

### عنوان مقاله:

Maximum payload of cable-based planar manipulator for two given end points of end-effector using optimal control approach

### محل انتشار:

هفدهمین کنفرانس سالانه مهندسی مکانیک (سال: 1388)

تعداد صفحات اصل مقاله: 5

### نویسندگان:

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### خلاصه مقاله:

This paper describes the planar cable-based mechanism as a haptic device , followed by dynamics modeling , trajectory planning and attempting to maintain positive cable tensions for all motion including a method for determination of the maximum -payload trajectory of cable-based parallel manipulator on the basis of the optimal .control approach

### کلمات کلیدی:

cable-based parallel manipulator, dynamic load carrying capacity

### لینک ثابت مقاله در پایگاه سیویلیکا:

<https://civilica.com/doc/90669>

