عنوان مقاله:

Kinematic Analysis of a Novel ٣-CRS/PU Parallel Manipulator

محل انتشار:

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نویسنده:

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خلاصه مقاله:

In this research work, a novel parallel manipulator with high positioning and orienting rate is introduced. This mechanism has two rotational and one translational degree of freedom. Kinematics and Jacobian analysis are investigated. Moreover, workspace analysis and optimization has been performed by using genetic algorithm toolbox in Matlab software. Because of decreasing moving elements, it is expected much more better dynamic performance with respect to other counterpart mechanisms with the same degrees of freedom. In addition, using couple of cylindrical and revolute joints increased mechanism ability to have more extended workspace.

کلمات کلیدی:

لینک ثابت مقاله در پایگاه سیویلیکا:

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