

عنوان مقاله:

Maximum dynamic payload carrying capacity of 6UPSS Stewart platform manipulator

محل انتشار:

اولین کنفرانس بین المللی و هفتمین کنفرانس ملی مهندسی ساخت و تولید (سال: 1384)

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خلاصه مقاله:

In this paper, a computational method for obtaining maximum dynamic payload carrying capacity for the 6-UPS Stewart platform manipulator is developed. In this method, the manipulator is supposed is a rigid manipulator and thus the joint actuator torque capacity is considered as the major limiting factor in determining the maximum payload. For a given trajectory, the maximum dynamic payload carrying capacity of manipulator is established while dynamic model of a typical hydraulic actuator system is used in the joint actuator force capacity

کلمات کلیدی:

Parallel manipulator, Dynamic load-carrying capacity, Stewart platform

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