manipulators based on L1 adaptive control This latter is known for its decoupled control and estimation loops enabling fast adaptation and guaranteed robustness Chapter Two focuses on the control of parallel robots Chapter Three reviews structure synthesis of fully isotropic two rotational and two translational parallel robotic manipulators Chapter Four reviews the new prototype of the two legged parallel kinematic walking robot CENTAUROB

developed at Hamburg University of Technology Chapter Five analyzes and robustly controls the 6 DOF 3 legged Wide Open parallel manipulator using a Lyapunov analysis approach **Industrial Robotics**, 2004 **Cable-Driven Parallel Robots** Stéphane Caro, Andreas Pott, Tobias Bruckmann, 2023-07-04 This volume gathers the latest advances innovations and applications in the field of cable robots as presented by leading international researchers and engineers at the 6th International Conference on Cable Driven Parallel Robots CableCon held in Nantes France on June 25 28 2023 It covers the theory and applications of cable driven parallel robots including their classification kinematics and singularity analysis workspace statics and dynamics cable modeling and technologies control and calibration design methodologies hardware development experimental evaluation and prototypes as well as application reports and new application concepts The contributions which were selected through a rigorous international peer review process share exciting ideas that will spur novel research directions and foster new multidisciplinary collaborations **Robotics** Matjaž Mihelj, Tadej Bajd, Aleš Ude, Jadran Lenarčič, Aleš Stanovnik, Marko Munih, Jure Rejc, Sebastjan Šlajpah, 2018-07-25 This book introduces readers to robotics industrial robot mechanisms and types of robots e g parallel robots mobile robots and humanoid robots The book is based on over 20 years of teaching robotics and has been extensively class tested and praised for its simplicity It addresses the following subjects a general introduction to robotics basic characteristics of industrial robot mechanisms position and movement of an object which are described by homogenous transformation matrices a geometric model of robot mechanisms expanded with robot wrist orientation description in this new edition a brief introduction to the kinematics and dynamics of robots robot sensors and planning of robot trajectories fundamentals of robot vision basic control schemes resulting in either desired end effector trajectory or force robot workcells with feeding devices and robot grippers This second edition has been expanded to include the following new topics parallel robots collaborative robots teaching of robots mobile robots and humanoid robots The book is optimally suited for courses in robotics or industrial robotics and requires a minimal grasp of physics and mathematics The 1st edition of this book won the Outstanding Academic Title distinction from the library magazine CHOICE in 2011 **Cable-Driven Parallel Robots** Andreas Pott, Tobias Bruckmann, 2014-08-14 This volume presents the outcome of the second forum to cable driven parallel robots bringing the cable robot community together It shows the new ideas of the active researchers developing cable driven robots The book presents the state of the art including both summarizing contributions as well as latest research and future options The book cover all topics which are essential for cable driven robots Classification Kinematics Workspace and Singularity Analysis Statics and Dynamics Cable Modeling Control and Calibration Design Methodology Hardware Development Experimental Evaluation Prototypes Application Reports and new Application concepts **Parallel PnP Robots** Guanglei Wu, 2025-03-24 This book provides the design and application of multiple control algorithms and motion planning to a family of parallel robots which can be generalized to other robot counterparts The book covers the fundamentals of dynamic models for control design as well as a comparison of

the control effects from the classical to advanced control algorithms step by step which can help the researcher to understand the design procedure of control algorithms It also includes different trajectory planning algorithms to ensure optimal robot performances Furthermore the research results previously scattered in many prestigious journals and conferences worldwide are methodically edited and presented in a unified form The book is likely to be of interest to university researchers R D engineers and graduate students in industrial parallel robotics who wish to learn the core principles methods algorithms and applications

**Mechatronics, Robotics and Automation** Yun Hae Kim,2013-08-30  
Selected peer reviewed papers from the 2013 International Conference on Mechatronics Robotics and Automation ICMRA 2013 June 13 14 2013 Guangzhou China

**Control, Instrumentation and Mechatronics: Theory and Practice**  
Norhaliza Abdul Wahab,Zaharuddin Mohamed,2022-07-07 This proceeding includes original and peer reviewed research papers from the 3rd International Conference on Control Instrumentation and Mechatronics Engineering CIM2022 The conference is a virtual conference held on 2 3 March 2022 The topics covered latest work and finding in the area of Control Engineering Mechatronics Robotics and Automation Artificial Intelligence Manufacturing Sensor Measurement and Instrumentation Moreover the latest applications of instrumentations control and mechatronics are provided Therefore this proceeding is a valuable material for researchers academicians university students and engineers

New Frontiers in Parallel Robots Zhufeng Shao,Dan Zhang,Stéphane Caro,2023-07-05 The parallel robot a kind of robot that utilizes multiple closed loop branch chains jointly connecting and driving the moving platform is an important part of modern robotics with outstanding advantages of high stiffness high precision and high speed Parallel robots can efficiently change performance through the configuration of synthesis and design The rich variety of configurations and the existence of a large number of passive joints also brought abundant challenges and research topics to the modeling optimization calibration and trajectory planning of parallel robots This book focuses on the research frontiers of parallel robots from fundamental theory to application technology Special attention is paid to kinematics dynamics modeling error modeling and calibration impedance control and the machining stability of parallel robots Notably a considerable portion of the book focuses on cable driven parallel robots CDPRs that integrate cable driven kinematic chains and parallel mechanism theory CDPRs inherit the high dynamics and heavy load capacities of parallel robots and significantly improve the workspace cost and energy efficiency simultaneously following the cutting edge trend of rigid flexible fusion

*Advances in Intelligent Systems, Computer Science and Digital Economics IV* Zhengbing Hu,Yong Wang,Matthew He,2023-01-28 This book comprises high quality peer reviewed research papers presented at the 4th International Symposium on Computer Science Digital Economy and Intelligent Systems CSDEIS2022 held in Wuhan China from November 11 13 2022 organized jointly by the Wuhan University of Technology Hubei University of Technology Wuhan University of Science and Technology the Polish Operational and Systems Society and the International Center of Informatics and Computer Science ICICS The topics discussed in the book

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