## References

- [abadi2018] Abadi B.N.R., Farid M., and Mahzoon M. Redundancy resolution and control of a novel spatial parallel mechanism with kinematic redundancy. *Mechanism and Machine Theory*, 133:112–126, 2018.
- [abbasnejad2011] Abbasnejad G., Daniali H.M., and Fathi A. Architecture optimization of 4PUS+1PS parallel manipulator. *Robotica*, 29(5):683–690, September 2011.
- [abbasnejad2012] Abbasnejad G. and Carricato M. Real solutions of the direct geometrico-static problem of underconstrained cable-driven parallel robot with 3 cables: a numerical investigation. *Meccanica*, 473(7):1761–1773, 2012.
- [abbasnejad2012-1] Abbasnejad G., Daniali H.M., and Kazemi S.M. A new approach to determine the maximal singularity-free zone of 3-RPR planar parallel manipulator. *Robotica*, 30(6):1005–1012, October 2012.
- [abbasnejad2015] Abbasnejad G. and Carricato M. Direct geometrico-static problem of underconstrained cable-driven parallel robots with n cables. *IEEE Trans. on Robotics*, 31(2):468–478, April 2015.
- [abbasnejad2016] Abbasnejad G., Yoon J., and Lee H. Optimum kinematic design of a planar cable-driven parallel robot with wrench-closure gait trajectory. *Mechanism and Machine Theory*, 99:1–18, May 2016.
- [abbasnejad2019] Abbasnejad G., Eden J., and Lau D. Generalized ray-based lattice generation and graph representation of wrench-closure workspace for arbitrary cable-driven robots. *IEEE Trans. on Robotics*, 35(1), February 2019.
- [abdallah2017] Abdallah F.B. and others. Modeling and stabilization of a cable-driven parallel platform suspended by an airship. In 11th International Workshop on Robot Motion and Control, Wasowo, July, 3-5, 2017.
- [abdallah2018] Abdallah F.B. and others . Modeling and control of an aerial robocrane using a wire driven system. In Annual American Control Conference (ACC), Milwaukee,, June, 27-29, 2018.
- [abdallah2019] Abdallah F.B. and others. Modeling of a heavy-lift airship carrying a payload by a cable-driven parallel manipulator. *International Journal of Advanced Robotic Systems*, 16(4), 2019.
- [abdelaziz 2010] Abdelaziz S. and others . Combining structural and kinematic analysis using interval analysis for a wire-driven manipulator. In ARK, pages 147–156, Piran, June 28- July 1, 2010.
- [abdelaziz2012] Abdelaziz S. and others . Development of a MR-compatible cable-driven manipulator design and technological issues. In *IEEE Int. Conf. on Robotics and Automation*, pages 1488–1494, Saint Paul, May, 14-18, 2012.
- [abdelaziz2012-phd] Abdelaziz S. Développement d'un système robotique pour la radiologie interventionnelle sous IRM. Ph.D. Thesis, Université de Strasbourg, Strasbourg, November, 29, 2012. **Keywords:** wire robot, medical, applications, planar robot.
- [abdelaziz 2014] Abdelaziz S. and others . Design of a magnetic resonance imaging-compatible cable-driven manipulator with new instrumentation and synthesis methods. ASME J. of Mechanical Design, 136(19), September 2014.
- [abdelaziz2017] Abdelaziz S. and others. Control of cable-driven manipulators in the presence of friction. *Mechanism and Machine Theory*, 107:139–147, January 2017.
- [abdellatif2005] Abdellatif H. and Heimann B. Adapted time-optimal trajectory planning for parallel robot with full dynamic modelling. In *IEEE Int. Conf. on Robotics and Automation*, pages 413–418, Barcelona, April, 19-22, 2005.
- [abdellatif2006] Abdellatif H. and Heimann B. Learning control for accuracy enhancement of parallel kinematic machines. In 5th Chemnitzer Parallelkinematik Seminar, pages 443–456, Chemnitz, April, 25-26, 2006.
- [abdellatif2007] Abdellatif H., Grotjahn M., and Heimann B. Independent identification of friction characteristics for parallel manipulators. ASME J. of Mechanical Design, 129(7):294–302, May 2007.

- [abdellatif2007-1] Abdellatif H. and Heimann B. *Industrial Robotics*, *Theory*, *Modelling and Control*, chapter Model based control for industrial robots: uniform approaches for serial and parallel structures, pages 523–556. pro literatur Verlag, January 2007. **Keywords:** kinematics,dynamics,control,state of the art.
- [abdellatif2008] Abdellatif H., Heimann B., and Kotlarski J. Passivity-based observer/controller design with desired dynamics compensation for 6 dofs parallel manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems* (*IROS*), pages 2392–2397, Nice, France, September, 22-26, 2008.
- [abdellatif2008-1] Abdellatif H., Heimann B., and Kotlarski J. *Parallel manipulators, New Developments*, chapter On the robust dynamics identification of parallel manipulators: methodology and experiments, pages 1–20. ITECH, April 2008. **Keywords:** dynamics, calibration.
- [abdellatif2009] Abdellatif H. and Heimann B. Computational efficient inverse dynamics of 6-DOF fully parallel manipulators by using the Lagrangian formalism. *Mechanism and Machine Theory*, 44(1):192–207, January 2009
- [abdellatif2010] Abdellatif H. and Heimann B. Experimental identification of the dynamics model for 6-dof parallel manipulators. *Robotica*, 28(3):359–368, May 2010.
- [abdellatif2010-1] Abdellatif H. and Heimann B. Advanced model-based control of a 6-DOF Hexapod Robot: A case study. *IEEE/ASME Trans. on Mechatronics*, 15(2):269–279, 2010.
- [abdolshah2014] Abdolshah S. and Rosati G. First experimental testing of a dynamic minimum tension control (dmtc) for cable driven parallel robots. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), Duisburg, August, 24-27, 2014.
- [abdolshah2017] Abdolshah S. and others . Optimizing stiffness and dexterity of planar adaptive cable-driven parallel robots. J. of Mechanisms and Robotics, 9, June 2017.
- [abdolshah2017-1] Abdolshah S. and others . Performance evaluation of a new design of cable-suspended camera system. In *IEEE Int. Conf. on Robotics and Automation*, Singapore, 2017.
- [abedinnasab2017] abedinnasab M.H. and others . Kinematic effects of number of legs in 6-DOF UPS parallel mechanisms. *Robotica*, 35:2257–2277, 2017.
- [abtahi2010] Abtahi M. and others . Experimental kinematic calibration of parallel manipulators using a relative position error measurement system. *Robotics and Computer-Integrated Manufacturing*, 26(6):799–804, December 2010.
- [achili2010] Achili R. and others . A robust adaptive control of a parallel robot. Int. J. of Control, 83(10):2107–2119, 2010.
- [achili2012] Achili R. and others . A stable adaptive force/position controller for a C5 parallel robot: a neural network approach. *Robotica*, 30(7):1177–1187, December 2012.
- [adkins97] Adkins F.A. and Haug E.J. Operational envelope of a spatial Stewart platform. ASME J. of Mechanical Design, 119(2):330–332, June 1997.
- [adli91] Adli M.A., Nagai K., Miyata K., and Hanafusa H. Analysis of internal force effect in parallel manipulators. Trans. of the Society of Instrument and Control Engineers, 27(11):1266–1273, November 1991.
- [advani2002] Advani S. and others. Design of a hexapod motion cueing system for the NASA Ames vertical motion simulator. In AIAA Modeling and Simulation Technologies Conf., Monterey, August, 5-8, 2002.
- [advani2004] Advani S. and others . A full-flight simulator of the 1903 Wright flyer. In AIAA Modeling and Simulation Technologies Conf., Austin, August, 11-14, 2004.
- [affi2004] Affi Z., Romdhane L., and Maalej A. Dimensional synthesis of a 3-translational-dof in-parallel manipulator for a desired workspace. European Journal of Mechanics A/Solids, 23(2):311–324, March April , 2004.
- [affi2008] Affi Z. and Romdhane L. Modellling of the orientation error of a 3-dof translational parallel manipulator. In 2nd European Conf. on Mechanism Science (Eucomes), Cassino, September, 17-20, 2008.

- [affi2009] Affi Z. and Romdhane L. Analysis and mapping of the orientation error of a 3-dof translational parallel manipulator. *Robotica*, 27(3):367–377, May 2009.
- [aflakian2015] Aflakian A. and others . Computed torque control of a cable suspended parallel robot. In 3rd RSI/ISM International Conference on Robotics and Mechatronics, Teheran, October, 7-9, 2015.
- [aflakian2018] Aflakian A. and others . Experimental study on the kinematics control of a cable suspended parallel robot for tracking purpose. *Mechatronics*, 50:160–176, 2018.
- [afzali2015] Afzali-Far B. and others . Influence of strut inertia on the vibrations in initially symmetric Gough–Stewart platforms-an analytical study. *Journal of Sound and Vibration*, 352:142–157, 2015.
- [agarwal2016] Agarwal A., Nasa C., and Bandyopadhyay S. Dynamic singularity avoidance for parallel manipulator using a task-priority based control scheme. *Mechanism and Machine Theory*, pages 107–126, 2016.
- [aghezi2014] Aghazi M. and Nestinger S.S. Comprehensive closed-form solution for the reachable workspace of 2-RPR planar parallel manipulator. *Mechanism and Machine Theory*, 74:102–116, 2014.
- [agrawal91] Agrawal S.K. Workspace boundaries of in-parallel manipulator systems. In *ICAR*, pages 1147–1152, Pise, June, 19-22, 1991.
- [agrawal92] Agrawal S.K. and Roth B. Statics of in-parallel manipulator systems. ASME J. of Mechanical Design, 114(4):564–568, December 1992.
- [agrawal92-1] Agrawal S.K. Workspace boundaries of in-parallel manipulator systems. *Int. J. of Robotics and Automation*, 7(2):94–99, 1992.
- [agrawal95] Agrawal S.K., Desmier G., and Li S. Fabrication and analysis of a novel 3 dof parallel wrist mechanism. ASME J. of Mechanical Design, 117(2):343–345, June 1995.
- [ahn2007] Ahn C. and others . High-tilt parallel positioning mechanism development and cutter path simulation for laser micro-machining. *Computer-aided design*, 39(3):218–228, March 2007.
- [ahouee 2017] Ahouee R.A., Moussavi S.Z., and Hamedi J. Neuro-fuzzy intelligent control algorithm for cable-driven robots with elastic cables. In 2nd International Conference on Cybernetics, Robotics and Control, 2017.
- [ait-ahmed91] Ait-Ahmed M. and Renaud M. Dynamic modeling of closed-chain mechanisms and its application for a 6 d.o.f. actuated manipulator. Research Report 91420, LAAS, Toulouse, France, September 1991.
- [ait-ahmed 92] Ait-Ahmed M. and Renaud M. Dynamic modeling of closed-chain mechanisms and its application for a 6 d.o.f. actuated manipulator. In 1st Int. Conf. in Electronics and Automatic Control, pages 203–209, Tizi Ouzou, Algérie, May 1992.
- [ait-ahmed93-1] Ait-Ahmed M. and Renaud M. Polynomial representation of the forward kinematics of a 6 d.o.f. parallel manipulator. In *Int. Symp. on intelligent robotics*, Bangalore, Inde, January 1993.
- [ait-ahmed93-phd] Ait-Ahmed M. Contribution à la modélisation géométrique et dynamique des robots parallèles. Ph.D. Thesis, Université Paul Sabatier, Toulouse, February, 2, 1993. **Keywords:** kinematics,dynamics.
- [akbarzadeh2011] Akbarzadeh A. and Enferadi J. A virtual work based algorithm for solving direct dynamics problem of a 3-RRP spherical parallel manipulator. *J. of Intelligent and Robotic Systems*, 63(1):25–49, 1994.
- [akbarzadeh2013] Akbarzadeh A., Enferadi J., and Sharifnia M. Dynamics analysis of a 3-rrp spherical parallel manipulator using the natural orthogonal complement. *Multibody System Dynamics*, 29:361–380, 2013.
- [akbas2008] Akbas A. Parallel manipulators, New Developments, chapter Application of neural network to modeling and control of parallel manipulators, pages 21–40. ITECH, April 2008. **Keywords:** control,dynamics.
- [akcali2006] Akcali I.D. and Mutlu H. A novel approach in the direct kinematics of Stewart platform mechanisms with planar platform. ASME J. of Mechanical Design, 128(1):252–263, January 2006.
- [alamdar2020] Alamdar A. and others . A geometrical approach for configuration and singularity analysis of a new non-symmetric 2dof 5R spherical parallel manipulator. *Mechanism and Machine Theory*, 147, 2020.

- [alamdari2015] Alamdari A. and Krovi V.N. Modeling and control of a novel home-based cable-driven parallel platform robot:PACER. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 6330–6335, Hamburg, Germany, September 28- October 2, 2015.
- [alamdari2015-1] Alamdari A. and Krovi V.N. Robotical physical exercise and system (ROPES): a cable-driven robotic rehabilitation system for lower-extremity motor therapy. In *ASME DETC*, Boston, August, 2-5, 2015.
- [albagomez2007] Alba-Gomez O.G., Pamanes J.A., and Wenger P. Trajectory planning of a redundant parallel manipulator changing of working mode. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [albus92] Albus J., Bostelman R., and Dagalakis N. The NIST SPIDER, a robot crane. *Journal of research of the National Institute of Standards and Technology*, 97(3):373–385, May 1992.
- [albus93] Albus J., Bostelman R., and Dagalakis N. The NIST ROBOCRANE. J. of Robotic Systems, 10(5):709–724, July 1993.
- [alexandre2012] Alexandre dit Sandretto J., Daney D., and Gouttefarde M. Calibration of a fully-constrained parallel cable-driven robot. In *RoManSy*, pages 12–41, Paris, June, 12-15, 2012.
- [alexandre2012-1] Alexandre dit Sandretto J., Trombettoni G., and Daney D. Confirmation of hypothesis on cable properties for cable-driven robots. In 4th European Conf. on Mechanism Science (Eucomes), pages 85–94, Santander, September, 19-21, 2012.
- [alexandre2013] Alexandre dit Sandretto J. and others . Certified calibration of a cable-driven robot using interval contractor programming. In *Computational Kinematics*, Barcelona, May, 12-15, 2013.
- [alexandre2013-phd] Alexandre dit Sandretto J. Étalonnage des robot à câbles, identification et qualification. Ph.D. Thesis, Université de Nice- Sophia Antipolis, Nice, September, 11, 2013. **Keywords:** wire robot, calibration.
- [alia2018] Alias C. and others. An overview of warehousing applications based on cable robot technology in logistics. In *Int. Conf. on Service Operations and Logistics, and Informatics (SOLI)*, 2018.
- [alici2003] Alici G. and Shirinzadeh B. Optimum force balancing with mass distribution and a single elastic element for a five-bar parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3666–3671, Taipei, September, 14-19, 2003.
- [alici2004] Alici G. and Shirinzadeh B. Optimum dynamic balancing of planar parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 4527–4532, New Orleans, April, 28-30, 2004.
- [alici2004-1] Alici G. and Shirinzadeh B. Optimum synthesis of planar parallel manipulators based on kinematic isotropy and force balancing. *Robotica*, 22(1):97–108, 2004.
- [alici2004-2] Alici G. and Shirinzadeh B. Topology optimisation and singularity analysis of a 3-SPS parallel manipulator with a passive constraining spherical joint. *Mechanism and Machine Theory*, 39:215–235, 2004.
- [alikhani2009] Alikhani A. and others . Workspace analysis of a three DOF cable-driven mechanism. *J. of Mechanisms and Robotics*, 1(4), 2009.
- [alikhani2011] Alikhani A. and others . Design of a large-scale cable-driven robot with translational motion. *Robotics and Computer-Integrated Manufacturing*, 27(2):357–366, April 2011.
- [alikhani2011-1] Alikhani A. and Vali M. Modeling and robust control of a new large scale suspended cable-driven robot under input constraint. In 8th International Conference on Ubiquitous Robots and Ambient Intelligence (URAI), Songdo, November, 23-26, 2011.
- [alizade94] Alizade R.I. and Tagiyev N.R. A forward and reverse displacement analysis of a 6-dof in-parallel manipulator. *Mechanism and Machine Theory*, 29(1):115–124, January 1994.
- [alizade94-1] Alizade R.I., Tagiyev N.R., and Duffy J. A forward and reverse displacement analysis of an in-parallel spherical manipulator. *Mechanism and Machine Theory*, 29(1):125–137, January 1994.
- [alizade2004] Alizade R.I. and Bayram C. Structural synthesis of parallel manipulators. *Mechanism and Machine Theory*, 39(8):857–870, August 2004.

- [alizade2007] Alizade R.I. and others . Structural synthesis of new parallel and serial platform manipulators. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [alizade2008] Alizade R.I., Cemal Can F., and Gezgin E. Structural synthesis of euclidean platform robot manipulators with variable general constraints. *Mechanism and Machine Theory*, 43(11):1431–1449, November 2008.
- [alizade2010-1] Alizade R, Selvi O., and Gezgin E. Structural design of parallel manifold manifolds with general constraint one. *Mechanism and Machine Theory*, 45(1):1–14, January 2010.
- [alizadeh2009] Alizadeh D., Angeles J., and Nokleby S. On the computation of the home posture of the McGill Schöenflies-motion generator. In *Computational Kinematics*, Duisburg, May, 6-8, 2009.
- [alizadeh2010] Alizadeh D., Angeles J., and Nokleby S. Optimum design of a pan-tilt drive for parallel robots. In ARK, pages 169–176, Piran, June 28- July 1, 2010.
- [allais 2012] Allais A.A., McInroy J.E., and O'Brien J.F. A new class of locally decoupled Gough-Stewart platform manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1301–1306, Vilamoura, October, 7-12, 2012.
- [allais2012-1] Allais A.A. and McInroy J.E. Locally decoupled micromanipulator using an even number of of parallel force actuators. *IEEE Trans. on Robotics*, 28(6):1325–1334, February 2012.
- [almonacid2003] Almonacid M. and others. Motion planning of climbing parallel robots. *IEEE Trans. on Robotics and Automation*, 19(3):485–489, June 2003.
- [altuzarra2004] Altuzarra O. and others . A practical procedure to analyze singular configurations in closed kinematic chains. *IEEE Trans. on Robotics*, 20(6):929–940, December 2004.
- [altuzarra2006] Altuzarra O. and others . Motion pattern singularity in lower mobility parallel manipulators. In ARK, pages 489–496, Ljubljana, June, 26-29, 2006.
- [altuzarra2007] Altuzarra O. and others . Partially decoupled parallel manipulators based on multiple platforms. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [altuzarra2009] Altuzarra O. and others . Motion pattern analysis of parallel kinematic machines: a case study. Robotics and Computer-Integrated Manufacturing, 25(2):432–440, April 2009.
- [altuzarra2009-1] Altuzarra O. and others . Multiobjective optimum design of a symmetric parallel Schönflies-motion generator. ASME J. of Mechanical Design, 131(3):031002–1/031002–9, March 2009.
- [altuzarra2009-2] Altuzarra O. and others . Motion pattern analysis of parallel kinematic machines: a case study. Robotics and Computer-Integrated Manufacturing, 25(2):432–440, April 2009.
- [altuzarra2011] Altuzarra O. and others . A symmetric parallel Schönflies-motion manipulator for pick-and-place operations. *Robotica*, 29(6):853–862, October 2011.
- [altuzarra2011-1] Altuzarra O. and others . Workspace analysis of positioning discontinuities due to the clearances in parallel manipulators. *Mechanism and Machine Theory*, 46(5):577–592, May 2011.
- [altuzarra2011-2] Altuzarra O. and others . Design procedure for cuspidal parallel manipulators.  $Mechanism\ and\ Machine\ Theory,\ 46:97-111,\ 2011.$
- [altuzarra2012] Altuzarra O. and others . A low energy consumption solar tracker based in parallel kinematics. In RoManSy, Paris, June, 12-15, 2012.
- [altuzarra2018] Altuzarra O. and others . Forward and inverse kinematics of 2-dof planar parallel continuum manipulators. In *EUCOMES*, pages 231–238, Aachen, September, 4-6, 2018.
- [altuzarra2018-1] Altuzarra O. and others. Position analysis in planar parallel continuum mechanisms. *Mechanism and Machine Theory*, 132:13–29, 2018.
- [altuzarra2018-2] Altuzarra O. and others . Kinematic characteristics of parallel continuum mechanisms. In ARK, pages 293–301, Bologna, July, 1-5, 2018.

- [altuzarra2019] Altuzarra O. and Merlet J-P. Certified kinematics solution of 2-dof planar parallel continuum mechanisms. In 15th IFToMM World Congress, Cracow, June 30- July 4, 2019.
- [alwidyan2002] Al-Widyan K. and Angeles J. The kinetostatic design of a Schonflies-motion generator. In *ARK*, pages 311–318, Caldes de Malavalla, June 29- July 2, 2002.
- [alwidyan2011] Al-Widyan K. and Angeles J. The robust design of parallel spherical robots. *Mechanism and Machine Theory*, 46(3):335–343, March 2011.
- [amara2020] Amara V.D. and others . On the efficient control of series-parallel compliant articulated robots. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [amici2008] Amici C. and others. A parallel compliant meso-manipulator for finger rehabilitation treatments: Kinematic and dynamic analysis. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 735–740, Nice, France, September, 22-26, 2008.
- [amici2008-1] Amici C. and others. Kinematic analysis of a compliant, parallel and three-dimensional mesomanipulator generated from a planar structure. In 2nd European Conf. on Mechanism Science (Eucomes), Cassino, September, 17-20, 2008.
- [amine2010] Amine S. and others . Singularity analysis of lower-mobility parallel robots with an articulated nacelle. In ARK, pages 273–282, Piran, June 28- July 1, 2010.
- [amine2012] Amine S. and others . Singularity analysis of the H4 robot using Grassman-Cayley algebra. *Robotica*, 30(7):1109–1118, December 2012.
- [amine2012-1] Amine S. and others . Singularity conditions of 3T1R parallel manipulators with identical limb structures. J. of Mechanisms and Robotics, 4(1), 2012.
- [amirat91] Amirat M.Y., Pontnau J., and Artigue F. Force-feedback control of a six dof parallel robot. Application to assembly in car manufacturing. Revue d'Automatique et de Productique Appliquée, 4(2):109–121, 1991.
- [amirat92] Amirat M.Y., Pontnau J., and Artigue F. Six degrees of freedom parallel robot with C5 link. *Robotica*, 10(1):35–44, January 1992.
- [amirat94] Amirat M.Y., Pontnau J., and Artigue F. A three-dimensional measurement system for robot manipulators. J. of Intelligent and Robotic Systems, 9(3):291–299, 1994.
- [amirat96] Amirat M.Y. and others. Design and control of a new six dof parallel robot: application to equestrian gait simulation. *Mechatronics*, 6(2):227–239, 1996.
- [amirinezhad2018] Amirinezhad S.V. and Donelan P. Kinematic constraint maps and C-space singularities for planar mechanisms with prismatic joints. In ARK, pages 212–220, Bologna, July, 1-5, 2018.
- [ancuta2009] Ancunta A., Company O., and Pierrot F. Modeling and optimization of Quadriglide, a Schönflies motion generator module for 5-axis milling machine-tools. In *IEEE Int. Conf. on Robotics and Automation*, pages 2174–2179, Kobe, May, 14-16, 2009.
- [anderson96] Anderson E.H., Leo D.J., and Holcomb M.D. Ultraquiet platform for active vibration isolation. In SPIE Smart structures and Materials, pages 436–451, San Diego, February, 25-29, 1996.
- [ando2000] Ando N., Ohta M., and Hashimoto H. Micro teleoperation with parallel manipulator. In *IEEE Int. Conf.* on *Intelligent Robots and Systems (IROS)*, Takamatsu, Japan, October 30- November 5, 2000.
- [ando2001] Ando N., Ohta M., and Hashimoto H. Development of the parallel manipulator workspace display system for tele-micromanipulation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Maui, Hawaii, October 29- November 3, 2001.
- [andrade2006] Andrade-Cetto J. and Thomas F. Wire-based tracking using mutual information. In ARK, pages 3–14, Ljubljana, June, 26-29, 2006.
- [andreff2005] Andreff N., Marchadier A., and Martinet P. Vision-based control of a Gough-Stewart parallel mechanism using legs observation. In *IEEE Int. Conf. on Robotics and Automation*, pages 2546–2551, Barcelona, April, 19-22, 2005.

- [andreff2006] Andreff N. and Martinet P. Unifying kinematic modeling, identification, and control of a Gough–Stewart parallel robot into a vision-based framework. *IEEE Trans. on Robotics*, 22(6), December 2006.
- [andreff2006-h] Andreff N. Des droites et des robots, July, 13, 2006. **Keywords:** kinematics,control.
- [andreff2007] Andreff N., Dallej T., and Martinet P. Image-based visual servoing of a Gough-Stewart parallel manipulator using leg observations. *Int. J. of Robotics Research*, 26(7):677–688, July 2007.
- [andreff2008] Andreff N. and Dressler I. Closed-form calibration of the Gantry-Tau parallel robot. In *IEEE Int. Conf.* on *Intelligent Robots and Systems (IROS)*, pages 993–998, Nice, France, September, 22-26, 2008.
- [angel2004] Angel L.and others. Robotenis: parallel robot with visual control. In World Automation Congress, Seville, 2004.
- [angel2005] Angel L.and others. Robotenis system part ii: dynamics and control. In *IEEE Conference on Decision and Control*, Seville, 2005.
- [angel2005-1] Angel L.and others. Robotenis: design, dynamic modeling and preliminary control. In *IEEE/ASME International Conference on Advanced Intelligent Mechatronics*, Monterey, 2005.
- [angel2007] Angel L.and others. Visual servoing of a parallel robot system. In *European Control Conference*, Kos, 2007.
- [angeles87] Angeles J. and Gosselin C. Détermination du degré de liberté des chaînes cinématiques simples et complexes. In 7th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 199–202, Seville, September, 17-22, 1987.
- [angeles92] Angeles J. and Zanganeh K.E. The semi-graphical solution of the direct kinematics of general platform manipulators. In *ISRAM*, pages 45–52, Santa-Fe, November, 11-13, 1992.
- [angeles2002] Angeles J. The robust design of parallel manipulators. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 9–30, Braunschweig, May, 29-30, 2002.
- [angeles 2002-1] Angeles J. The qualitative synthesis of parallel manipulators. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, Québec, October, 3-4, 2002.
- [angeles 2003] Angeles J., Yang G., and Chen I-M. Singularity analysis of three-legged, six-dof platform manipulators with URS legs. *IEEE/ASME Trans. on Mechatronics*, 8(4):469–475, December 2003.
- [angeles2004] Angeles J. The qualitative synthesis of parallel manipulators. ASME J. of Mechanical Design, 126(4):617–624, July 2004.
- [angeles 2005] Angeles J. The morphology design for a parallel Schönflies-motion generator. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 37–56, Braunschweig, May, 10-11, 2005.
- [angeles 2005-1] Angeles J. Is there a characteristic length of a rigid-body displacement? In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [angeles2005-2] Angeles J. The degree of freedom of parallel robots: a group-theoretic approach. In *IEEE Int. Conf.* on Robotics and Automation, pages 1017–1024, Barcelona, April, 19-22, 2005.
- [angeles 2006] Angeles J. Is there a characteristic length of a rigid-body displacement? *Mechanism and Machine Theory*, 41(8):884–898, August 2006.
- [angeles 2006-1] Angeles J. and others . The kinetostatic design of an innovative schönflies motion generator. *Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science*, 220:935–944, 2006.
- [angeles2012] Angeles J. Design challenges in the development of fast pick-and-place robots. In *RoManSy*, Paris, June, 12-15, 2012.
- [annacondia96] Annacondia E. and others. An approach to simulation of parallel architecture machines. In 27th Int. Symp. on Industrial Robots (ISIR), pages 627–632, Milan, October, 6-8, 1996.
- [annacondia2002] Annacondia E. and others. An experience in design and development of joints for parallel kinematics machine. In 3rd Chemnitzer Parallelkinematik Seminar, pages 243–261, Chemnitz, April, 23-25, 2002.

- [anvari2019] Anvari Z., Ataei P., and Masouleh M.T. Collision-free workspace and kinetostatic performances of a 4-DOF Delta parallel robot. *Journal of the Brazilian Society of Mechanical Sciences and Engineering*, 41(2):99, January 2019.
- [aquino2020] Aquino G. and others . Novel nonlinear hypothesis for the Delta parallel robot modeling. *IEEE Access*, 2020.
- [aracil2000] Aracil R. and others . Kinematics control for navigation of mobile parallel robots applied to large structures. In 17th Int. Symp. on Automation and Robotics in Construction, Taipei, Taiwan, 2000.
- [aracil2000-1] Aracil R. and others . Climbing parallel robots morphologies. In *IFAC Symp. on Robot Control, Syroco*, pages 471–476, Vienne, September, 21-23, 2000.
- [aracil2005] Aracil R. and others . REMO project: design, modelling and hydrodynamic simulation of a robot of variable geometry for actuations on maritime disasters. In *Symposium on Marine Accidental Oil Spills (VER-TIMAR)*, Vigo, July, 13-16, 2005.
- [aracil2006] Aracil R., Saltarén R.J., and Reinoso O. A climbing parallel robot. *IEEE Robotics and Automation Magazine*, 13(1):16–22, March 2006.
- [arai90] Arai T., Cleary K., and others . Design, analysis and construction of a prototype parallel link manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, volume 1, pages 205–212, Ibaraki, Japan, July, 3-6, 1990.
- [arai91] Arai T. and others . Development of a parallel link manipulator. In *ICAR*, pages 839–844, Pise, June, 19-22, 1991.
- [arai92] Arai T., Stoughton R., and Merlet J-P. Teleoperator assisted hybrid control for parallel link manipulator and its application to assembly task. In *Int. Symp. on Measurement and Control in Robotics, ISMCR'92*, pages 817–822, Tsukuba, November, 15-19, 1992.
- [arai92-1] Arai T., Stoughton R., and Raju G.J. Bilateral control for parallel link manipulators. In *IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems*, pages 467–472, Kobe, September, 16-20, 1992.
- [arai93] Arai T., Stoughton R., and Jaya Y.M. Micro hand module using parallel link mechanism. In *Japan-USA Symp. on Flexible Automation*, pages 163–168, San Francisco, July, 13-15, 1993.
- [arai93-1] Arai T., Larsonneur R., and Jaya Y.M. Calibration and basic motion of a micro-hand module. In *Int. Conf. on Indus. Electronics, Control and Instrumentation (IECON)*, pages 1660–1665, Hawai, November, 15-19, 1993.
- [arai96] Arai T., Tanikawa T., Merlet J-P., and Sendai T. Development of a new parallel manipulator with fixed linear actuator. In *Japan-USA Symp. on Flexible Automation*, pages 145–149, Boston, July, 7-10, 1996.
- [arai96-1] Arai T., Hervè J.M., and Tanikawa T. Development of 3 dof micro finger. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 981–987, Osaka, November, 5-8, 1996.
- [arai2000] Arai T. and others . Parallel mechanisms with adjustable link parameters. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Takamatsu, Japan, October 30- November 5, 2000.
- [arai2002] Arai T. and others . A hybrid drive parallel robot for heavy material handling. *IEEE Robotics and Automation Magazine*, 9(1):45–54, March 2002.
- [arakelian2006] Arakelian V., Briot S., and Glazunov V.A. Singular positions of a Paminsa parallel manipulator. J. of Machinery Manufacture and Reliability, (1):62–69, 2006.
- [arakelian 2007] Arakelian V., Briot S., and Glazunov V.A. Improvement of functional performance of spatial parallel manipulators using mechanisms of variable structure. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [arakelian2008] Arakelian V., Briot S., and Glazunov V. Increase of singularity-free zones in the workspace of parallel manipulators using mechanisms of variable structure. *Mechanism and Machine Theory*, 43(9):1129–1140, September 2008.

- [arakelian2008-1] Arakelian V. and Smith M.R. Design of planar 3-dof 3-RRR reactionless parallel manipulators. *Mechatronics*, 18(10):601–606, December 2008.
- [arata2009] Arata J. and others. Development of a haptic device DELTA-4 using parallel link mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 294–300, Kobe, May, 14-16, 2009.
- [arata2011] Arata J. and others . Hapitc device using a newly developed redundant parallel mechanism. *IEEE Trans.* on Robotics, 27(2):201–214, April 2006.
- [arcara2000] Arcara P. and others . Perception of depth information by means of a wire-actuated haptic interface. In *IEEE Int. Conf. on Robotics and Automation*, pages 3443–3348, San Francisco, April, 24-28, 2000.
- [aref2008] Aref M.M. and Taghirad H. Geometrical workspace analysis of a cable-driven redundant parallel manipulator: KNTU CDRPM. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1958–1963, Nice, France, September, 22-26, 2008.
- [aref2009] Aref M.M., Taghirad H., and Barissi S. Optimal design of dexterous cable driven parallel manipulators. *International Journal of Robotics*, 1(1):29–47, 2009.
- [ares2001] Ares J., Brazales A., and Busturia J.M. Tuning and validation of the motion platform washout filter parameters for a driving simulator. In *Driving simulation Conf (DSC)*, pages 295–304, Sophia-Antipolis, September, 5-7, 2001.
- [arian2020] Arian A., Isaksson M., and Gosselin C. Kinematic and dynamic analysis of a novel parallel kinematic Schönflies motion generator. *Mechanism and Machine Theory*, 149, 2020.
- [aridon2007] Aridon G. and others . A model to predict the deployment of a space hexapod. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [aridon2007-phd] Aridon G. Dynamique du déploiement autonome d'un hexapode à rubans pour applications spatiales. Ph.D. Thesis, INSA, Lyon, October, 22, 2007. **Keywords:** dynamics, flexible robot, applications.
- [aridon2009] Aridon G. and others . Self-deployment of a tape-spring hexapod: experimental and numerical investigation. ASME J. of Mechanical Design, 131(2):021003-1/0210003-7, February 2009.
- [arreguin2022] Arreguin J.L.R., Ceccarelli M., and Torres-SanMiguel C.R. Design and simulation of a PK testbed for head impact evaluation. *Robotica*, 40:1293–1308, 2022.
- [arrouk2010] Arrouk K.A., Bouzgarrou B.C., and Gogu G. Workspace determination and representation of planar parallel manipulator in a CAD environment. In 3rd European Conf. on Mechanism Science (Eucomes), pages 605–612, Cluj-Napoca, September, 14-17, 2010.
- [arrouk2016] Arrouk K.A., Bouzgarrou B.C., and Gogu G. CAD-based unified graphical methodology for solving the main problems related to geometric and kinematic analysis of planar parallel robotic manipulators. *Robotics and Computer-Integrated Manufacturing*, 37:302–321, 2016.
- [arrouk2018] Arrouk K.A., Bouzgarrou B.C., and Gogu G. On the full-spin dexterous orientation workspace of spherical parallel robot of 3 RR-type. In *EUCOMES*, pages 347–354, Aachen, September, 4-6, 2018.
- [arsenault2004] Arsenault M. and Boudreau R. The synthesis of three-degree-of-freedom planar parallel mechanisms with revolute joints (3-RR) for an optimal singularity-free workspace. J. of Robotic Systems, 21(5):259–274, 2004.
- [arsenault2006] Arsenault M. and Gosselin C.M. Kinematic and static analysis of a planar modular 2-dof tensegrity mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 4193–4198, Orlando, May, 16-18, 2006.
- [arsenault2006-1] Arsenault M. and Gosselin C.M. Kinematic, static and dynamic analysis of a spatial three-degree-of-freedom tensegrity mechanism. ASME J. of Mechanical Design, 128(5):1061–1069, September 2006.
- [arsenault2006-2] Arsenault M. and Boudreau R. Synthesis of planar parallel mechanisms while considering workspace, dexterity, stiffness and singularity avoidance. ASME J. of Mechanical Design, 128(1):69–78, January 2006.
- [arsenault2009] Arsenault M. and Gosselin C.M. Kinematic and static analysis of a 3-PUPS spatial tensegrity mechanism. *Mechanism and Machine Theory*, 44(1):162–179, January 2009.

- [arsenault2010] Arsenault M. Optimization of the prestress stable wrench closure workspace of planar parallel three-degree-of-freedom cable-driven mechanisms with four cables. In *IEEE Int. Conf. on Robotics and Automation*, pages 1182–1187, Anchorage, May, 3-8, 2010.
- [arsenault2012] Arsenault M. Stiffness analysis of a planar 2-dof cable-suspended mechanism while considering cable mass. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [artigue89] Artigue F., Amirat M.Y., and Pontnau J. Isoelastic behavior of parallel robots. *Robotica*, 7(4):323–325, 1989.
- [artz2001] Artz B. and others . The design and construction of the visual subsystem for VIRTTEX, the driving simulator at the Ford research laboratories. In *Driving simulation Conf (DSC)*, pages 255–262, Sophia-Antipolis, September, 5-7, 2001.
- [arumugam2004] Arumugam H.K., Voyles R.M, and Bapat S. Stiffness analysis of a class of parallel mechanisms for micro-positionning applications. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Sendai, September 28- October 2, 2004.
- [arun92] Arun V. and others. Determination of the workspace of the 3-dof double-octahedral variable-geometry-truss manipulator. In 22nd Biennial Mechanisms Conf., pages 493–500, Scottsdale, September, 13-16, 1992.
- [asada85] Asada H. and Granito C. Kinematic and static characterization of wrist joints and their optimal design. In *IEEE Int. Conf. on Robotics and Automation*, pages 244–250, St Louis, March, 25-28, 1985.
- [ashiththshyam2018] Ashith Shyam R.B. and Ghosal A. Path planning of a 3-upu wrist manipulator for sun tracking in central receiver tower systems. *Mechanism and Machine Theory*, 119:130–141, 2018.
- [assal2011] Assal S.F.M. Learning multiple solution branches for the direct kinematics of parallel manipulators. In *IEEE Int. Conf. on Mechatronics*, Istanbul, April, 13-15, 2011.
- [assal2012] Assal S.F.M. Self-organizing approach for learning the forward kinematic multiple solutions of parallel manipulators. *Robotica*, 30(6):951–961, September 2012.
- [assal2017] Assal S.F.M. A novel planar parallel manipulator with high orientation capability for a hybrid machine tool: kinematics, dimensional synthesis and performance evaluation. *Robotica*, 35:1031–1053, 2017.
- [assomou2013] Assomou Nzue R-M. and others . Comparison of serial and parallel robot repeatability based on different performance criterion. *Mechanism and Machine Theory*, 61:136–155, March 2013.
- [astanin2000] Astanin V.O. and Usov V.V. Multi-objective synthesis of machining center configurations with parallel structure kinematics. In 2nd Chemnitzer Parallelkinematik Seminar, pages 299–312, Chemnitz, April, 12-13, 2000.
- [astanin2002] Astanin V.O. and others. The modeling and optimization of hexapod layout. In 3rd Chemnitzer Parallelkinematik Seminar, pages 189–195, Chemnitz, April, 23-25, 2002.
- [atarod2014] Atarod M. and others . A novel testing platform for assessing knee joint mechanics: a parallel robotic system combined with an instrumented spatial linkage. *Annals of Biomedical Engineering*, 42(5):1121–1132, May 2014.
- [austad87] Austad A. Arm device, June, 4, 1987. Keywords: mechanical architecture, 5 dof robot, patent.
- [avci2014] Avci E. and others . Vibration control of 3P(S)<sub>4</sub> class parallel mechanisms for high speed applications using quantitative feedback design. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Chicago, September, 14-18, 2014.
- [awais2018] Awais M. and others. Real-time vision-based localization of planar cable-driven parallel robot. In 18th International Conference on Control, Automation and Systems (ICCAS), GangWon, October, 17-20, 2018.
- [awtar2007] Awtar S. and Slocum A.H. Constraint-based design of parallel kinematic XY flexure mechanisms. ASME J. of Mechanical Design, 129(8):816–830, August 2007.
- [axehill2014] Axehill J.W. and others . Estimation-based ILC applied to a parallel kinematic robot. *Control Eng. Practice*, 33:1–9, 2014.

- [ayas 2017] Ayas M.S. and Altas I.K. Fuzzy logic based adaptive admittance control of a redundantly actuated ankle rehabilitation robot. *Control Eng. Practice*, 59:44–54, 2017.
- [azar-at2019] Azar A.T. and others. Neuro-fuzzy system for 3-dof parallel robot manipulator. In *Novel Intelligent* and Leading Emerging Sciences Conference (NILES), 2019.
- [azar2016] Azar W.A., Akbarimajd A., and Parvari E. Intelligent control method of a 6-dof parallel robot used for rehabilitation treatment in lower limbs. *Automatika*, 57(2):466–476, 2016.
- [azizian2012] Azizian K. and Cardou P. The constant orientation dimensional synthesis of planar cable-driven prallel mechanisms through convex relaxation. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [azizian2012-phd] Azizian K. Optimum-synthesis methods for cable-driven parallel mechanisms. Ph.D. Thesis, Université Laval, Québec, 20212. **Keywords:** wire robot, optimal design, workspace.
- [azizian2013] Azizian K. and Cardou P. The dimensional synthesis of spatial cable-driven parallel mechanisms. *J. of Mechanisms and Robotics*, 5(4), November 2013.
- [babaghasabha2014] Babaghasabha R., Khosravi M.A., and Taghirad H.M. Adaptive control of KNTU planar cable-driven parallel robot with uncertainties in dynamic and kinematic parameters. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 145–159, Duisburg, August, 24-27, 2014.
- [babaghasabha2015] Babaghasabha R., Khosravi M.A., and Taghirad H.M. Adaptive robust control of fully constrained cable driven parallel robot. *Mechatronics*, 25:27–36, 2015.
- [bachta2009] Bachta W. and others . Cardiolock2: Parallel singularities for the design of an active heart stabilizer. In *IEEE Int. Conf. on Robotics and Automation*, pages 3839–3844, Kobe, May, 14-16, 2009.
- [baczynski2009] Baczynski M. and Baczynski J. The kinematics problems of 9 dof cable driven robotic crane. In 7th IEEE International Conference on Industrial Informatics, pages 686–689, 2009.
- [baczynski2010] Baczynski J. and Baczynski M. Simple system for determining starting position of cable-driven manipulator. In *IEEE Int. Conf. on Computer Information Systems and Industrial Management Applications* (CISIM), pages 102–106, Cracow, October, 8-10, 2010.
- [badano94] Badano F. and others . Evaluation of exploration strategies in robotic assembly. In *IFAC Symp. on Robot Control, Syroco*, pages 63–68, Capri, September, 19-21, 1994.
- [badano95] Badano F. and others . Random exploration strategy: a new paradigm in robotics. A comparison with determinist approaches. *Control Eng. Practice*, 3(9):1301–1306, 1995.
- [badescu2002] Badescu M., Morman J., and Mavroidis C. Workspace optimization of 3-UPU parallel platforms with joint constraints. In *IEEE Int. Conf. on Robotics and Automation*, pages 3678–3683, Washington, May, 11-15, 2002.
- [badescu2002-1] Badescu M., Morman J., and Mavroidis C. Workspace optimization of orientational 3-legged UPS parallel platforms. In *ASME Design Engineering Technical Conference*, Montréal, September 29- October 2, 2002.
- [badescu2004] Badescu M. and Mavroidis C. Workspace optimization of 3-legged UPU and UPS parallel platforms with joint constraints. ASME J. of Mechanical Design, 126(2):291–300, March 2004.
- [badi2017] Badi A. and others . Inverse kinematics for a novel rehabilitation robot for lower limbs. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [bahrami2011] Bahrami A. and Bahrami M.N. Multi-objective design of spatial cable robots. In *IASTED International Conference Robotics (Robo 2011)*, Pittsburgh, 2011.
- [bahrami2011-1] Bahrami A. and Bahrami M.N. Optimal design of a spatial four cable driven parallel manipulator. In *IEEE International Conference on Robotics and Biomimetics*, Phuket, 2011.
- [bahrami2012] Bahrami A., Aghbali B., and Bahrami M.N. Design optimization of a 3-d three cable driven manipulator. In ASME DETC, Chicago, 2012.

- [bai2001] Bai S. and others . Workspace analysis of a parallel manipulator with one redundant dof for skull-base surgery. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Maui, Hawaii, October 29- November 3, 2001.
- [bai2003] Bai S. and Teo M.Y. Kinematic calibration and pose measurement of a medical parallel manipulator by optical position sensors. *J. of Robotic Systems*, 20(4):201–209, 2003.
- [bai2007] Bai S. and Hansen M.R. Modelling of a spherical robotic wrist with euler parameters. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [bai2009] Bai S., Hansen M.R., and Angeles J. A robust forward-displacement analysis of spherical parallel robot. *Mechanism and Machine Theory*, 44(12):2204–2216, December 2009.
- [bai2009-1] Bai S., Hansen M.R., and Andersen T.O. Modelling of a special class of spherical parallel manipulators with euler parameters. *Robotica*, 27(2):161–170, March 2009.
- [bai2010] Bai S. Optimum design of spherical parallel manipulators for a prescribed workspace. *Mechanism and Machine Theory*, 45(2):200–211, February 2010.
- [baigorri2002] Baigorri H.J. Machine for machining large parts, September, 19, 2002. WIPO Patent n° WO 02/072308, A1. **Keywords:** machine-tool,patent.
- [baigunchekov2005] Baigunchekov Zh. and others. Kinematic synthesis of positioning parallel manipulator with functionally independent drives by quadratic approximation. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [baigunchekov2007] Baigunchekov Zh. and others . The new parallel manipulator with 6 degree-of-freedom. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [bailey99] Bailey R.P.S. Mechanical manipulator, January, 12, 1999. United States Patent n° 5,857,815. **Keywords:** mechanical architecture,6 dof robot,patent.
- [bak2016] Bak J-H. and others. Sliding-mode control of cable-driven parallel robots with elastic cables. In 16th International Conference on Control, Automation and Systems (ICCAS), Gyeongju, October, 16-19, 2016.
- [baker 80] Baker J.E. An analysis of the Bricard linkages. Mechanism and Machine Theory, 15(4):267–286, 1980.
- [baker95] Baker J.E. On the 6-hinge loops in Bricard's line-symmetric and plane-symmetric octahedra. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1494–1498, Milan, August 30- September 2, 1995.
- [baker 2002] Baker J.E. On closure modes and singular configurations of kinematic chains. In ARK, pages 175–182, Caldes de Malavalla, June 29- July 2, 2002.
- [baklouti2017] Baklouti S., Caro S., and Courteille E. Dynamic and oscillatory motions of cable-driven parallel robots based on a non-linear cable tension model. *J. of Mechanisms and Robotics*, 9, September 2017.
- [baklouti2017-1] Baklouti S., Caro S., and Courteille E. Sensitivity analys of the elasto-geometrical model of cable-driven parallel robot. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [baklouti2018] Baklouti S., Caro S., and Courteille E. Elasto-dynamic model-based control of non redundant cable-driven parallel robot. In *RoManSy*, Nantes, June, 25-28, 2018.
- [baklouti2018-phd] Baklouti S. Vibration analysis and reduction of cable-driven parallel robots. Ph.D. Thesis, Insa Rennes, Rennes, December, 11, 2018. **Keywords:** wire robot, vibration, control.
- [balan2007] Balan R. and others. Integration of microcontroller system design in mechatronic education- Low cost solutions. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [balchanowski2016] Balchanowski J. General method of structural synthesis of parallel mechanisms. Archive of Civil and Mechanical Engineering, 10, 2016.

- [bamberger2004] Bamberger H. and Shoham M. A new configuration of a six degrees-of-freedom parallel robot for mems fabrication. In *IEEE Int. Conf. on Robotics and Automation*, pages 4545–4550, New Orleans, April, 28-30, 2004.
- [bamberger 2006] Bamberger H., Shoham M., and Wolf A. Kinematics of micro planar parallel robot comprising large joint clearances. In ARK, pages 75–84, Ljubljana, June, 26-29, 2006.
- [bamberger2007] Bamberger H., Wolf A., and Shoham M. Architectures of translational parallel mechanism for MEMS fabrication. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [bamberger 2008] Bamberger H., Wolf A., and Shoham M. Architectures of translational parallel mechanism for MEMS fabrication. ASME J. of Mechanical Design, 130(8), August 2008.
- [bamdad2012] Bamdad M. Time-energy optimal trajectory planning of cable-suspended manipulators. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [bamdad2015] Bamdad M., Taheri F., and Abtahi N. Dynamic analysis of a hybrid cable-suspended planar manipulator. In *IEEE Int. Conf. on Robotics and Automation*, Seattle, May, 26-30, 2015.
- [bande2005] Bande P. and others . Kinematics analysis of Dodekapod. *Mechanism and Machine Theory*, 40(6):740–756, June 2005.
- [bandyopadhyay2004] Bandyopadhyay S. and Ghosal A. Analysis of configuration space singularities of closed-loop mechanisms and parallel manipulators. *Mechanism and Machine Theory*, 39(5):519–544, May 2004.
- [bandyopadhyay2007] Bandyopadhyay S. and Ghosal A. An algebraic formulation of exact force-,moment-isotropy in spatial parallel manipulators. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [bandyopadhyay2008] Bandyopadhyay S. and Ghosal A. An algebraic formulation of kinematic isotropy and design of isotropic 6-6 Stewart platform manipulator. *Mechanism and Machine Theory*, 43(5):591–616, May 2008.
- [bandyopadhyay2009] Bandyopadhyay S. and Ghosal A. An algebraic formulation of static isotropy and design of statically isotropic 6-6 Stewart platform manipulators. *Mechanism and Machine Theory*, 44(7):1360–1370, 2009.
- [bannwart2019] Bannwart M. and others . Robotic body weight support enables safe stair negotiation in compliance with basic locomotor principles. J. of NeuroEngineering and Rehabilitation, 16(157), 2019.
- [bannwart2020] Bannwart M. and others. Mediolateral damping of an overhead body weight support system assists stability during treadmill walking. J. of NeuroEngineering and Rehabilitation, 17(108), 2020.
- [baokun2013] Baokun L. and others . Position-singularity analysis of a special class of the Stewart parallel mechanism with two dissimilar semi-symmetrical hexagons. *Robotica*, 31(1):123–136, January 2013.
- [baradat2008] Baradat C. and others . Design and prototyping of a new balancing mechanism for spatial parallel manipulators. ASME J. of Mechanical Design, 130(7):072305–1–072305–13, July 2008.
- [baran2019] Baran E.A. and others . Unified kinematics of prismatically actuated parallel Delta robots. *Robotica*, 37:1513–1532, 2019.
- [barbazza2017] Barbazza L. and others . Trajectory planning of a suspended cable driven parallel robot with reconfigurable end effector. *Robotics and Computer-Integrated Manufacturing*, 48(6):1–11, 2017.
- [baret78] Baret M. Six degrees of freedom large motion system for flight simulators, piloted aircraft environment simulation techniques. In AGARD Conference Proceeding n°249, Piloted aircraft environment simulation techniques, pages 22–1/22–7, Bruxelles, April, 24-27, 1978.
- [barhaghtalab2016] Barhaghtalab M.H. and others. On the design of the robust neuro-adaptive controller for cable-driven parallel robots. *Automatika*, 57(3):724–735, 2016.
- [barnett2015] Barnett E. and Gosselin C. Large-scale 3d printing with a cable-suspended robot. *Additive Manufacturing*, 7:27–44, July 2015.

- [barnfather 2017] Barnfather J.D., Goodfellow M.J., and T. Abram. Positional capability of a hexapod robot for machining applications. The International Journal of Advanced Manufacturing Technology, 89:1103–1111, 2017.
- [barnfather 2018] Barnfather J.D., Goodfellow M.J., and T. Abram. Achievable tolerances in robotic feature machining operations using a low-cost hexapod. *The International Journal of Advanced Manufacturing Technology*, 95:1421–1436, 2018.
- [baron-n2020] Baron N., Philippides A., and Rojas N. A robust geometric method of singularity avoidance for kinematically redundant planar parallel robot manipulators. *Mechanism and Machine Theory*, 151, 2020.
- [baron-n2021] Baron N., Philippides A., and Rojas N. A dynamically balanced kinematically redundant planar parallel robot. ASME J. of Mechanical Design, 143(8), August 2021.
- [baron-n2018] Baron N., Philippides A., and Rojas N. A geometric method of singularity avoidnce for kinematically redundant planar parallel robot. In *ARK*, Bologna, July, 1-5, 2018.
- [baron94] Baron L. and Angeles J. The measurement subspaces of parallel manipulators under sensor redundancy. In ASME Design Automation Conf., pages 467–474, Minneapolis, September, 11-14, 1994.
- [baron 95] Baron L. and Angeles J. The isotropic decoupling of the direct kinematic of parallel manipulators under sensor redundancy. In *IEEE Int. Conf. on Robotics and Automation*, pages 1541–1546, Nagoya, May, 25-27, 1995.
- [baron97-phd] Baron L. Contributions to the estimation of rigid-body motion under sensor redundancy. Ph.D. Thesis, MCGill University, Montréal, February 1997. **Keywords:** forward kinematics with redundant sensors.
- [baron 98] Baron L. and Angeles J. The on-line direct kinematics of parallel manipulators using joint-sensor redundancy. In ARK, pages 127–136, Strobl, June 29- July 4, 1998.
- [baron 98-1] Baron L. and Angeles J. The hip-joint measurement subspaces of parallel manipulators under joint-sensor redundancy. In 12th RoManSy, pages 61–68, Paris, July, 6-9, 1998.
- [baron2000] Baron L. and Angeles J. The kinematic decoupling of parallel manipulators using joint-sensor data. *IEEE Trans. on Robotics and Automation*, 16(6):644–651, December 2000.
- [baron2000-1] Baron L. and Angeles J. The direct kinematics of parallel manipulators under joint-sensor redundancy. *IEEE Trans. on Robotics and Automation*, 16(1):12–19, February 2000.
- [baron2001] Baron L. and Bernier G. The design of parallel manipulators of Star topology under isotropic constraint. In ASME Design Engineering Technical Conference, Pittsburgh, September, 9-12, 2001.
- [baron2002] Baron L., Wang X., and Cloutier G. The isotropic conditions of parallel manipulators of Delta topology. In ARK, pages 357–366, Caldes de Malavalla, June 29- July 2, 2002.
- [barrette2005] Barrette G. and Gosselin C. Determination of dynamic workspace of cable-driven planar parallel mechanisms. ASME J. of Mechanical Design, 127(2):242–248, March 2005.
- [barroso2018] Barroso A.R. and others . Smooth path planner for dynamic simulators based on cable-driven parallel robots. In *Int. Conf. on Smart Systems and Technologies (SST)*, 2018.
- [basu97] Basu D. and Ghosal A. Singularity analysis of platform-type multi-loop spatial mechanisms. *Mechanism and Machine Theory*, 32(3):375–389, April 1997.
- [bauma2006] Bauma V. and others. Increase of PKM positioning accuracy by redundant measurement. In 5th Chemnitzer Parallelkinematik Seminar, pages 547–564, Chemnitz, April, 25-26, 2006.
- [baumann97] Baumann R., Maeder W., Glauser D., and Clavel R. The Pantoscope: a spherical remote-center-of-motion parallel manipulators for force reflection. In *IEEE Int. Conf. on Robotics and Automation*, pages 718–723, Albuquerque, April, 21-28, 1997.
- [baumli2013] Baumli N. and others. Design and analysis of PKM robots for ultra fast blanking. In IEEE ISR, 2013.
- [bayani2014] Bayani H. and others . On the determination of the maximal inscribed ellipsoid in the wrench-feasible workspace of the cable-driven parallel robots. In 2nd RSI/ISM International Conference on Robotics and Mechatronics, Teheran, October, 15-17, 2014.

- [bayani2016] Bayani H., Masouleh M.T., and Kalhor A. An experimental study on the vision-based control and identification of planar cable-driven parallel robots. *Advanced Robotics*, 75:187–202, 2016.
- [bayaziz2005] Bayaziz O.B., Xie D., and Anamato N.M. Iterative relaxation of constraints: a framework for improving automated motion planning. In *IEEE Int. Conf. on Robotics and Automation*, Barcelona, April, 19-22, 2005.
- [beberek2013] Bebrek O., Hwang M.Y., and Cavusoglu M.C. Design of a parallel robot for needle-based interventions on small animals. *IEEE/ASME Trans. on Mechatronics*, 18(1), February 2013.
- [beck86] Beck A.S. and McCloy D. A comparative study of the power requirement of several basic robot designs. In 16th Int. Symp. on Industrial Robot designs, pages 77–86, Bruxelles, August 30- September 2, 1986.
- [becker-o-2003] Becker O., Pietsch I., and Hesselbach J. Robust joint-space control of 6 dof parallel robot with hydraulic actuators. In RAAD, Cassino, May, 7-10, 2003.
- [becker 94] Becker M. and others . The kinematics of a parallel wrist with actuation redundancy. In *ISRAM*, pages 405–410, Hawaï, August, 15-17, 1994.
- [bedoustani 2010] Bedoustani Y.B. and Taghirad H.D. Iterative-analytic redundancy resolution scheme for a cable-driven redundant parallel manipulator. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, Montréal, July, 6-9, 2010.
- [bedoustani2011] Bedoustani Y.B. and others . Lagrangian dynamics of cable-driven parallel manipulators: a variable mass formulation.  $Trans.\ CSME,\ 35(4):529=542,\ 2011.$
- [beer2008] Beer R.F and others. Development and evaluation of a gravity compensated training environment for robotic rehabilitation of post-stroke reaching. In *IEEE/RAS-EMBS International Conference on Biomedical Robotics and Biomechatronics*, Scottsdale, October, 19-22, 2008.
- [beer2008-1] Beer R.F and others. Technical evaluation of the MACARM: A cable robot for upper limb neurore-habilitation. In *IEEE/RAS-EMBS International Conference on Biomedical Robotics and Biomechatronics*, Scottsdale, October, 19-22, 2008.
- [begey2019] Begey J. and others . Dynamic control of parallel robot driven by flexible cables and actuated by position-controlled winches. *IEEE Trans. on Robotics*, 35(1):286–293, February 2019.
- [begey2020] Begey J. Analyse, conception et commande de manipulateurs tenségrité. Ph.D. Thesis, Université de Strasbourg, Strasbourg, November, 25, 2020. **Keywords:** tensegrity.
- [begon94] Bégon P., Fraisse P., Pierrot F., and Dauchez P. Variable structure control stabilized by high-frequency oscillations: theory-simulation-experiments. *Laboratory Robotic and Automation*, 6(6):283–292, December 1994.
- [begon95] Bégon P. Commande des robots parallèles rapides. Application au robot HEXA. Ph.D. Thesis, Université Montpellier II, Montpellier, June, 23, 1995. **Keywords:** kinematics,control.
- [begon95-1] Bégon P., Pierrot F., and Dauchez P. Insertions rapides avec un robot parallèle à six degrés de liberté. Revue d'Automatique et de Productique Appliquée, 8(4):513–528, 1995.
- [begon95-2] Bégon P., Pierrot F., and Dauchez P. Fuzzy sliding mode control of a fast parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, Nagoya, May, 25-27, 1995.
- [behi88] Behi F. Kinematic analysis for a six-degree-of-freedom 3-PRPS parallel mechanism. *Int. J. of Robotics and Automation*, 4(5):561–565, October 1988.
- [behi90] Behi F., Mehregany M., and Gabriel K.J. A microfabricated three-degree-of-freedom parallel mechanism. In *IEEE Micro Electro Mechanical Workshop*, pages 159–165, Napa Valley, February, 11-14, 1990.
- [behzadipour2004] Behzadipour S. and Khajepour A. Design of reduced dof parallel cable-based robots. *Mechanism and Machine Theory*, 39(10):1051–1065, October 2004.
- [behzadipour 2005] Behzadipour S. and Khajepour A. A new cable-based parallel robot with three degrees of freedom. Multibody System Dynamics, 13:371–383, 2005.

- [behzadipour 2006] Behzadipour S. and Khajepour A. Industrial Robotics: Theory, Modelling and Control, chapter Cable-based Robot Manipulators with Translational Degrees of Freedom, pages 211–236. Pro Literatur Verlag, Germany / ARS, Austria, Germany, December 2006. **Keywords:** wire robot, 3 dof robot, planar robot.
- [behzadipour 2007] Behzadipour S. and Azadi Sohi M. Antagonistic stiffness in cable-driven mechanisms. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [behzadipour 2007-1] Behzadipour S. and Khajepour A. *Industrial robotics. Theory, Modeling and Control*, chapter Cable based robot manipulators with translational degrees of freedom, pages 211–236. pro literatur Verlag, January 2007. **Keywords:** ,wire robot,3 dof robot,mechanical architecture,planar robot,hybrid robot.
- [beiranvand2021] Beiranvand A., Kalhor A., and Tale Masouleh M. Modeling, identification and minimum length integral sliding mode control of a 3-dof cartesian parallel robot by considering virtual flexible links. *Mechanism and Machine Theory*, 157, 2021.
- [beji96] Beji L. and others . Non linear control of a parallel robot including motor dynamics. In 11th RoManSy, pages 45–52, Udine, July, 1-4, 1996.
- [beji97-phd] Beji L. Modélisation, identification et commande d'un robot parallèle. Ph.D. Thesis, Université Evry Val d'Essonne, Evry, 1997. **Keywords:** mechanical architecture, control.
- [belda2006] Belda K. and Böhm J. Predictive control of redundant parallel robot and trajectory planning. In 5th Chemnitzer Parallelkinematik Seminar, pages 497–514, Chemnitz, April, 25-26, 2006.
- [bellakehal2011] Bellakehal S. and others . Vision/force control of parallel robots. *Mechanism and Machine Theory*, 46:1376–1395, 2011.
- [bellido90] Bellido A., Dedieu J-P., and Yakoubsohn J-C. Combien existe-t-il d'octaèdres dont les longueurs des arêtes sont données? In Séminaire INRIA sur les robots parallèles, Sophia-Antipolis, February 1990.
- [belzile2020] Belzile B., Eskandary P.K., and Angeles J. Workspace determination and feedback control of a pick-and-place parallel robot: analysis and experiments. *IEEE Robotics and Automation Letters*, 5(1), 2020.
- [benabdallah2018] Ben Abdallah F. and others. Modeling and control of an aerial robocrane using a wire driven system. In *Annual American Control Conference (ACC)*, Milwaukee, June, 27-29, 2018.
- [benali99] Benali A., Richard P., and Bidaud P. Design, control and evaluation of a six DOF force feedback interface for virtual reality applications. In *IEEE Int. Workshop on Robot and Human Interaction*, pages 338–343, Pisa, September, 27-29, 1999.
- [benea96] Bénéa R. and Giordano M. Dynamical simulation for a parallel manipulator applied to the 6-RKS structure. In 27th Int. Symp. on Industrial Robots (ISIR), pages 689–694, Milan, October, 6-8, 1996.
- [benea96-phd] Bénéa R. Contribution à l'étude des robots pleinement parallèles de type 6R-RR-S. Ph.D. Thesis, Université de Savoie, Annecy, December, 16, 1996. **Keywords:** mechanical architecture, workspace, singularity, dynamics, statics, mobility.
- [bengoa2015] Bengoa P. and others . A stable model-based control scheme for parallel robots using additional sensors. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, September 28- October 2, 2015.
- [benhamida2020] Ben Hamida I. and others . Dimensional synthesis and performance evaluation of four translational parallel manipulators. *Robotica*, 39(2):233–249, 2020.
- [benhamida2021] Ben Hamida I. and others. Multi-objective optimal design of a cable driven parallel robot for rehabilitation tasks. *Mechanism and Machine Theory*, 156, 2021.
- [benhorin96] Ben-Horin R. and Shoham M. Construction of a new type of a six-degrees-of-freedom parallel manipulator with three planarly actuated links. In *ASME Design Engineering Technical Conference*, pages 96—DETC/MECH-1561, Irvine, August, 18-22, 1996.
- [benhorin98] Ben-Horin R., Shoham M., and Djerassi S. Kinematics, dynamics and construction of a planarly actuated parallel robot. *Robotics and Computer-Integrated Manufacturing*, 14(2):163–172, April 1998.

- [benhorin2005] Ben-Horin R. and Shoham M. Singularity analysis of a class of parallel robots based on Grassmann-Cayley algebra. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [benhorin2006] Ben-Horin R. and Shoham M. Singularity of a class of Gough-Stewart platforms with three concurrent joints. In ARK, pages 265–274, Ljubljana, June, 26-29, 2006.
- [benhorin2006-1] Ben-Horin R. and Shoham M. Singularity analysis of a class of parallel robots based on Grassmann-Cayley algebra. *Mechanism and Machine Theory*, 41(8):958–970, August 2006.
- [benhorin2006-2] Ben-Horin R. and Shoham M. Singularity condition of six-degree-of-freedom three-legged parallel robot based on Grassmann-Cayley algebra. *IEEE Trans. on Robotics*, 22(4):577–590, August 2006.
- [benhorin2006-3] Ben-Horin R. and others. Dynamics of a six degrees-of-freedom parallel robot actuated by three two-wheel carts. *Multibody System Dynamics*, 16(2):105–121, September 2006.
- [benhorin2007] Ben-Horin R. and Shoham M. Singularity of Gough-Stewart platforms with collinear joints. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [benhorin2008] Ben-Horin P. and others . Singulab. a graphical user interface for the singularity analysis of parallel robots based on Grassmann-Cayley algebra. In ARK, pages 49–58, Batz/mer, June, 23-26, 2008.
- [benhorin2008-1] Ben-Horin R. and Shoham M. A class of parallel robot practically free of singularities. ASME J. of Mechanical Design, 130(5):052303–1/9, May 2008.
- [benhorin2009] Ben-Horin R. and Shoham M. Application of Grassmann Cayley algebra to geometrical interpretation of parallel robot singularities. *Int. J. of Robotics Research*, 28(1):127–141, January 2009.
- [bennehar2014] Bennehar M., Chemori A., and Pierrot F. A novel RISE-based adaptive feedforward controller for redundantly actuated parallel manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Chicago, September, 14-18, 2014.
- [bennehar 2015-phd] Bennehar M. Some contributions to nonlinear adaptive control of PKMs: from design to real-time experiments. Ph.D. Thesis, Université de Montpellier, Montpellier, December, 17, 2015. **Keywords:** control.
- [bennehar 2018] Bennehar M., Chemori A., Bouri M., Jenni L-F., and Pierrot F. A new RISE-based adaptive control of PKMs: design, stability analysis and experiments. *Int. J. of Control*, 91(3):593–607, 2018.
- [bennour2011] Bennour S., Harshe M., Romdhane L., and Merlet J-P. A robotic application for analysis and control of human motion. In 4eme Congrès International Conception et Modélisation des Systèmes Mécaniques CMSM, Sousse, May 30- June 1, 2011.
- [bennour2011-1] Bennour S., Romdhane L., Merlet J-P., and Harshe M. Nouvelle machine robotisée à base d'une plateforme à câbles pour la rééducation fonctionnelle. In 20ème Congrés Français de Mécanique, Besancon, August 28- September 2, 2011.
- [bennour2011-2] Bennour S., Harshe M., Romdhane L., and Merlet J-P. A new experimental setup based on a parallel cable robot for analysis and control of human motion. *Computer Methods in Biomechanics and Biomedical Engineering*, 14(Supplement 1):83–85, August 2011.
- [bennour2012-phd] Bennour S. Contribution au Développement d'une Plateforme Robotisée pour la Rééducation Fonctionnelle. Ph.D. Thesis, Ecole Nationale d'Ingénieurs de Monastir, Monastir, February 2012. **Keywords:** wire robot, medical.
- [bensghaier2005] Ben Sghaier A. and Romdhane L. A software package for parallel mechanisms modeling and simulation. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [bentaleb2020] Bentaleb T. and Iqbal J. On the improvement of calibration accuracy of parallel robots -modeling and optimization. *Journal of Theoretical and Applied Mechanics*, 58(1), 2020.
- [benyahia2021] Ben Yahia I., Merlet J-P., and Papegay Y. Mixing neural networks, Newton method and inverval analysis for the kinematics of cable-driven parallel robots with sagging cables. In *ICAR*, Ljulbjana, 2021.
- [berger2004] Berger K.T., Horta L.G., and Taleghani B.K. Static testing of an inflatable/rigidizable hexapod structure. In 45th AIAA Structures, Structural Dynamics and Material Conf., Palm-Spring, April, 19-22, 2004.

- [bernelli95] Bernelli-Zazzera F. and Gallieni D. Analysis and design of an hexapod mechanism for autonomous payload pointing. In 46th IAF Congress, Oslo, October, 2-6, 1995.
- [bernier95] Bernier D., Castelain J-M., and Li X. A new parallel structure with six degree of freedom. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 8–12, Milan, August 30- September 2, 1995.
- [bernstein 2013] Bernstein N., Lawrence D., and Pao L. Dynamic modeling for parallel haptic interfaces with for sensing and control. *IEEE Trans. on Haptics*, 6(4):429–439, December 2013.
- [berthomieu89-phd] Berthomieu T. Étude d'un micro-manipulateur parallèle et de son couplage avec un robot porteur. Ph.D. Thesis, ENSTAE, Toulouse, January, 24, 1989. **Keywords:** kinematics,dynamics,workspace,mechanical architecture,actuators,6 dof robot,pneumatic,hardware,force feedback,micro-macro robot,singularity,force sensor,orientation workspace.
- [berti2012] Berti A., Merlet J-P., and Carricato M. Solving the direct geometrico-static problem of the 3-3 cable-driven parallel robots by interval analysis: preliminary results. In 1st Int. Conf. on cable-driven parallel robots (CableCon), pages 251–268, Stuttgart, September, 3-4, 2012.
- [berti2014] Berti A., Merlet J-P., and Carricato M. Workspace analysis of redundant cable-suspended parallel robots. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 41–54, Duisburg, August, 24-27, 2014.
- [berti2015-phd] Berti A. Kinematics and statics of cable-driven parallel robots by interval-analysis-based methods. Ph.D. Thesis, University of Bologna, Bologna, April, 21, 2015. **Keywords:** kinematics, wire robot.
- [berti2016] Berti A., Merlet J-P., and Carricato M. Solving the direct geometrico-static problem of underconstrained cable-driven parallel robots by interval analysis. *Int. J. of Robotics Research*, 35(6):723–739, 2016.
- [besnard98] Besnard S. Etalonnage autonome des manipulateurs parallèles. In *9ème Journées Jeunes Chercheurs en Robotique*, pages 11–15, Clermont-Fd, May, 11-12, 1998.
- [besnard99] Besnard S. and Khalil W. Calibration of parallel robot using two inclinometers. In *IEEE Int. Conf. on Robotics and Automation*, pages 1758–1763, Detroit, May, 10-15, 1999.
- [besnard2000] Besnard S. Etalonnage géométrique des robots série et parallèles. Ph.D. Thesis, Université de Nantes, Nantes, September, 21, 2000. **Keywords:** calibration.
- [besnard2001] Besnard S. and Khalil W. Identifiable parameters for parallel robots kinematic calibration. In *IEEE Int. Conf. on Robotics and Automation*, pages 2859–2866, Seoul, May, 23-25, 2001.
- [bessala95] Bessala J., Bidaud P., and Ben Ouezdou F. Analysis of complex mechanical systems through geometrical reachable workspace. In *IASTED Int. Conf. on Robotics and Manufacturing*, Cancun, June, 14-17, 1995.
- [bessala95-1] Bessala J., Bidaud P., and Ben Ouezdou F. Analysis of complex mechanical systems, design, motion, planning, optimal transmissions. In *IMACS Symp. on System Analysis and Simulation*, 1995.
- [bessala95-phd] Bessala J. Détermination des expressions analytiques d'espaces de travail des systèmes mécaniques, et applications. Ph.D. Thesis, Université Paris 6, September, 11, 1995. **Keywords:** workspace, optimal design.
- [beyer2002] Beyer L. and Wulfsberg J-P. Calibration of parallel robot with ROSY. In 3rd Chemnitzer Parallelkinematik Seminar, pages 493–505, Chemnitz, April, 23-25, 2002.
- [beyer2004] Beyer L. and Wulfsberg J. Practical robot calibration with ROSY. *Robotica*, 22(5):505–512, September 2004.
- [bhagat 2014] Bhagat U. and others . Design and analysis of a novel flexure-based 3-dof mechanism. *Mechanism and Machine Theory*, 73:173–187, April 2014.
- [bharadwaj 2006] Bharadwaj K. and Sugar T.G. Kinematics of a robotic gait trainer for stroke rehabilitation. In *IEEE Int. Conf. on Robotics and Automation*, pages 3492–3497, Orlando, May, 16-18, 2006.
- [bhattacharya95] Bhattacharya S., Hatwal H., and Ghosh A. On the optimum design of a Stewart platform type parallel manipulators. *Robotica*, 13(2):133–140, March April , 1995.

- [bhattacharya97] Bhattacharya S., Hatwal H., and Ghosh A. An on-line estimation scheme for generalized Stewart platform type parallel manipulators. *Mechanism and Machine Theory*, 32(1):79–89, January 1997.
- [bhattacharya97-1] Bhattacharya S., Nenchev D.N., and Uchiyama M. A singularity-consistent parametrization based direct kinematics algorithm for a class of parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2671–2676, Albuquerque, April, 21-28, 1997.
- [bhattacharya98] Bhattacharya S., Nenchev D.N., and Uchiyama M. A recursive formula for the inverse of the inertia matrix of a parallel manipulator. *Mechanism and Machine Theory*, 33(7):957–964, October 1998.
- [bhattacharya98-1] Bhattacharya S., Hatwal H., and Ghosh A. Comparison of an exact and an approximate method of singularity avoidance in platform type parallel manipulators. *Mechanism and Machine Theory*, 33(7):965–974, October 1998.
- [bhuatni2014] Bhutani G. and T.A. Dwarakanath. Practical feasibility of a high precision 3-UPU parallel mechanism. *Robotica*, 32(3):341–353, May 2014.
- [bhuatni2014-1] Bhutani G. and T.A. Dwarakanath. Novel design solution to high precision 3 axes translational parallel mechanism. *Mechanism and Machine Theory*, 75:118–130, May 2014.
- [bi2006] Bi Z.M. and Lang S.Y.T. Forward kinematic solution and its applications for a 3-dof parallel kinematic machine (PKM) with a passive link. *Robotica*, 24(5):549–555, 2006.
- [bi2007] Bi Z.M. and others. Integrated design toolbox for tripod-based parallel kinematic machines. ASME J. of Mechanical Design, 129(8):799–807, August 2007.
- [bi2009] Bi Z.M. and Lang S.Y.T. Joint workspace of parallel kinematic machines. *Robotics and Computer-Integrated Manufacturing*, 25(1):57–63, 2009.
- [bi2009-1] Bi Z.M. and Wang L. Optimal design of reconfigurable parallel machining systems. *Robotics and Computer-Integrated Manufacturing*, 25(6):951–961, December 2009.
- [bi2011] Bi Z.M. and Jin Y. Kinematic modeling of Exechon parallel kinematic machine. *Robotics and Computer-Integrated Manufacturing*, 27(1):186–193, February 2011.
- [bier2006] Bier C., Campos A., and Hesselbach J. Direct singularity closeness indexes for the Hexa parallel robot. In ARK, pages 239–246, Ljubljana, June, 26-29, 2006.
- [bihari2016] Bihari B. and others . A geometric approach for the workspace analysis of two symmetrical planar parallel manipulator. *Robotica*, 34(4):738–763, April 2016.
- [billette2009] Billette G. and Gosselin C. Producing rigid contacts in cable-driven haptic interfaces using impact generating reels. In *IEEE Int. Conf. on Robotics and Automation*, pages 307–312, Kobe, May, 14-16, 2009.
- [bilton2012] Bilton A.M. and Dubowsky S. Inverse kinematics for the control of hyper-redundant binary mechanisms with application to solar concentrator mirrors. In ARK, pages 421–428, Innsbruck, June, 25-28, 2012.
- [binaud2008] Binaud N., Caro S., and Wenger P. Sensitivity analysis of degenerate and non-degenerate planar parallel manupulator. In 2nd European Conf. on Mechanism Science (Eucomes), Cassino, September, 17-20, 2008.
- [binaud2009] Binaud N., Caro S., and Wenger P. Sensitivity and dexterity comparison of  $3 \underline{R}RR$  planar parallel manipulators. In *Computational Kinematics*, pages 77–84, Duisburg, May, 6-8, 2009.
- [binaud2010] Binaud N., Caro S., and Wenger P. Sensitivity comparison of planar parallel manipulators. *Mechanism and Machine Theory*, 45(11):1477–1490, November 2010.
- [binaud2010-1] Binaud N., Caro S., Bai S., and Wenger P. Comparison of  $3-\underline{P}PR$  parallel planar manipulators based on their sensitivity to joint clearances. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Taipei, October, 18-22, 2010.
- [binaud2010-1-phd] Binaud N. Sensibilité des manipulateurs parallèles aux variations des paramètres géométriques et aux jeux. Ph.D. Thesis, École Centrale de Nantes, Nantes, December, 13, 2010. **Keywords:** performance analysis, accuracy, clearance.

- [birglen2002] Birglen L. and others . SHaDe, a new 3-dof haptic device. *IEEE Trans. on Robotics and Automation*, 18(2):166–175, April 2002.
- [birlescu2018] Birlescu J. and others . On the singulrities of a parallel robotic system used for elbow and wrist rehabilitation. In ARK, Bologna, July, 1-5, 2018.
- [birlescu2022] Birlescu J. and others . A new approach to forward kinematics for a SILS robotic orientation platform based on perturbation theory. In ARK, Bilbao, June, 26-30, 2022.
- [black2018] Black C.B., Till J., and Rucker D.C. Parallel continuum robots: Modeling, analysis, and actuation-based force sensing. *IEEE Trans. on Robotics*, 34(1), February 2018.
- [blaise 2010] Blaise J. and others . Kinematic characterisation of hexapods for industry. *Industrial Robot*, 37(1):79–88, 2010.
- [blanchard2005] Blanchard L., Falzon F., Dupuis J., and Merlet J-P. Deployable hexapod using tape-springs. In *Disruption in Space,ESA/CNES Symp.*, Marseille, 2005.
- [blanchet 2012] Blanchet L. and Merlet J-P. Dimensionnement d'un robot à câbles garantissant une contrainte de précision via le calcul par intervalles des paramètres de conception. In *Journées Scientifiques Robotique et Automatique*, Nantes, France, October 2012.
- [blanchet2014] Blanchet L. and Merlet J-P. Interference detection for cable-driven parallel robots (CDPRs). In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 1413–1418, Besancon, July, 8-11, 2014.
- [blanchet 2015] Blanchet L. Contribution à la modélisation de robots à câbles pour leur commande et leur conception. Ph.D. Thesis, Université de Nice- Sophia Antipolis, Nice, May, 13, 2015. **Keywords:** wire robot, statics, kinematics.
- [bleicher 2002] Bleicher F. Optimizing the three-axis machine-tool with parallel kinematic structure. In 3rd Chemnitzer Parallelkinematik Seminar, pages 883–894, Chemnitz, April, 23-25, 2002.
- [bleicher 2006] Bleicher F., Puschitz F., and Theiner A. Laser based measurement system for calibrating machine-tools in 6 DOF. In 5th Chemnitzer Parallelkinematik Seminar, pages 617–634, Chemnitz, April, 25-26, 2006.
- [boanta2017] Boanta C. and Csiszar A. Optimal design of a parallel structure used as a haptic interface. *Mechanism and Machine Theory*, 116:69–88, 2017.
- [bohigas 2010] Bohigas O., Ros L., and Manubens M. A complete method for workspace boundary determination. In ARK, pages 329–338, Piran, June 28- July 1, 2010.
- [bohigas2012] Bohigas O. and others . A singularity-free path planner for closed-chain manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2128–2134, Saint Paul, May, 14-18, 2012.
- [bohigas 2012-1] Bohigas O., Manubens M., and Ros L. Planning singularity-free force-feasible paths on the Stewart platform. In ARK, pages 245–253, Innsbruck, June, 25-28, 2012.
- [bohigas 2012-2] Bohigas O., Manubens M., and Ros L. A complete method for workspace boundary determination of general structure manipulators. *IEEE Trans. on Robotics*, 28(5):903–1006, October 2012.
- [bohigas 2012-3] Bohigas O., Manubens M., and Ros L. Navigating the wrench-feasible C-space of cable-driven hexapods. In 1st Int. Conf. on cable-driven parallel robots (Cable Con), Stuttgart, September, 3-4, 2012.
- [bohigas2012-4] Bohigas O. and others . Numerical computation of manipulator singularities. In *IEEE Int. Conf. on Robotics and Automation*, Saint Paul, May, 14-18, 2012.
- [bohigas 2016] Bohigas O., Manubens M., and Ros L. Planning wrench-feasible motions for cable-driven hexapods. *IEEE Trans. on Robotics*, 32(2):442–451, April 2016.
- [bolboli2019] Boloboli J. and others. Stiffness feasible workspace of cable-driven parallel robots with application to optimal design of a planar cable robot. *Robotics and Autonomous Systems*, 114:19–28, 2019.
- [bombin2001] Bombin C., Ros L., and Thomas F. On the computation of the direct kinematics of parallel spherical mechanism using Bernstein polynomials. In *IEEE Int. Conf. on Robotics and Automation*, pages 3332–3337, Seoul, May, 21-26, 2001.

- [bonev99] Bonev J., I.A. and Ryu. Workspace analysis of 6-PRRS parallel manipulators based on the vertex space concept. In ASME Design Engineering Technical Conference, Las Vegas, September, 12-15, 1999.
- [bonev99-1] Bonev I.A. and others . A simple new closed-form solution of the direct kinematics using three linear extra sensors. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 526–530, Atlanta, September, 19-23, 1999.
- [bonev99-2] Bonev J., I.A.and Ryu. Orientation workspace analysis of a 6-DOF parallel manipulators. In ASME Design Engineering Technical Conference, Las Vegas, September, 12-15, 1999.
- [bonev99-3] Bonev I.A.and others. A simple new closed-form solution of the direct kinematics of parallel manipulators using three linear extra sensors. In *Int. Conf. on Advanced Intelligent Mechatronics*, pages 526–530, Atlanta, September, 19-22, 1999.
- [bonev2000] Bonev J., I.A. and Ryu. A new method for solving the direct kinematics of general 6-6 Stewart platforms using three linear extra sensors. *Mechanism and Machine Theory*, 35(3):423–436, March 2000.
- [bonev2001] Bonev I.A. and Ryu J. A geometrical method for computing the constant-orientation workspace of 6-Prss parallel manipulators. *Mechanism and Machine Theory*, 36(1):1–13, 2001.
- [bonev2001-1] Bonev I.A. and Gosselin C.M. Singularity loci of planar parallel manipulators with revolute joints. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 291–299. EJCK, May, 20-22, 2001. **Keywords:** planar robot, singularity.
- [bonev2001-2] Bonev I.A. and Ryu J. A new approach to orientation workspace analysis of 6 dof parallel manipulator. *Mechanism and Machine Theory*, 36(1):15–28, January 2001.
- [bonev2001-3] Bonev I.A. Delta parallel robot-the story of success. May, 6, 2001, http://www.parallemic.org/Reviews/Review002.html. **Keywords:** history,3 dof robot.
- [bonev2001-4] Bonev I.A. and Zlatanov D. The mystery of the singular SNU translational parallel robot. June, 12, 2001, www.parallemic.org/Reviews/Review004.html. **Keywords:** singularity,3 dof robot.
- [bonev2001-5] Bonev I.A. and others . A closed-form solution to the direct kinematics of nearly general parallel manipulators with optimally located three linear extra sensors. *IEEE Trans. on Robotics and Automation*, 17(2):148–156, April 2001.
- [bonev2002] Bonev I. and Gosselin C.M. Geometric algorithms for the computation of the constant-orientation workspace and singularity surfaces of a special 6-RUS parallel manipulator. In *ASME Design Engineering Technical Conference*, Montréal, September 29- October 2, 2002.
- [bonev2003] Bonev I.A. The true origins of parallel robots. January, 24, 2003, http://www.parallemic.org/Reviews/Review007.html. **Keywords:** history,mechanical architecture.
- [bonev2003-1] Bonev I.A., Zlatanov D., and Gosselin C. Singularity analysis of 3 dof planar mechanisms via screw theory. ASME J. of Mechanical Design, 125(3):573–581, September 2003.
- [bonev2005] Bonev I. and Gosselin C.M. Singularity loci of spherical parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 2968–2973, Barcelona, April, 19-22, 2005.
- [bonev2006] Bonev I., Chablat D., and Wenger P. Working and assembly modes of the Agile Eye. In *IEEE Int. Conf. on Robotics and Automation*, pages 2317–2322, Orlando, May, 16-18, 2006.
- [bonev2008] Bonev I.A. Direct kinematics of zero-torsion parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 3851–3856, Pasadena, May, 19-23, 2008.
- [bonnemains 2008] Bonnemains T. and others . Definition of a new static model of parallel kinematic machines: highlighting of overconstraint influence. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2416–2421, Nice, France, September, 22-26, 2008.
- [bonnemains 2013] Bonnemains T. and others. Dynamic model of an overconstrained PKM with compliance: the Tripteor X7. Robotics and Computer-Integrated Manufacturing, 29(1):180–191, February 2013.

- [borchert2012] Borchert G. and others. Design methodology for a compliant binary actuated parallel mechanism with flexure hinges. In 4th European Conf. on Mechanism Science (Eucomes), pages 171–179, Santander, September, 19-21, 2012.
- [borchert2015] Borchert G. and others. Analysis of the mass distribution of a functionally extended Delta robot. Robotics and Computer-Integrated Manufacturing, 31:111–120, February 2015.
- [borchert2017] Borchert G. and Raatz A. A new method for combining handling systems with passive orientation devices. *Annals of the CIRP*, 65(1):49–52, 2016.
- [bordalba2017] Bordalba R., Porta J.M., and Ros L. Randomized kinodynamic planning for cable-suspended parallel robots. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [bordalba2018] Bordalba R., Porta J.M., and Ros L. A singularity-robust LQR controller for parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Madrid, October, 1-5, 2018.
- [bordalba2021] Bordalba R., Ros L., and Porta J.M. A randomized kinodynamic planner for closed-chain robotic systems. *IEEE Trans. on Robotics*, 37(1), February 2021.
- [borel08] Borel E. Mémoire sur les déplacements à trajectoire sphériques. *Mémoire présentés par divers savants*, 33(1):1–128, 1908.
- [borgstrom2007] Borgstrom P.H. and others. Discrete trajectory control algorithms for NIMS3D, an autonomous underconstrained three-dimensional cabled robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 253–240, San Diego, September, 22-26, 2007.
- [borgstrom2008] Borgstrom P.H. and others . Generation of energy efficient trajectories for NIMS3D, a three-dimensional cabled robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 2222–2227, Pasadena, May, 19-23, 2008.
- [borgstrom2008-1] Borgstrom P.H. and others . Energy based path planning for a novel cabled robotic systems. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1745–1751, Nice, France, September, 22-26, 2008.
- [borgstrom2009] Borgstrom P.H. and others . Design and implementation of NIMS3D, a 3-D cabled robot for actuated sensing applications. *IEEE Trans. on Robotics*, 25(2):325–339, April 2009.
- [borgstrom2009-1] Borgstrom P.H. and others . NIMS-PL: A cable-driven robot with self-calibration capabilities.  $IEEE\ Trans.\ on\ Robotics,\ 25(5):1005-1015,\ 2009.$
- [borgstrom2009-2] Borgstrom P.H. and others . Rapid computation of optimally safe tension distributions for parallel cable-driven robots. *IEEE Trans. on Robotics*, 25(6):1271–1281, 2009.
- [borgstrom2009-3] Borgstrom P.H. and others . Field-tests of a redundantly actuated cable-driven robot for environmental sampling applications. In *IEEE Conference on Automation Science and Engineering*, Bangalore, August, 22-25, 2009.
- [borrras2008] Borràs J., Thomas F., and Torras C. Architecture singularities in flagged parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 3844–3850, Pasadena, May, 19-23, 2008.
- [borras2009] Borràs J. and Thomas F. Kinematics of line-plane subassemblies in Stewart platforms. In *IEEE Int. Conf. on Robotics and Automation*, pages 4094–4099, Kobe, May, 14-16, 2009.
- [borras2009-1] Borràs J., Thomas F., and Torras C. Straightening-free algorithm for the singularity analysis of Stewart-Gough platform with colinear/coplan attachments. In *Computational Kinematics*, Duisburg, May, 6-8, 2009.
- [borras2010] Borràs J., Thomas F., and Torras C. A family of quadratically-solvable 5-SPU parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 4703–4708, Anchorage, May, 3-8, 2010.
- [borras2010-1] Borràs J., Thomas F., and Torras C. Singularity invariant leg rearrangements in Stewart-Gough platforms. In ARK, pages 421–428, Piran, June 28- July 1, 2010.

- [borras2011] Borràs J., Thomas F., and Torras C. Architectural singularities of a class of pentapods. *Mechanism and Machine Theory*, 46(8):1107–1120, August 2011.
- [borras2012] Borràs J. and Dollar A.M. Static analysis of parallel robots with compliant joints for in-hand manipulation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3086–3091, Vilamoura, October, 7-12, 2012.
- [borras2012-1] Borràs J. and Thomas F. On the primal and dual forms of the Stewart plztform pure condition. *IEEE Trans. on Robotics*, 28(6):1205–1215, December 2012.
- [borras2013] Borras J. and Dollar A. A parallel robots framework to study precision grasping and dexterous manipulation. In *IEEE Int. Conf. on Robotics and Automation*, pages 1587–1593, Karlsruhe, May, 6-10, 2013.
- [borras2014] Borràs J., Thomas F., and Torras C. New geometric approaches to the analysis and design of Stewart–Gough platforms. *IEEE/ASME Trans. on Mechatronics*, 19(2):445–455, 2014.
- [bortone2018] Bortone I. and others. Wearable haptics and immersive virtual reality rehabilitation training in children with neuromotor impairments. *IEEE Trans. on Neural Systems and Rehabilitation Engineering*, 26(7), July 2018.
- [boschetti2014] Boschetti G. and Trevisani A. Performance evaluation for cable direct driven robot. In 12th Biennial Conference on Engineering Systems Design and Analysis, Copenhagen, July, 25-27, 2014.
- [boschetti2017] Boschetti G. and others . A fast algorithm for wrench exertion capability computation. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [bosscher 2003] Bosscher P. and Ebert-Uphoff I. A novel mechanism for implementing multiple collocated spherical joints. In *IEEE Int. Conf. on Robotics and Automation*, pages 336–341, Taipei, September, 14-19, 2003.
- [bosscher 2004] Bosscher P. and Ebert-Uphoff I. Wrench-based analysis of cable-driven robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 4950–4955, New Orleans, April, 28-30, 2004.
- [bosscher2004-1] Bosscher P. and Ebert-Uphoff I. A stability measure for underconstrained cable-driven robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 4943–4949, New Orleans, April, 28-30, 2004.
- [bosscher 2006] Bosscher P. and Ebert-Uphoff I. Disturbance robustness measures for underconstrained cable-driven robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 4206–4212, Orlando, May, 16-18, 2006.
- [bosscher2006-1] Bosscher P. and others . Cable-suspended robotic contour crafting system. In ASME Design Engineering Technical Conference, Philadelphia, September, 10-13, 2006.
- [bosscher 2007] Bosscher P. and others . Cable-suspended robotic contour crafting system. *Automation in Construction*, 17:45–55, 2007.
- [bossoni2006] Bossoni S. and others . Interaction of metrology, control and modeling in the machine-tool design. In 5th Chemnitzer Parallelkinematik Seminar, pages 135–154, Chemnitz, April, 25-26, 2006.
- [bostelman96] Bostelman R.V. Underwater work platform support system, April, 16, 1996. United States Patent n° 5,507,596 US Secretary of Commerce. **Keywords:** applications,patent.
- [bostelman96-1] Bostelman R., Albus J., Dagalakis N., and Jacoff A. RoboCrane project: an advanced concept for large scale manufacturing. In *Proceedings Association for Unmanned vehicle systems International*, pages 509–521, Orlando, July, 15-19, 1996.
- [bostelman97] Bostelman R., Albus J., and Graham R.E. RoboCrane and Emma applied to waste storage tank remediation. In *American Nuclear Society 7th Topical Meeting on Robotics and Remote Systems*, Augusta, April 27- May 1, 1997.
- [botelloaceves 2018] Botello-Aceves S. and others . Evaluating concurrent design approaches for a Delta parallel manipulator. *Robotica*, 36:697–714, 2018.
- [bouanane92] Bouanane K. and Fenton R.G. Kinematic analysis of parallel manipulators. In ARK, pages 115–122, Ferrare, September, 7-9, 1992.

- [bouchard2008-phd] Bouchard S. Géométrie des robots parallèles entraînés par des câbles. Ph.D. Thesis, Université Laval, Québec, 2008. **Keywords:** wire robot, mechanical architecture, optimal design.
- [bouchemal 2013] Bouchemal B. and Zaatri A. Gestural and image-based control combination. In 1st Int. Conf. on Technology for helping people with special needs, Ryadh, February, 18-20, 2013.
- [boudreau96] Boudreau R. and Turkkan N. Solving the forward kinematics of parallel manipulators with a genetic algorithm. J. of Robotic Systems, 13(2):111–125, February 1996.
- [boudreau98] Boudreau R., Darenfed S., and Turkkan N. Etude comparative de trois nouvelles approches pour la solution du problème géométrique direct des manipulateurs parallèles. *Mechanism and Machine Theory*, 33(5):463–477, July 1998.
- [boudreau98-1] Boudreau R., Levesque G., and Darenfed S. Parallel manipulator kinematics learning using holographic neural network models. *Robotics and Computer-Integrated Manufacturing*, 14(1):37–44, 1998.
- [boudreau99] Boudreau R. and Gosselin C.M. La synthèse d'une plate-forme de Gough-Stewart pour un espace atteignable prescrit. In 10th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 449–454, Oulu, June, 20-24, 1999.
- [boudreau99-1] Boudreau R. and Gosselin C.M. The synthesis of planar parallel manipulators with a genetic algorithm. ASME J. of Mechanical Design, 121(4):533–537, December 1999.
- [bounab2016] Bounab B. Multi-objective optimal design based kineto-elastostatic performance for the delta parallel mechanism. *Robotica*, 34(2):258–273, February 2016.
- [bourbonnais2015] Bourbonnais F., Bigras P., and Bonev I.A. Minimum-time trajectory planning and control of a pick-and-place five-bar parallel robot. *IEEE/ASME Trans. on Mechatronics*, 20(2), Avril February 2015.
- [bouri2010] Bouri M. and Clavel R. The linear delta: Developments and applications. In 41st International Symposium on Robotics, pages 1–8, Munchen, June 2010.
- [bouzgarrou2020] Bouzgarrou C., Koessler A., and Bouton N. Singularity analysis and reconfiguration mode of the  $3-\underline{C}RS$  parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [boye2005] Boye T. and Pritschow G. New transformation and analysis of a N-DOF LINAPOD with six struts for higher accuracy. *Robotica*, 23(5):555–560, September 2005.
- [boye2006] Boye T. and Verl A. Optimal set of poses to calibrate parallel kinematics for given measurement devices. In 5th Chemnitzer Parallelkinematik Seminar, pages 635–653, Chemnitz, April, 25-26, 2006.
- [boztas2022] Boztas S. and Kiper G. Enumeration and instantaneous mobility analysis of a class of 3-UPU parallel manipulators with equilateral triangular platforms. *Robotica*, 40:1538–1569, 2022.
- [bracher 2007] Bracher S., Baron L., and Wang X. Rotating table with parallel kinematic featuring a planar joint. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [brahmia2022] Brahmia A. and others . Kinematic sensitivity analysis of manipulators using a novel dimensionless index. *Robotics and Autonomous Systems*, 150, 2022.
- [brandt96] Brandt G. and others. Development of a robot with optimal kinematics for the treatment of bone structures. In 18th Annual Int. Conf. of the IEEE Engineering in Medicine and Biology Society, Amsterdam, October 31- November 3, 1996.
- [brandt97] Brandt G. and others. A compact robot for image guided orthopedic surgery. In First Joint Conf. of Computer Vision, Virtual Reality and Robotics (CRVMED)II and Medical Robotics and Computer Assisted Surgery (MRCAS)III, Grenoble, March, 19-22, 1997.
- [brandt97-1] Brandt G. and others . Developement of a x-ray image-guided parallel robot for orthopedic surgery. In 2nd Workshop on Medical robotics, pages 69–79, Heidelberg, November, 10-12, 1997.
- [brandt99] Brandt G. and others . CRIGOS: a compact robot for image-guided orthopedic surgery. *IEEE Trans. on Robotics and Automation*, 3(4):252–260, December 1999.

- [brau2005] Brau E., Gosselin F., and Lallemand J-P. Design of a singularity free architecture for cable driven haptic interfaces. In rst Joint Eurohaptics Conference and Symposium on Haptic Interfaces for Virtual Environment and Teleoperator Systems. World Haptics Conference, 2005.
- [brecher 2006] Brecher C. and Hoffmann F. Multi-criteria comparison of standardized kinematic structure for machine-tools. In 5th Chemnitzer Parallelkinematik Seminar, pages 65–82, Chemnitz, April, 25-26, 2006.
- [brecher2006-1] Brecher C. and others . Control concepts for PKM considering the mechanical coupling between actuators. In 5th Chemnitzer Parallelkinematik Seminar, pages 413–427, Chemnitz, April, 25-26, 2006.
- [breguet96] Breguet J-M., Pernette E., and Clavel R. Stick and slip actuators and parallel architectures dedicated to microrobotics. In *Microrobotics: componants and applications, SPIE Photonic East*, pages 13–24, Boston, November 1996.
- [breitbach2005] Breitbach E. and others . Adaptive tools in parallel robotics. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 203–220, Braunschweig, May, 10-11, 2005.
- [brethe2012-h] Brethe J-F. Caractérisation, dimensionnement et des commande des robots manipulateurs industriels pour une meilleure précision, December, 7, 2012. Habilitation à diriger les recherches, Université du Havre. **Keywords:** accuracy.
- [bricard97] Bricard R. Mémoire sur la théorie de l'octaèdre articulé. Journal de Mathématiques pures et appliquées, Liouville, tome 3:113–148, 1897.
- [bricard06] Bricard R. Mémoire sur les déplacements à trajectoire sphériques. *Journal de l'École Polytechnique*, 11(2):1–96, 1906.
- [bringmann2006] Bringmann B. 3D error compensation for parallel kinematics. In 5th Chemnitzer Parallelkinematik Seminar, pages 531–546, Chemnitz, April, 25-26, 2006.
- [brinker2018] Brinker J., Corves B., and Takeda Y. Kinematic performance evaluation of high-speed Delta parallel robots based on motion/force transmission indices. *Mechanism and Machine Theory*, 125:111–125, 2018.
- [briot2007] Briot S. and Arakelian V. Singularity analysis of PAMINSA Manipulators. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [briot2007-1] Briot S. and Bonev I.A. Are parallel robots more accurate than serial robots? *Trans. CSME*, 31(4):445–456, 2007.
- [briot2007-2] Briot S. Analyse et optimisation d'une nouvelle famille de manipulateurs parallèles aux mouvements découplés. Ph.D. Thesis, INSA, Rennes, June 2007. **Keywords:** mechanical architecture, decoupled robot, optimal design, kinematics.
- [briot2008] Briot S. and Arakelian V. On the dynamic properties and optimum control of parallel manipulators in the presence of singularity. In *IEEE Int. Conf. on Robotics and Automation*, pages 1549–1555, Pasadena, May, 19-23, 2008.
- [briot2008-1] Briot S. and Bonev I.A. Accuracy analysis of a 3-dof planar parallel robot. *Mechanism and Machine Theory*, 43(4):445–458, April 2008.
- [briot2008-2] Briot S. and Bonev I.A. Singularity analysis of zero-torsion parallel mechanisms. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1952–1957, Nice, France, September, 22-26, 2008.
- [briot2008-3] Briot S., Arakelian V., and Guégan S. Design and prototyping of a partially decoupled 4-dof 3T1R parallel manipulator with high-load carrying capacity. *ASME J. of Mechanical Design*, 130(12):122303–1/8, December 2008.
- [briot2008-4] Briot S. and others . Self-motions of general  $\underline{R}PR$  planar parallel robots. Int. J. of Robotics Research, 27(7):855-866, July 2008.
- [briot2008-5] Briot S. and Arakelian V. Optimal force generation in parallel manipulators for passing through the singular positions. *Int. J. of Robotics Research*, 27(2):967–983, August 2008.

- [briot2009] Briot S., Arakelian V., and Guégan S. PAMINSA a new family of partially decoupled manipulators. *Mechanism and Machine Theory*, 44(2):425–444, February 2009.
- [briot2009-1] Briot S. and Bonev I.A. Pantotepron: a new fully decoupled 3-dof translational parallel robot for pick-and-place applications. J. of Mechanisms and Robotics, 1(2):021001-1/9, May 2009.
- [briot2010] Briot S., Pashkevich A., and Chablat D. Optimal technology-oriented design of parallel robots for high-speed machining applications. In *IEEE Int. Conf. on Robotics and Automation*, pages 1155–1161, Anchorage, May, 3-8, 2010.
- [briot2010-1] Briot S. and Bonev I.A. Pantopteron-4: A new 3T1R decoupled parallel manipulator for pick-and-place applications. *Mechanism and Machine Theory*, 45(5):707–721, May 2010.
- [briot2010-2] Briot S. and Bonev I.A. Accuracy analysis of 3T1R fully-parallel robots. *Mechanism and Machine Theory*, 45(5):695–708, May 2010.
- [briot2010-3] Briot S. and Arakelian V. On the dynamic properties of rigid-link flexible-joint parallel manipulators in the presence of type 2 singularities. *J. of Mechanisms and Robotics*, 2(2):021004–1/6, May 2010.
- [briot2012] Briot S. and Gautier M. Global identification of drive gains and dynamic parameters of parallel robots part 1: Theory. In *RoManSy*, Paris, June, 12-15, 2012.
- [briot2012-1] Briot S. and Gautier M. Global identification of drive gains and dynamic parameters of parallel robots part 2: Case study. In *RoManSy*, Paris, June, 12-15, 2012.
- [briot2012-2] Briot S. and others . Optimal force generation of 3-RRR decoupled planar robots for ensuring unlimited platform rotation. In *RoManSy*, Paris, June, 12-15, 2012.
- [briot2013] Briot S. and Khalil W. Recursive symbolic calculation of the dynamic model of flexible parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 5413–5418, Karlsruhe, May, 6-10, 2013.
- [briot2013-1] Briot S., Gautier M., and Krut S. Dynamic parameter identification of actuation redundant parallel robots using their power identification model: application to the DualV. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Tokyo, November, 3-7, 2013.
- [briot2013-2"] Briot S., Glazunov V., and Arakelian V. Investigation on the effort transmission in planar parallel manipulators. J. of Mechanisms and Robotics, 5(1), February 2013.
- [briot2014] Briot S., Rosenzveug V., and Martinet P. The hidden robot concept: a tool for control analysis and robot control-based design. In *ARK*, pages 31–39, Ljulbjana, June 29- July 3, 2014.
- [briot2014-1] Briot S. and Khalil W. Recursive and symbolic calculation of the elastodynamic model of flexible parallel robot. *Int. J. of Robotics Research*, 33(3):461–483, April 2014.
- [briot2015] Briot S., Martinet P., and Rosenzveig V. The hidden robot: An efficient concept contributing to the analysis of the controllability of parallel robots in advanced visual servoing techniques. *IEEE Trans. on Robotics*, 31(6):1337–1352, December 2015.
- [briot2016] Briot S. and others . Degeneracy conditions of the dynamic model of parallel robots.  $Multibody\ System\ Dynamics,\ 37(4):371-412,\ 2016.$
- [briot2016-1] Briot S. and others. Minimal representation for the control of parallel robots via leg observation considering a hidden robot model. *Mechanism and Machine Theory*, 106:115–147, December 2016.
- [briot2016-h] Briot S. Contribution à la maîtrise de la dynamique des robot parallèles, January, 8, 2016. Habilitation à diriger les recherches, Université de Nantes. **Keywords:** kinematics, design, dynamics.
- [briot2017] Briot S., Chaumette F., and Martinet P. Revisiting the determination of the singularity cases in the visual servoing of images points through the concept of hidden robot. *IEEE Trans. on Robotics*, 33(3):536–546, July 2017.
- [briot2017-1] Briot S., Caro S., and Germain C. Design procedure for a fast and accurate parallel manipulator. *J. of Mechanisms and Robotics*, 9(6), 2017.

- [briot2018] Briot S. and Goldsztejn A. Topology optimization of industrial robots: Application to a five-bar mechanism. *Mechanism and Machine Theory*, 120:30–56, 2018.
- [briot2023] Briot S. and Merlet J-P. Direct kinematic singularities and stability analysis of sagging cable-driven parallel robots. *IEEE Trans. on Robotics*, 2023.
- [brisan2002] Brisan C., Franitza D., and Hiller M. Modelling and analysis of errors for parallel robots. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 83–96, Braunschweig, May, 29-30, 2002.
- [brisan2002-1] Brisan C. and Hiller M. Particular aspects in designing anthropomorphic mechanisms. In ARK, pages 99–106, Caldes de Malavalla, June 29- July 2, 2002.
- [brisan2011] Brisan C. and Csiszar A. Computation and analysis of the workspace of a reconfigurable parallel robotic system. *Mechanism and Machine Theory*, 46:1647–1668, 2011.
- [brodsky98] Brodsky V., Glozman D., and Shoham M. Double circular-triangular six-degree-of-freedom parallel robot. In ARK, pages 155–164, Strobl, June 29- July 4, 1998.
- [brogardh2002] Brogardh T. and Gu C.Y. Parallel robot development at ABB. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 229–244, Braunschweig, May, 29-30, 2002.
- [brogardh2005] Brogardh T., Hanssen S., and Hovland G. Application-oriented development of parallel kinematic manipulators with large workspace. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 153–170, Braunschweig, May, 10-11, 2005.
- [brooks93] Brooks T.L., Cleary K.R., and Uebel M. Six degree of freedom motion devices, November, 23, 1993. United States Patent n° 5,263,382 Hughes Aircraft Company. **Keywords:** mechanical architecture, patent.
- [bruckmann2006] Bruckmann T., Pott A., and Hiller M. Calculating force distributions for redundantly actuated tendon-based Stewart platforms. In ARK, pages 403–412, Ljubljana, June, 26-29, 2006.
- [bruckmann2006-1] Bruckmann T., Pott A., Franitza D., and Hiller M. A modular controller for redundantly actuated tendon-based Stewart platforms. In 1st European Conf. on Mechanism Science (Eucomes), Obergurgl, February, 21-26, 2006.
- [bruckmann2008] Bruckmann T. and others . Parallel manipulators, New Developments, chapter Wire robot part I, kinematics, analysis and design, pages 109–132. ITECH, April 2008. **Keywords:** wire robot,kinematics,statics,mechanical architecture,optimal design.
- [bruckmann2008-1] Bruckmann T. and others . Parallel manipulators, New Developments, chapter Wire robot part II, dynamics, control & applications, pages 133–152. ITECH, April 2008. **Keywords:** wire robot,dynamics,control,statics.
- [bruckmann2008-2] Bruckmann T., Mikelsons L., and Hiller M. A design-to-task approach for wire robots. In 1st Conf. on Interdisciplinary Applications in Kinematics, Lima, January, 9-11, 2008.
- [bruckmann2010] Bruckmann T., Hiller M., and Schramm D. An active suspension system for simulation of ship maneuvers in wind tunnels. In 3rd European Conf. on Mechanism Science (Eucomes), Cluj-Napoca, September, 14-17, 2010.
- [bruckmann2012] Bruckmann T. and others . Development of a storage retrieval machine for high racks using a wire robot. In ASME DETC, Chicago, 2012.
- [bruckmann2015] Bruckmann T., Merlet J-P., Spanjer S., and Herder J. Puppet on a string. *Mikroniek*, 6:40–44, 2015.
- [bruckmann2017] Bruckmann T. and others. Concept studies of automated construction using cable-driven parallel robots. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [bruckmann2018] Bruckmann T., Reicheirt C., and Ji H. Energy consumption reduction of a cable-driven storage and retrieval system. In ARK, Bologna, July, 1-5, 2018.

- [bruni2007] Bruni S., Cerveri P., and Espinosa I. An application of an hybrid robot in the total knee replacement procedure. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [bruyninckx96] Bruyninckx H. and De Shutter J. A class of fully parallel manipulators with closed-form forward position kinematics. In ARK, pages 411–420, Portoroz-Bernadin, June, 22-26, 1996.
- [bruyninckx97] Bruyninckx H. The 321-hexa: a fully parallel manipulator with closed-form position and velocity kinematics. In *IEEE Int. Conf. on Robotics and Automation*, pages 2657–2662, Albuquerque, April, 21-28, 1997.
- [bruyninckx97-1] Bruyninckx H. The analytical forward displacement kinematics of the 32-12 parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 2956–2960, Albuquerque, April, 21-28, 1997.
- [bruyninckx98] Bruyninckx H. Closed-form position kinematics of a  $(3-1-1-1)^2$  fully parallel manipulator. *IEEE Trans. on Robotics and Automation*, 14(2):326–328, April 1998.
- [bruyninckx98-1] Bruyninckx H. and De Schutter J. Unified kinetostatics for serial, parallel and mobile robots. In ARK, pages 343–352, Strobl, June 29- July 4, 1998.
- [bruyninckx99] Bruyninckx H. Forward kinematics for Hunt-Primrose parallel manipulators. *Mechanism and Machine Theory*, 34(4):657–664, May 1999.
- [bruzzone2002] Bruzzone L.E., R. Molfino, and Zoppi M. A cost-effective purely translational parallel robot for rapid assembly tasks. In 3rd Chemnitzer Parallelkinematik Seminar, pages 429–440, Chemnitz, April, 23-25, 2002.
- [bruzzone2002-1] Bruzzone L.E., R. Molfino, and Razzoli R.P. Modelling and design of a parallel robot for laser-cutting applications. In *IASTED Int. Conf. Modelling, Identification and Control*, pages 518–522, Innsbruck, February, 18-21, 2002.
- [bruzzone2003] Bruzzone L.E. and R. Molfino. Special-purpose parallel robot for active suspension of ambulance stretchers. *Int. J. of Robotics and Automation*, 18(3):121–129, 2003.
- [bruzzone2003-1] Bruzzone L.E. and others . Experimental tests on the prototype of an impedance controlled three-degree-of-freedom parallel robot. In *RAAD*, Cassino, May, 7-10, 2003.
- [bruzzone2003-2] Bruzzone L.E. and others . The PRIDE prototype: control layout of a parallel robot for assembly tasks. In *IASTED Int. Conf. Modelling, Identification and Control*, pages 606–611, Innsbruck, February, 10-13, 2003.
- [bruzzone 2004] Bruzzone L.E., R. Molfino, and Zoppi M. Kinematic modelling and simulation of a novel interconnected-chains PKM. In *Int. Conf. Modelling*, *Identification and Control*, *MIC2004*, Grindelwald, February, 23-25, 2004.
- [bruzzone2005] Bruzzone L.E., R. Molfino, and Zoppi M. An impedance-controlled parallel robots for high-speed assembly of white goods. *Industrial Robot*, 32(3):226–233, 2005.
- [bryfogle95] Bryfogle M.D. Material handling devices and controllers, September, 19, 1995. United States Patent n° 5,451,136. **Keywords:** applications, patent.
- [bryfogle97] Bryfogle M.D., Nguyen C.C., Zhou Z-l., and Antrazi S.S. A methodology for geometry design of closed kinematic chain mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 2974–2979, Albuquerque, April, 21-28, 1997.
- [bryson2016] Bryson J.T. The optimal design of cable-driven robots. Ph.D. Thesis, University of Delaware, 2017. **Keywords:** wire robot, optimal design.
- [bu2106] Bu W. Closeness to singularities of robotic manipulators measure by characteristic angles. *Robotica*, 34:2105–2115, 2016.
- [bu2107] Bu W. Closeness to singularities of manipulators based on geometric average normalized volume spanned by weighted screws. *Robotica*, 35(7):1616–1626, 2017.

- [budde2007] Budde C., Last P., and Hesselbach J. Development of a Triglide robot with enlarged workspace. In *IEEE Int. Conf. on Robotics and Automation*, pages 543–548, Roma, April, 10-14, 2007.
- [budde2008] Budde C. and others . Automatic detection of assembly mode for a Triglide-robot. In *IEEE Int. Conf.* on Robotics and Automation, pages 1568–1575, Pasadena, May, 19-23, 2008.
- [bulca96] Bulca F., Angeles J., and Zsombor-Murray P.J. On the workspace analysis of a spherical platform mechanisms. In *World Automation Congress*, volume 3, pages 131–136, Montpellier, May, 28-30, 1996.
- [bulca99] Bulca F., Angeles J., and Zsombor-Murray P.J. On the workspace determination of spherical serial and platform mechanisms. *Mechanism and Machine Theory*, 34(3):497–512, April 1999.
- [burdet2000] Burdet E., Honegger M., and Codourey A. Controllers with desired dynamic compensation and their implementation on a 6 dof parallel manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Takamatsu, October 30- November 5, 2000.
- [burisch2010] Burisch A. and others . Analysis and inverse dynamic model of a miniaturized robot structure. In 3rd European Conf. on Mechanism Science (Eucomes), Cluj-Napoca, September, 14-17, 2010.
- [bury2020-1] Bury D. and others . Continuous tension validation for cable-driven parallel robots. In *IEEE Int. Conf.* on *Intelligent Robots and Systems (IROS)*, Las Vegas, October, 25-29, 2020.
- [buruncuk99] Bürüncük K. and Tokad Y. On the kinematic of a 3-DOF Stewart Platform. *J. of Robotic Systems*, 16(2):105–117, 1999.
- [bury2019] Bury D. and others . Continuous collision detection for a robotic arm mounted on a cable-driven parallel robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Macau, November, 4-8, 2019.
- [bury2020] Bury D. Planification de tâches de manipulation pour robots parallèles à câbles. Ph.D. Thesis, Université de Toulouse, Toulouse, December, 17, 2020. **Keywords:** wire robot, trajectory planning.
- [butefisch-2000] Bütefisch S. and others . A new SMA actuated miniature silicon gripper for micro assembly. In 7th Int. Conf. on New Actuators, pages 334–337, Bremen, June, 19-20, 2000.
- [buttgenbach2002] Büttgenbach S. and others . Microsensors for parallel robot. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 141–152, Braunschweig, May, 29-30, 2002.
- [buttgenbach2005] Büttgenbach S. and others . Development of angular joint-sensors and application to parallel robots. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 237–252, Braunschweig, May, 10-11, 2005.
- [byun95] Byun Y.K., Kim D.Y., and Cho H-S. Analysis of a 6-dof pose/wrench sensor integrated Stewart platform-based robotic wrist. In 4th Int. Symp. on Measurement and Control in Robotics, pages 283–288, Smolenice Castle, Slovaquie, June, 12-16, 1995.
- [byun97] Byun Y.K. and Cho H-S. Analysis of a novel 6-dof,3-PPSP parallel manipulator. *Int. J. of Robotics Research*, 16(6):859–872, December 1997.
- [caccavale2000] Caccavale F. and others . On the dynamics of a class of parallel robots. In ARK, pages 187–196, Piran, June, 25-29, 2000.
- [cai-g99] Cai G.Q. and others . Development and study of a new kind of 3-dof tripod. Annals of the CIRP, 48(1):333–336, 1999.
- [cai2017] Cai K. and others . Design and control of a 6-degree-of-freedom precision positioning system. *Robotics and Computer-Integrated Manufacturing*, 44:77–96, 2017.
- [callegari2003] Callegari M. and Tarantini M. Kinematic analysis of a novel translational platform. ASME J. of Mechanical Design, 125(2):308–315, June 2003.
- [callegari2003-1] Callegari M. and Marzetti P. Kinematics of a family of parallel translating mechanisms. In RAAD, Cassino, May, 7-10, 2003.

- [callegari2004] Callegari M. and Marzetti P. Kinematic characterization of the 3-<u>P</u>UU parallel robot. In *Proc. Intelligent Manipulation and Grasping, IMG'04*, pages 377–382, Genova, June 30- July 1, 2004.
- [callegari2004-1] Callegari M., Marzetti P., and Olivieri B. Kinematics of a parallel mechanism for the generation of spherical motions. In ARK, pages 449–458, Sestri-Levante, June 28- July 1, 2004.
- [callegari2005] Callegari M., Palpacelli M., and Scarponi M. Kinematics of the 3-CPU parallel manipulator assembled for motions of pure translation. In *IEEE Int. Conf. on Robotics and Automation*, pages 4031–4036, Barcelona, April, 19-22, 2005.
- [callegari2006] Callegari M. and Palpacelli M-C. Kinematics and optimization of the translating 3-CCR/3-RCC parallel mechanisms. In ARK, pages 423–432, Ljubljana, June, 26-29, 2006.
- [callegari2007] Callegari M. and Cammarata A. Kinematics and dynamics of a 3-CRU spherical parallel robot. In ASME IDETC/CIE, Las Vegas, September, 4-7, 2007.
- [callegari2008] Callegari M. and Palpacelli M-C. Prototype design of a translating parallel robot. *Meccanica*, 43(2):135–151, April 2008.
- [callegari2008-1] Callegari M. Parallel manipulators, New Developments, chapter Design and prototyping of a spherical parallel machine based on 3-CPU kinematics, pages 172–198. ITECH, April 2008. **Keywords:** 3 dof robot,wrist,kinematics,dynamics,structural synthesis.
- [callegari2008-2] Callegari M., Gabrielli A., and Ruggiu M. Kineto-elasto-static synthesis of a 3-CRU spherical wrist for miniaturized assembly tasks. *Meccanica*, 43(4):377–389, August 2008.
- [callegari2009] Callegari M. and others . Analysis and design of a spherical micromechanism with flexure hinges. ASME J. of Mechanical Design, 131(5), April 2009.
- [callegari2013] Callegari M., Carbonari L., Palmieri G., and Palpacelli M-Co. *Parallel Wrists for Enhancing Grasping Performance*, pages 189–219. Springer London, 2013. **Keywords:** wrist,3 dof robot,mechanical architecture.
- [camacho2020] Camacho-Arreguin J. and others . A novel class of reconfigurable parallel kinematic manipulators: Concepts and Fourier-based singularity analysis. *Mechanism and Machine Theory*, 153, 2020.
- [cammarata2014] Cammarata A. and Sinatra R. Elastodynamic optimization of a 3T1R parallel manipulator. *Mechanism and Machine Theory*, 73:184–196, March 2014.
- [cammarata2016] Cammarata A. and others . Dynamic stiffness model of spherical parallel robots. *Journal of Sound and Vibration*, 384:312–324, 2016.
- [cammarata2020] Cammarata A. Full and reduced models for the elastodynamics of fully flexible parallel robots. Mechanism and Machine Theory, 151, 2020.
- [campa2022] F.J. Campa and others . Analysis of a compliant parallel manipulator for torso balance rehabilitation. In ARK, Bilbao, June, 26-30, 2022.
- [campolo2014] Campolo D. and others . H-Man: a planar, H-shape cabled differential robotic manipulandum for experiments on human motor control. *Journal of Neuroscience Methods*, 235, 2014.
- [campos2008] Campos A. and others . An active helideck testbed for floating structures based on a Stewart-Gough platform. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3705–3710, Nice, France, September, 22-26, 2008.
- [canfield97] Canfield S.L. and Reinholtz C.F. Development of the carpal robotic wrist. In *ISER*, pages 360–371, Barcelone, June, 15-18, 1997.
- [canfield99] Canfield S.L., Soper R.R., and Reinholtz C.F. Velocity analysis of parallel manipulators by truss transformations. *Mechanism and Machine Theory*, 34(3):345–357, April 1999.
- [cano2006] Cano T. and others . Measuring the deformation of a parallel kinematics machine under dynamic conditions, by combining video and accelerometers. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Beijing, October, 9-15, 2006.

- [cao-w-2018] Cao W-A., Yang D., and Ding H. A method for stiffness analysis of overconstrained parallel robotic mechanisms with scara motion. *Robotics and Computer-Integrated Manufacturing*, 49:426–435, 2018.
- [cao-w-2018-1] Cao W-A. and Ding H. A method for solving all joint reactions of 3R2T parallel mechanisms with complicated structures and multiple redundant constraints. *Mechanism and Machine Theory*, 121:718–730, 2018.
- [cao-wa2019] Cao W-A., Ding H., and Zhu W. Stiffness modeling of overconstrained parallel mechanisms under considering gravity and external payloads. *Mechanism and Machine Theory*, 135:1–16, 2019.
- [cao2005] Cao Y., Huang Z., and Ge Q.J. Orientation singularity and orientation capability analyses of the Stewart-Gough manipulator. In *ASME Design Engineering Technical Conference*, Long Beach, September, 24-28, 2005.
- [cao2010] Cao Y. and others . Orientation-singularity and nonsingular orientation-workspace analysis of the semi-regular Stewart-Gough platform manipulator.  $Advanced\ Robotics,\ 24(15):2119-2135,\ 2010.$
- [cao2013] Cao Y. and others. Orientation-singularity analysis and orientationability evaluation of a special class of the Stewart–Gough parallel manipulators. *Robotica*, 31(8):1361–1372, December 2013.
- [cao2016] Cao S., Luo Z., and Quan C. Passive velocity field control of a redundant cable-driven robot with tension limitations. In *IEEE International Conference on Robotics and Biomimetics*, Qingdao, December, 3-7, 2016.
- [cao2020] Cao Y. and others . Construction method of parallel mechanisms with a partially constant jacobian matrix. Mechanism and Machine Theory, 145, 2020.
- [cappel67] Cappel K.L. Motion simulator, January, 3, 1967. United States Patent n° 3,295,224 The Franklin Institute. **Keywords:** applications, patent, simulator.
- [cappel99] Cappel K.L. Invention and development of the Synergistic motion system. January 1999, http://www.triz-journal.com/archives/1999/01/a. **Keywords:** history.
- [capua2010] Capua A., Shapiro A., and Shoval S. Motion planning algorithm for a mobile robot suspended by seven cables. In *IEEE Int. Conf. on Robotics and Automation*, Anchorage, May, 3-8, 2010.
- [capua2011] Capua A., Shapiro A., and Shoval S. Spiderbot: A cable suspended mobile robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 5135–5140, Shangai, May, 9-13, 2011.
- [capua2014] Capua A., Shapiro A., and Shoval S. SpiderBot: a cable-suspended walking robot. *Mechanism and Machine Theory*, 82:56–70, 2014.
- [capustiac2010] Capustiac A. and Brisan C. Aspect concerning VRML simulation of calibration for parallel mechanisms. In 3rd European Conf. on Mechanism Science (Eucomes), Cluj-Napoca, September, 14-17, 2010.
- [carabin2021] Carabin G. and others . An energy-efficient approach for 3d printing with a linear Delta robot equipped with optimal springs. *Robotics and Computer-Integrated Manufacturing*, 67, 2021.
- [carbonari2012] Carbonari L. and Callegari M. The kinematotropic 3-CPU parallel robot: analysis of mobility and reconfigurability aspects. In ARK, pages 373–380, Innsbruck, June, 25-28, 2012.
- [carbonari2014] Carbonari L. and others . Simplified model for inverse dynamics control of the Cartesian parallel manipulator I.Ca.Ro. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 1406–1412, Besancon, July, 8-11, 2014.
- [carbonari2014-1] Carbonari L. and others . Analysis of kinematics and reconfigurability of a spherical parallel manipulator. *IEEE Trans. on Robotics*, 30(6):1541–1547, December 2014.
- [carbone2001] Carbone G., Ceccarelli M., and Teolis M. A numerical evaluation of the stiffness of CaHyMan (cassino hybrid manipulator). In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 145–154. EJCK, May, 20-22, 2001. **Keywords:** stiffness,hybrid robot.
- [carbone2003] Carbone G. and others . A study of feasibility for a macro-milli serial parallel robot manipulator for surgery operated by a 3 dofs haptic device. In RAAD, Cassino, May, 7-10, 2003.

- [carbone2005] Carbone G. and Ceccarelli M. A serial-parallel robotic architecture for surgical tasks. *Robotica*, 23(3):345–354, 2005.
- [carbone2009] Carbone G. and others . Design improvements on a carotid blood flow measurement system. In *Computational Kinematics*, pages 283–290, Duisburg, May, 6-8, 2009.
- [carboni2020] Carboni A.P., Simas H., and Martins D. Actuation scheme enumeration and optimal selection for parallel mechanisms based on matroid theory. *Mechanism and Machine Theory*, 151, 2020.
- [cardou2007] Cardou P. and Angeles J. Simplectic architectures for true multi-axial accelerometers: a novel application of parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 181–186, Roma, April, 10-14, 2007.
- [caro2006] Caro S. and others . Sensitivity analysis of the Orthoglide: a three-dof translational parallel kinematic machine. ASME J. of Mechanical Design, 128(2):392–402, March 2006.
- [caro2009] Caro S. and others . Sensitivity analysis of  $3-R\underline{P}R$  planar parallel manipulators. ASME J. of Mechanical Design, 131(12):121004-1/13, December 2009.
- [caro2012] Caro S., Wenger P., and Chablat D. Non-singular assembly mode changing trajectories of a 6-dof parallel robot. In ASME IDETC/CIE, Chicago, August, 12-15, 2012.
- [caro2012-1] Caro S., Chablat D., and Chen C. Elastostatic modeling and shape optimization of a 6 dof haptic interface device. In ASME ESDA, Nantes, 2012.
- [caro2012-2] Caro S. and others . A branch and prune algorithm for the computation of generalized aspects of parallel robots. In *Principles and Practice of Constraint Programming*, pages 867–882, 2012.
- [caro2014-h] Caro S. Contributions à la conception et l'analyse de manipulateurs parallèles et de robot d'usinage, December, 5, 2014. Habilitation à diriger les recherches, Université de Nantes. **Keywords:** kinematics,design,singularity.
- [caro2020] Caro S. and Merlet J-P. Failure analysis of a collaborative 4-1 cable-driven parallel robot. In *EUCOMES*, Cluj-Napoca, virtual, 2020.
- [carpanzano2006] Carpanzano E. and others. An open source real time environment for control solutions design, optimization and testing of parallel kinematics machines. In 5th Chemnitzer Parallelkinematik Seminar, pages 457–479, Chemnitz, April, 25-26, 2006.
- [carpio2018] Carpio-Aleman M.A. and others. Collision and tension analysis of cable-driven parallel robot for positionning and orientation. In *IEEE Int. Autumn Meeting on Power, Electronic and Computing (ROPEC)*, 2018.
- [carretero97] Carretero J. A. and others . Kinematic analysis of a three-dof parallel mechanism for telescope applications. In ASME Design Engineering Technical Conference, pages DETC97/DAC-3981, Sacramento, September, 14-17, 1997.
- [carretero2000] Carretero J. A. and others. Kinematic analysis and optimization of a new three degree-of-freedom spatial parallel manipulator. ASME J. of Mechanical Design, 122(1):17–24, March 2000.
- [carretero2006] Carretero J. A. and Pond G.T. Quantitative dexterous workspace comparison. In ARK, pages 297–306, Ljubljana, June, 26-29, 2006.
- [carretero2008] Carretero J. A., Ebrahimi I., and Boudreau R. A comparison between two motion planning strategies for kinematically redundant parallel manipulators. In ARK, pages 243–251, Batz/mer, June, 23-26, 2008.
- [carricato2002-1] Carricato M. and Parenti-Castelli V. Singularity-free fully isotropic translational parallel mechanisms. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [carricato2002] Carricato M. and Parenti-Castelli V. Singularity-free fully isotropic translational parallel mechanisms. *Int. J. of Robotics Research*, 21(2):161–174, February 2002.
- [carricato2003] Carricato M. and Parenti-Castelli V. A family of 3-DOF translational parallel manipulators. ASME J. of Mechanical Design, 125(2):302–307, June 2003.

- [carricato2003-1] Carricato M. and Parenti-Castelli V. Position analysis of a new family of 3-dof translational parallel manipulators. ASME J. of Mechanical Design, 125(2):316–322, June 2003.
- [carricato2004] Carricato M. and Parenti-Castelli V. A novel fully decoupled two-degrees-of-freedom parallel wrist. *Int. J. of Robotics Research*, 23(6):661667, June 2004.
- [carricato2005] Carricato M. Fully isotropic four-degrees-of-freedom parallel mechanisms for Schoenflies motion. *Int. J. of Robotics Research*, 24(5):397–414, May 2005.
- [carricato2009] Carricato M. and Gosselin C. On the modelling of leg constraints in the dynamic analysis of Gough/Stewart-type platforms. ASME Journal of Computational and Nonlinear Dynamics, 4, Janvier May 2009.
- [carricato2010] Carricato M. and Merlet J-P. Geometrico-static analysis of under-constrained cable-driven parallel robot. In ARK, pages 309–320, Piran, June 28- July 1, 2010.
- [carricato2011] Carricato M. and Merlet J-P. Direct geometrico-static problem of under-constrained cable-driven parallel robots with three cables. In *IEEE Int. Conf. on Robotics and Automation*, pages 3011–3017, Shangai, May, 9-13, 2011.
- [carricato2012] Carricato M., Abbasnejad G., and Walter D. Inverse geometrico-static analysis of under-constrained cable-driven parallel robots with four cables. In ARK, pages 365–372, Innsbruck, June, 25-28, 2012.
- [carricato2012-1] Carricato M. and Abbasnejad G. Direct geometrico-static analysis of under-constrained cable-driven parallel robots with 4 cables. In 1st Int. Conf. on cable-driven parallel robots (CableCon), pages 269–286, Stuttgart, September, 3-4, 2012.
- [carricato2013] Carricato M. and Merlet J-P. Stability analysis of underconstrained cable-driven parallel robots. *IEEE Trans. on Robotics*, 29(1):288–296, 2013.
- [carricato2013-1] Carricato M. Inverse geometrico-static problem of underconstrained cable-driven parallel robots with three cables. J. of Mechanisms and Robotics, 5(3), August 2013.
- [carricato2013-2] Carricato M. Direct geometrico-static problem of underconstrained cable-driven parallel robots with three cables. J. of Mechanisms and Robotics, 5(3), August 2013.
- [carvalho2001] Carvalho J.C.M. and Ceccarelli M. The inverse dynamics of Cassino parallel manipulator. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 301–308. EJCK, May, 20-22, 2001. **Keywords:** dynamics.
- [carvalho2001-1] Carvalho J.C.M. and Ceccarelli M. A closed-form formulation for the inverse dynamics of a cassino parallel manipulator. *Multibody System Dynamics*, 5:185–210, 2001.
- [castellet98-phd] Castellet A. Solving inverse kinematics problems using an interval method. Ph.D. Thesis, Universitat Politechnica de Catalunya, Barcelone, June 1998. **Keywords:** forward kinematics.
- [castelli2009] Castelli G. and Ottaviano E. Modeling and simulation of a cable-based parallel manipulator as an assisting device. In *Computational Kinematics*, pages 17–24, Duisburg, May, 6-8, 2009.
- [castelli2010] Castelli G. and Ottaviano E. Modelling, simulation and testing of a reconfigurable cable-based parallel manipulator as motion aiding system. *Applied Bionics and Biomechanics*, 7(4):235–268, December 2010.
- [castelli2014] Castelli G., Ottaviano E., and Rea P. A cartesian cable-suspended robot for improving end-users mobility in an urban environment. *Robotics and Computer-Integrated Manufacturing*, 30(3):335–343, June 2014.
- [castillo2008] Castillo-Castaneda E. and Takeda Y. Improving path accuracy of a crank-type 6-dof parallel mechanism by stiction compensation. *Mechanism and Machine Theory*, 43(1):104–114, January 2008.
- [castillo2003] Castillo-Castaneda E. and others . Precision motion control of a crank-type 6 dof parallel mechanism. In RAAD, Cassino, May, 7-10, 2003.
- [castillo2007] Castillo-Castaneda E., Fonseca-Reyes M.J., and López-Cajún C.S. Non-linear control to compensate low velocity friction of a planar parallel robot. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.

- [cauchy13] Cauchy A. Deuxième mémoire sur les polygones et les polyèdres. *Journal de l'École Polytechnique*, pages 87–98, May 1813.
- [caverly2014] Caverly R.J. and Forbes J.R. Dynamic modeling and noncollocated control of a flexible planar cable-driven manipulator. *IEEE Trans. on Robotics*, 30(6):1386–1397, December 2014.
- [cazalilla2014] Cazalilla J. and others . Implementation of dynamic controllers using real-time middleware for a low-cost parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, Hong-Kong, 7 December 31- June , 2014.
- [ceccarelli93] Ceccarelli M., Ferraresi C., and Sorli M. Stiffness evaluation of a 6 d.o.f. platform prototype. In 3rd Int. Symp. on Measurement and Control in Robotics, pages Bm.III-19,Bm.III-24, Turin, September, 21-24, 1993.
- [ceccarelli96] Ceccarelli M. A study of feasibility for a new wrist. In World Automation Congress, volume 3, pages 161–166, Montpellier, May, 28-30, 1996.
- [ceccarelli97] Ceccarelli M. A new 3 d.o.f. spatial parallel mechanism. *Mechanism and Machine Theory*, 32(8):896–902, 1997.
- [ceccarelli98] Ceccarelli M. and Sorli M. The effects of design parameters on the workspace of a Turin parallel robot. *Int. J. of Robotics Research*, 17(8):886–902, August 1998.
- [ceccarelli98-1] Ceccarelli M. A stiffness analysis for CAPAMAN, the Cassino Parallel Manipulator. In *New machine concepts for handling and manufacturing devices on the basis of parallel structures*, pages 67–80, Braunschweig, November, 10-11, 1998.
- [ceccarelli2002] Ceccarelli M. An optimum design of parallel manipulators: formulation and experimental validation. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 47–64, Braunschweig, May, 29-30, 2002.
- [ceccarelli2002-1] Ceccarelli M. and Ottaviano E. A workspace evaluation of an Eclipse robot. *Robotica*, 20(3):299–313, May 2002.
- [ceccarelli2005] Ceccarelli M. and Carbone G. Numerical and experimental analysis of the stiffness performances of parallel manipulators. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 21–36, Braunschweig, May, 10-11, 2005.
- [ceccarelli2007] Ceccarelli M., Ottaviano E., and Tavolieri C. Experimental activity on cable-based parallel manipulators: issues and results at LARM in Cassino. In 2nd Int. Congress, Design and Modelling of mechanical systems, Monastir, March, 19-21, 2007.
- [celaya2002] Celaya E. Interval propagation for solving parallel spherical mechanisms. In ARK, pages 415–422, Caldes de Malavalla, June 29- July 2, 2002.
- [cenati2002] Cenati C. and others. Methodological aspects on pose error characterization and calibration of parallel kinematic machines (PKM). Proposal of a structured self-calibration procedure. In 3rd Chemnitzer Parallelkinematik Seminar, pages 963–981, Chemnitz, April, 23-25, 2002.
- [cervantes99] Cervantez-Sanchez J.J. and Rendon-Sanchez J.G. A simplified approach for obtaining the workspace of a class of 2-dof planar parallel robot. *Mechanism and Machine Theory*, 34(7):1057–1073, October 1999.
- [cervantes-h2017] Cervantes-Culebro H. and others . Constraint-handling techniques for the concurrent design of a five-bar parallel robot. *IEEE Access*, 2017.
- [cervantes-h2021] Cervantes-Culebro H. and others . Concurrent design of a 2 dof five-bar parallel robot a hybrid design of rigid and flexible links. *IEEE Access*, 2021.
- [cha2007] Cha S-H., Lasky T.A., and Velinsky S.A. Singularity avoidance for the 3-rrr mechanism using kinematic redundancy. In *IEEE Int. Conf. on Robotics and Automation*, pages 1195–1200, Roma, April, 10-14, 2007.
- [chablat96] Chablat D. and Wenger P. Domaine d'unicité pour les robots parallèles. Research Report 96-13, Ecole Centrale, Nantes, December 1996.
- [chablat98] Chablat D., Wenger P., and Angeles J. The isoconditionning loci of a class of closed-chain manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1970–1975, Louvain, May, 18-20, 1998.

- [chablat98-1] Chablat D. and Wenger P. Moveability and collision analysis for fully-parallel manipulators. In 12th RoManSy, pages 61–68, Paris, July, 6-9, 1998.
- [chablat98-phd] Chablat D. Domain d'unicité et parcourabilité pour les manipulateurs pleinement parallèles. Ph.D. Thesis, Ecole Centrale, Nantes, November, 6, 1998. **Keywords:** singularity,workspace.
- [chablat2000] Chablat D. and Wenger P. A new three-dof parallel mechanism: milling machine applications. In 2nd Chemnitzer Parallelkinematik Seminar, pages 141–152, Chemnitz, April, 12-13, 2000.
- [chablat2001] Chablat D. and Angeles J. The computation of all 4r serial spherical wrists with an isotropic architecture. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 1–10. EJCK, May, 20-22, 2001. **Keywords:** spherical robot, isotropy.
- [chablat2002] Chablat D., Wenger P., and Merlet J-P. Workspace analysis of the Orthoglide using interval analysis. In ARK, pages 397–406, Caldes de Malavalla, June 29- July 2, 2002.
- [chablat2002-1] Chablat D. and others . The isoconditioning loci of planar three-dof parallel manipulators. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [chablat2003] Chablat D. and Wenger P. Architecture optimization of a 3-dof translational parallel mechanism for machining applications, the Orthoglide. *IEEE Trans. on Robotics and Automation*, 19(3):403–410, June 2003.
- [chablat2003-1] Chablat D., Majou F., and Wenger P. The optimal design of a three degree-of-freedom parallel mechanism for machining applications. In 11th ICAR, pages 1775–1780, Coimbra, June 30- July 3, 2003.
- [chablat 2004] Chablat D., Wenger P., and Merlet J-P. A comparative study between two three-dof parallel kinematic machines using kinetostatic criteria and interval analysis. In 11th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1209–1213, Tianjin, April, 1-4, 2004.
- [chablat2004-1] Chablat D., Wenger P., Majou F., and Merlet J-P. An interval analysis based study for the design and the comparison of three-degrees-of-freedom parallel kinematic machine. *Int. J. of Robotics Research*, 23(6):615–624, 2004.
- [chablat2006] Chablat D., Wenger P., Majou F., and Bonev I.A. Self motion of a special  $3 \underline{R}PR$  planar parallel robot. In ARK, pages 221–228, Ljubljana, June, 26-29, 2006.
- [chablat2006-1] Chablat D. and Angeles J. The design of a novel prismatic drive for a three-dof parallel-kinematic machine. ASME J. of Mechanical Design, 128(4):710–718, July 2006.
- [chablat2008] Chablat D. Contribution à l'analyse et à l'optimisation de mécanismes poly-articulés, March, 31, 2008. Habilitation à diriger les recherches, Université de Nantes. **Keywords:** isotropy,design,optimal design,singularity.
- [chablat2010] Chablat D. and others . Comparison of planar parallel manipulator architectures based on a multi-objective design optimization approach. In ASME Design Engineering Technical Conference, Montréal, August, 15-18, 2010.
- [chablat2011] Chablat D., Ottaviano E., and Moroz G. A comparative study of 4-cable planar manipulators based on cylindrical algebraic decomposition. In *ASME Design Engineering Technical Conference*, pages 1253–1262, Washington, August, 28-31, 2011.
- [chablat2012] Chablat D. and others . Solution regions in the parameter space of a 3-RRR decoupled robot for a prescribed workspace. In ARK, pages 357–364, Innsbruck, June, 25-28, 2012.
- [chablat2013] Chablat D. and others . Workspace and joint space analysis of the 3-RPS parallel robot. In ASME DETC, Buffalo, 2013.
- [chablat2014] Chablat D. and others . Non-singular assembly mode changing trajectories in the workspace for the  $3-R\underline{P}S$  parallel robot. In ARK, pages 41–49, Ljulbjana, June 29- July 3, 2014.
- [chablat2016] Chablat D., Jha R., and Caro S. A framework for the control of a parallel manipulator with several actuation modes. In *IEEE 14th International Conference on Industrial Informatics (INDIN)*, 2016.

- [chablat2018] Chablat D., Kong X., and Zhang C. Kinematics, workspace, and singularity analysis of a parallel robot with five operation modes. J. of Mechanisms and Robotics, 10, June 2018.
- [chablat2018-1] Chablat D., Ottaviano E., and Venkateswaran S. Self-motion of the  $3 \underline{PPS}$  parallel robot with Delta-shaped base. In *EUCOMES*, pages 317–324, Aachen, September, 4-6, 2018.
- [chablat2018-2] Chablat D. and others . The  $3 \underline{PPPS}$  parallel robot with U-shape base, a 6-dof robot with simple kinematics. In ARK, Bologna, July, 1-5, 2018.
- [chablat2019] Chablat D., Ottaviano E., and Venkateswaran S. Self-motion conditions for a  $3 \underline{PPPS}$  parallel robot with delta-shaped base. *Mechanism and Machine Theory*, 135:109–114, 2019.
- [chablat2021] Chablat D. and others . Workspace analysis in the design parameter space of a 2-dof spherical parallel mechanism for a prescribed workspace: Application to the otologic surgery. *Mechanism and Machine Theory*, 157, 2021.
- [chai-x2012] Chai X. and others. Error modeling and accuracy analysis of a multi-level hybrid support robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 2319–2324, Saint Paul, May, 14-18, 2012.
- [chai-x2020] Chai X. and others . Dynamic modeling and analysis of a 2PRU-UPR parallel robot based on screw theory. *IEEE Access*, 2020.
- [chai-x2020-1] Chai X. and others. Kinematic sensitivity analysis and dimensional synthesis of a redundantly actuated parallel robot for friction stir welding. *Chinese J. of Mechanical Engineering*, 33(1), 2020.
- [chai2001] Chai K-S. and Young K. Designing a Stewart platform-based cooperative system for large component assembly. In *IEEE Int. Conf. on Methods and Models in Automation and Robotics*, Miedzyzdroje, August, 28-31, 2001.
- [chai2002] Chai K-S., Young K., and Tuersley I. A practical calibration process using partial information for a commercial Stewart platform. *Robotica*, 20(3):315–322, 2002.
- [chakarov94] Chakarov D. and Parushev P. Synthesis of parallel manipulator with linear drive modules. *Mechanism and Machine Theory*, 29(7):917–932, October 1994.
- [chakarov99] Chakarov D. Study of the passive compliance of parallel manipulators. *Mechanism and Machine Theory*, 34(3):373–389, April 1999.
- [chakarov2004] Chakarov D. Study of the antagonistic stiffness of parallel manipulators with actuation redundancy. Mechanism and Machine Theory, 39(6):583–601, June 2004.
- [chaker 2012] Chaker A. and others . Clearance and manufacturing errors effects on the accuracy of the 3-RCC spherical parallel manipulators. In *RoManSy*, Paris, June, 12-15, 2012.
- [chaker 2013] Chaker A. and others . Clearance and manufacturing errors effects on the accuracy of the 3-RCC spherical parallel manipulator.  $European\ Journal\ of\ Mechanics\ A/Solids,\ 27:86-95,\ January\ -$  February , 2013.
- [chan-yp2018] Chan Y.P. and others . Improved computational speed of system dynamics for cable-driven robots through generalised model compilation. In *Int. Conf. on Real-time Computing and Robotics*, Kandima, August, 1-5, 2018.
- [chan 2001] Chan V.K. and Ebert-Uphoff I. Investigation of the deficiencies of parallel manipulators in singular configurations through the jacobian nullspace. In *IEEE Int. Conf. on Robotics and Automation*, Seoul, May, 21-26, 2001.
- [chanal2009] Chanal H. and others . Reduction of a parallel kinematics machine tool inverse kinematics model with regard to machining behaviour. *Mechanism and Machine Theory*, 44(7):1371–1385, July 2009.
- [chanal2022] Chanal H. and others . Complete inverse geometric model computation of the Quattro parallel kinematic robot. In ARK, Bilbao, June, 26-30, 2022.
- [chandra2011] Chandra R. and Rolland L. On solving the forward kinematics of 3-RPR planar parallel manipulator using hybrid metaheuristics. *Applied Mathematics and Computation*, 217(17):8997–9008, May 2011.

- [chang-p-2006] Chang P., Li T., and Guan L. Minimal linear combinations of the error parameters for kinematic calibration of parallel kinematic machines. In 5th Chemnitzer Parallelkinematik Seminar, pages 565–583, Chemnitz, April, 25-26, 2006.
- [chang2003] Chang W-T., Lin C-C., and Lee J-J. Force transmissibility performance of parallel manipulators. *J. of Robotic Systems*, 20(11):659–670, 2003.
- [chang-d2013] Chang D. and others. Design of a novel tremor suppression device using a linear Delta manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 413–418, Tokyo, November, 3-7, 2013.
- [charentus88] Charentus S., Diaz C, and Renaud M. Modular serial parallel redundant robot. In *IMACS*, Cetraro, Italie, September, 18-21, 1988.
- [charentus89] Charentus S. and Renaud M. Calcul du modèle géométrique direct de la plate-forme de Stewart. Research Report 89260, LAAS, Toulouse, France, July 1989.
- [charentus90-phd] Charentus S. Modélisation et commande d'un robot manipulateur redondant composé de plusieurs plate-formes. Ph.D. Thesis, Université Paul Sabatier, Toulouse, April, 13, 1990. **Keywords:** kinematics, redundant robot, modular robot.
- [charles95] Charles P.A.S. Octahedral machine tool frame, February, 28, 1995. United States Patent n° 5,392,663 Ingersoll Milling Machine Company. **Keywords:** applications,machine-tool,patent.
- [chawla2021] Chawla I. and others. Effect of selection criterion on the kineto-static solution of a redundant cable-driven parallel robot considering cable mass and elasticity. *Mechanism and Machine Theory*, 156, 2021.
- [chawla2021-1] Chawla I. and others . Neural network-based inverse kineto-static analysis of cable-driven parallel robot considering cable mass and elasticity. In 5th Int. Conf. on cable-driven parallel robots (CableCon), virtual, July, 7-9, 2021.
- [chawla2021-2] Chawla I. and others. Workspace analysis and design of large-scale cable-driven printing robot considering cable mass and mobile platform orientation. *Mechanism and Machine Theory*, 165, 2021.
- [che2020] Che L. and others . Dimensional synthesis for a Rec4 parallel mechanism with maximum transmission workspace. *Mechanism and Machine Theory*, 153, 2020.
- [chebbi2009] Chebbi A-H., Affi Z., and Romdhane L. Kinetostatic and singularity analyses of the 3-UPU translational parallel robot. In *Computational Kinematics*, pages 61–68, Duisburg, May, 6-8, 2009.
- [chebbi2009-1] Chebbi A-H., Affi Z., and Romdhane L. Prediction of the pose errors produced by joints clearance for a 3-UPU parallel robot. *Mechanism and Machine Theory*, 44(9):1768–1783, September 2009.
- [chebbi2010] Chebbi A-H. and Parenti-Castelli V. Geometric and manufacturing issues of the 3-UPU pure translational manipulator. In 3rd European Conf. on Mechanism Science (Eucomes), pages 595–603, Cluj-Napoca, September, 14-17, 2010.
- [chellal2012] Chellal R., Laroche E., Cuvillon L., and Gangloff J. An identification methodology for 6-dof cable-driven parallel robots parameters. Application to the INCA 6D robot. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [chellal2014] Chellal R., Laroche E., and Cuvillon L. An  $H_{\infty}$  methodology for position control of 6-dof cable-driven parallel robots. In *European Control Conference*, Strasbourg, June, 24-27, 2014.
- [chellal2014-1] Chellal R., Cuvillon L., and Laroche E. A kinematic vison-based position control of a 6dof cable-driven parallel robot. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), Duisburg, August, 24-27, 2014.
- [chellal2017] Chellal R., Cuvillon L., and Laroche E. Model identification and vision-based  $H_{\infty}$  position control of 6-dof cable-driven parallel robots. *Int. J. of Control*, 90(4):684–701, 2017.
- [chen-c2012] Chen C. and others . A six degree of freedom epicyclic-parallel manipulator. *J. of Mechanisms and Robotics*, 4(4), November 2012.
- [chen-ct2008] Chen C-T. and Chi H-W. Singularity-free trajectory planning of platform-type parallel manipulators for minimum actuating efforts and reactions. *Robotica*, 26(3):371–384, May 2008.

- [chen-ct2008-1] Chen C-T. and Liao T.T. Optimal path programming of the Stewart platform manipulator using the Boltzmann-Hamel-d'Alembert dynamics formulation model. *Advanced Robotics*, 22(6-7):705–730, 2008.
- [chen-d2018] Chen D., Zhang Y., and Li S. Zeroing neural-dynamics approach and its robust and rapid solution for parallel robot manipulators against superposition of multiple disturbances. *Neurocomputing*, 275:845–858, 2018.
- [chen-g-2015] Chen G. and others . Configuration bifurcation and self-motion analysis of 3-SPS+1PS bionic parallel test platform for hip joint simulator. *Mechanism and Machine Theory*, 86:62–72, 2015.
- [chen-g2013] Chen G. and others . Stiffness analysis of a 3CPS parallel manipulator for mirror active adjusting platform in segmented telescope. *Robotics and Computer-Integrated Manufacturing*, 29(5):302–311, October 2013.
- [chen-g2013-1] Chen G. and Lin Z. A unified approach to the accuracy analysis of planar parallel manipulator both with uncertainties and joint clearance. *Mechanism and Machine Theory*, 64:1–17, June 2013.
- [chen-g2018] Chen G. and others . Complete, minimal and continuous error models for the kinematic calibration of parallel manipulators based on POE formula. *Mechanism and Machine Theory*, 121:844–856, 2018.
- [chen-g2018-1] Chen G. and others . A novel method for the dynamic modeling of Stewart parallel mechanism. Mechanism and Machine Theory, 126:397–412, 2018.
- [chen-g2019] Chen G. and others . A simple two-step geometric approach for the kinematic calibration of the  $3-\underline{P}RS$  parallel manipulator. Robotica, 37:437–450, 2019.
- [chen-g2020] Chen G. and others . Design and validation of a spatial two-limb 3r1t parallel manipulator with remote center-of-motion. *Mechanism and Machine Theory*, 149, 2020.
- [chen-im-2003] Chen I-M. and others . The management of parallel-manipulator singularities using joint-coupling. In *IEEE Int. Conf. on Robotics and Automation*, pages 773–778, Taipei, September, 14-19, 2003.
- [chen-im-2003-1] Chen I-M. and others . Shaping singularity loci of parallel manipulators using joint-coupling. In *Int. Conf. on Automation Technology*, Taipei, September, 12-14, 2003.
- [chen-im2001] Chen I-M. and others . Self-calibration of three-legged modular reconfigurable parallel robots based on measurement residues. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 117–132. EJCK, May, 20-22, 2001. **Keywords:** calibration.
- [chen-q2013] Chen Q. and others . An integrated two-level self-calibration method for cable-driven manipulator. IEEE Trans. on Robotics, 10(2):380-391, March 2004.
- [chen-q2019] Chen Q. and others . Design and development of a new cable-driven parallel robot for waist rehabilitation.  $IEEE/ASME\ Trans.\ on\ Mechatronics,\ 24(2),\ August\ 2019.$
- [chen-sh2008] Chen S-M., Huang C.I., and Fu L-C. Applying a non linear observer to solve forward kinematics of a Stewart platform. In 17th IEEE Int. Conf. on Control Applications, pages 1183–1188, San Antonio, September, 3-5, 2008.
- [chen-t2017] Chen T. and others . Mechanism design and analysis for an automatical reconfiguration cable-driven parallel robot. In 2nd International Conference on Cybernetics, Robotics and Control, 2017.
- [chen-wj-2001] Chen W-J. and others . A novel 4-dof parallel manipulator and its kinematic modelling. In *IEEE Int. Conf. on Robotics and Automation*, pages 3350–3355, Seoul, May, 23-25, 2001.
- [chen-wj-2002] Chen W-J. and others . A 2T-2R, 4-dof parallel manipulator. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [chen-ws-2008] Chen W-S. and Chen J-K., H.and Liu. Extreme configuration bifurcation analysis and link safety length of Stewart platform. *Mechanism and Machine Theory*, 43(5):617–626, May 2008.
- [chen-x-2002] Chen X. and others . Workspace generation of the 3-PRS parallel robot based on the NN. In 1st Int. Conf. on Machine Learning and Cybernetics, pages 2087–2089, Beijing, November, 4-5, 2002.

- [chen-x-2004] Chen X. and others . Study on kinematic characteristics and singularities of 3-dof parallel robot. In 3rd Int. Conf. on Machine Learning and Cybernetics, pages 2870–2873, Shangai, August, 26-29, 2004.
- [chen-y-2000] Chen Y. and McInroy J.E. Identification and decoupling control of flexure jointed hexapods. In *IEEE Int. Conf. on Robotics and Automation*, pages 1936–1941, San Francisco, April, 24-28, 2000.
- [chen-y-2003] Chen Y., McInroy J.E., and Yi Y. Optimal, fault-tolerant mappings to achieve secondary goals without compromising primary performance. *IEEE Trans. on Robotics and Automation*, 19(4):681–691, August 2003.
- [chen-y-2003-1] Chen Y. and McInroy J.E. A task space redundancy-based scheme for motion planning. In *American Control Conf.*, pages 3435–3445, Denver, June, 4-6, 2003.
- [chen-y-2004] Chen Y. and McInroy J.E. Decoupled control of flexure-jointed hexapods using estimated joint-space mass-inertia matrix. *IEEE Trans. on Control Systems Technology*, 12(3):413–421, May 2004.
- [chen-y-2024] Chen Y. and others. Error modeling and analysis of a spherical parallel mechanism with a multiloop circuit incremental method. *Mechanism and Machine Theory*, 191, 2024.
- [chen-yc-94] Chen Y-C. and Walker I.D. A consistent approach to the instantaneous kinematics of redundant, non-redundant and in-parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2172–2178, San Diego, May, 8-13, 1994.
- [chen-z2020] Chen Z. and others . Kinematics analysis of a novel 2R1T 3-PUU parallel mechanism with multiple rotation centers. *Mechanism and Machine Theory*, 152, 2020.
- [chen92] Chen N.X. and Song S-M. Direct position analysis of the 4-6 Stewart platform. In 22nd Biennial Mechanisms Conf., pages 75–80, Scottsdale, September, 13-16, 1992.
- [chen94] Chen N.X. and Song S-M. Direct position analysis of the 4-6 Stewart platform. ASME J. of Mechanical Design, 116(1):61–66, March 1994.
- [cheng-c2016] Cheng C., Xu W., and Shang J. Distributed-torque-based independent joint tracking control of a redundantly actuated parallel robot with two higher kinematic pairs. *IEEE Trans. on Industrial Electronics*, 63(2), February 2016.
- [cheng-c2020] Cheng C., Huang W., and Zhang C. Design and development of a novel 2-degree-of-freedom parallel robot. *Robotica*, 38:1–14, 2020.
- [cheng-g-2013] Cheng G. and otehrs . Stiffness analysis of the 3-SPS+1PS bionic parallel test platform for a hip joint simulator. *Robotica*, 31(6):936–944, September 2013.
- [cheng-g-2019] Cheng G. and otehrs . A simple two-step geometric approach for the kinematic calibration of the 3-PRS parallel manipulator. *Robotica*, 37:837–850, 2019.
- [cheng-j-2007] Cheng J. Research on the operating characteristics of parallel 4-dof electric platform with 4 TPS-PS structure. J. of Zheijang University Science A, 8(11):1800–1807, 2007.
- [cheng-y-2003] Cheng Y., Ren G., and Dai S. Vibration control of Gough-Stewart platform on flexible suspension. *IEEE Trans. on Robotics and Automation*, 19(3):489–493, June 2003.
- [cheng94] Cheng H.H. Real-time manipulation of a hybrid serial-and-parallel driven redundant industrial manipulator.  $ASME\ J.\ of\ Dynamic\ Systems,\ Measurement\ and\ Control,\ 116(4):687–701,\ December\ 1994.$
- [chen-jl2013] Chen J-L. and others. Using UWB sensor for Delta robot vibration detection. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 419–423, Tokyo, November, 3-7, 2013.
- [cheok93] Cheok Ka.C., Overholt J.L., and Beck R.R. Exact methods for determining the kinematics of a Stewart platform using additional displacement sensors. *J. of Robotic Systems*, 10(5):689–707, July 1993.
- [chetelat96] Chételat O., Myszkorowski P., Longchamp R., and Merlet J-P. Algorithme itératif à convergence démontrée pour les changements de coordonnées des mécanismes articulés. Research Report 1996-07, EPFL, Institut d'Automatique, Lausanne, Suisse, November 1996.

- [chetelat97] Chételat O., Merlet J-P., Myszkorowski P., and Longchamp R. Globally convergent iterative algorithms for the coordinate transformations in the articulated mechanisms. In *Syroco*, Nantes, September 1997.
- [chetelat97-phd] Chételat O. Algorithme numérique pour les changements de coordonnées des mécanismes articulés. Ph.D. Thesis, EPFL, Lausanne, October, 20, 1997. **Keywords:** forward kinematics.
- [chettibi2005] Chettibi T. and iothers . Generating optimal dynamic motions for closed-chain robotic systems. European Journal of Mechanics A/Solids, 24:504–518, 2005.
- [chiacchio93] Chiacchio P., Pierrot F., Sciavicco L., and Siciliano B. Robust design of independant joint controlers with experimentation on a high-speed parallel robot. *IEEE Trans. on Industrial Electronics*, 40(4):393–403, August 1993.
- [chianura-phd2018] Chianura M. Vision-based enhancement of the pose accuracy of a redundantly actuated cable-driven parallel robot. Ph.D. Thesis, University Bologna, 2018. **Keywords:** wire robot, accuracy, forward kinematics with redundant sensors.
- [chikh2010] Chikh L. and others . A mixed GPC- $H_{\infty}$  robust cascade position-pressure control strategy for electrop-neumatic cylinders. In *IEEE Int. Conf. on Robotics and Automation*, pages 5147–5154, Anchorage, May, 3-8, 2010.
- [chirikjian94] Chirikjian G.S. A binary paradigm for robotic manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 3063–3070, San Diego, May, 8-13, 1994.
- [chirikjian95] Chirikjian G.S. Hyper-redundant manipulator dynamics: a continuum approximation. Advanced Robotics, 9(3):217–243, 1995.
- [chirikjian96] Chirikjian G.S. Group theoretical synthesis of binary manipulators. In 11th RoManSy, pages 107–114, Udine, July, 1-4, 1996.
- [chirikjian2000] Chirikjian G.S. Symmetries in workspace densities of discretely actuated manipulators. In ARK, pages 259–266, Piran, June, 25-29, 2000.
- [chiu2001] Chiu Y.J. and Perng M-H. Forward kinematics of a general fully parallel manipulator with auxiliary sensors. *Int. J. of Robotics Research*, 20(5):401–414, May 2001.
- [chiu2002] Chiu Y.J. and Perng M-H. Total self-calibration of a general hexapod manipulator. In 3rd Chemnitzer Parallelkinematik Seminar, pages 469–490, Chemnitz, April, 23-25, 2002.
- [chiu2004] Chiu Y.J. and Perng M-H. Self-calibration of a general hexapod manipulator with enhanced precision in 5-dof motions. *Mechanism and Machine Theory*, 39(1):1–23, January 2004.
- [choi-hs-2005] Choi H-S.. and others . Development of hybrid robot for construction works with pneumatic actuator. *Automation in Construction*, 14(4):452–459, August 2005.
- [choi-jh2014] Choi J-H., Seo T.W., and Lee J.W. Torque distribution optimization of redundantly actuated planar parallel mechanisms based on a null-space solution. *Robotica*, 32(7):1125–1134, October 2014.
- [choi-jk-2004] Choi J-K., Omata T., and Mori O. Self-reconfigurable planar parallel robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2654–2660, Sendai, September 28- October 2, 2004.
- [choi-jk-2004-1] Choi J-K. and others . Self-reconfigurable planar parallel robot in the horizontal plane. *Advanced Robotics*, 18(1):45–60, 2004.
- [choi-k-2002] Choi K., Jiang S., and Li Z. Spatial stiffness realization with parallel springs using geometric parameters. *IEEE Trans. on Robotics and Automation*, 18(3):274–284, June 2002.
- [choi-sh-2017] Choi S-H. and others . The integrated elasto-plastic cable modeling for cable driven parallel robots (CDPRs). In *ICCAS*, Jeju, October, 18-21, 2017.
- [choi2003] Choi H.B. and others . Design and control of a novel 4-dofs parallel robot H4. In *IEEE Int. Conf. on Robotics and Automation*, pages 1185–1190, Taipei, September, 14-19, 2003.

- [choi2010] Choi H.B., Konno A., and Uchiyama M. Design, implementation and performance evaluation of a 4-dof parallel robot. *Robotica*, 28(1):107–118, January 2010.
- [choi2010-1] Choi H.B., Konno A., and Uchiyama M. Inverse dynamics analysis of a 4-d.o.f. parallel robot H4. *Advanced Robotics*, 24(1-2):159–177, 2010.
- [choi2012] Choi H.B. and Ryu J. Convex hull-based power manipulability analysis of robot manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 2972–2977, Saint Paul, May, 14-18, 2012.
- [chong2020] Chong Z. and others. Design of the parallel mechanism for a hybrid mobile robot in wind turbine blades polishing. *Robotics and Computer-Integrated Manufacturing*, 61, February 2020.
- [chouabi2016] Chouabi Y. and others . Analytical modeling and analysis of the clearance induced orientation error of the RAF translational parallel manipulator. *Robotica*, 34(8):1898–1921, August 2016.
- [choudhury 2000] Choudhury P. and Ghosal A. Singularity and controllability analysis of parallel manipulators and closed-loop mechanisms. *Mechanism and Machine Theory*, 35(10):1455–1479, October 2000.
- [chuang2000] Chuang H-Y. and Chang Y-C. A novel contour error compensator for 3-PRPS platform. *J. of Robotic Systems*, 17(5):273–289, 2000.
- [chung-gb-2001] Chung G.B. and others . Design and analysis of a spatial 3-dof micromanipulator for tele-operation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 337–342, Maui, Hawaii, October 29-November 3, 2001.
- [chung-j2010] Chung J. and others . Implementation of a 4-dof parallel mechanism as a needle insertion device. In *IEEE Int. Conf. on Robotics and Automation*, pages 662–668, Anchorage, May, 3-8, 2010.
- [chung-jh-2007] Chung J-H., Yi B-J., and Oh S. Design of a new spatial 3-dof parallel mechanism with application to a PDP TV mounting device. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3999–4006, San Diego, September, 22-26, 2007.
- [chung2001] Chung Y-H., Choo J-H, and Lee J-W. Sensation: a new 2 dof parallel mechanism for haptic device. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 45–56. EJCK, May, 20-22, 2001. **Keywords:** 2 dof robot, haptic device.
- [chung2002] Chung Y-H., Choo J-H, and Lee J-W. The effect of actuator relocation on singularity, jacobian and kinematic isotropy of parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2147–2153, Lausanne. October 2002.
- [cirillo2017] Cirillo P., Natale C., Cirillo A., and Marino A. Optimal custom design of both symmetric and unsymmetrical hexapod robots for aeronautics applications. *Robotics and Computer-Integrated Manufacturing*, 44:1–16, April 2017.
- [cisneroslimon2015] Cisneros-Limon R. and others . Workspace analysis of a 6-RSS parallel robot considering non-ideal spherical joints. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, September 28- October 2, 2015.
- [claudinon85] Claudinon B. and Lievre J. Test facility for rendez-vous and docking. In 36th Congress of the IAF, pages 1–6, Stockholm, October, 7-12, 1985.
- [clavel88] Clavel R. DELTA, a fast robot with parallel geometry. In 18th Int. Symp. on Industrial Robots (ISIR), pages 91–100, Lausanne, April, 26-28, 1988.
- [clavel89-1] Clavel R. Une nouvelle structure de manipulateur parallèle pour la robotique légère. APII, 23(6):501–519, 1989.
- [clavel90] Clavel R. Device for the movement and positioning of an element in space, December, 11, 1990. United States Patent n° 4,976,582, Sogeva S.A. **Keywords:** mechanical architecture, patent.
- [clavel91] Clavel R. Conception d'un robot parallèle rapide à 4 degrés de liberté. Ph.D. Thesis, EPFL, Lausanne, 1991. n° 925. **Keywords:** mechanical architecture, kinematics, singularity, 4 dof robot, workspace, kinetics, hardware.

- [clavel94] Clavel R. Robots parallèles, 1994. Techniques de l'Ingénieur, Traité Mesures et Contrôle. **Keywords:** state of the art, applications.
- [clavel2002] Clavel R. and others . A new parallel kinematics able to machine 5 sides of a cube-shaped object: Hita STT. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 107–118, Braunschweig, May, 29-30, 2002.
- [clavel2002-1] Clavel R. and others . A new 5 dof parallel kinematics for production applications. In *Int. Symp. on Robotics*, Stockolm, October, 9-11, 2002.
- [clavel2005] Clavel R. and others. High precision parallel robots for micro-factory applications. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 285–296, Braunschweig, May, 10-11, 2005.
- [cleary91] Cleary K. and Arai T. A prototype parallel manipulator: kinematics construction, software, workspace results and singularity analysis. In *IEEE Int. Conf. on Robotics and Automation*, pages 566–571, Sacramento, April, 11-14, 1991.
- [cleary93] Cleary K. and Brooks T. Kinematic analysis of a novel 6-dof parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 708–713, Atlanta, May, 2-6, 1993.
- [cleroux96] Cléroux L. and Gosselin C. Modeling and identification of non-geometric parameters in semi-flexible parallel robots. In 6th ISRAM, pages 115–120, Montpellier, May, 28-30, 1996.
- [cobet2002] Cobet M. Designing PKMs: working volume, stiffness, frequencies. In 3rd Chemnitzer Parallelkinematik Seminar, pages 83–103, Chemnitz, April, 23-25, 2002.
- [codourey91] Codourey A. Contribution à la commande des robots rapides et précis. Application au robot Delta à entrainement direct. Ph.D. Thesis, EPFL, Lausanne, 1991. n° 922. **Keywords:** hardware,dynamics,control,inverse kinematics,parallel computation.
- [codourey91-1] Codourey A. Control algorithm and controller for the direct drive Delta robot. In 3rd IFAC/IFIP/IMACS Symp. on Robot Control, Syroco, Vienne, September, 16-18, 1991.
- [codourey97] Codourey A. and Burdet E. A body oriented method for finding a linear form of the dynamic equations of fully parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 1612–1618, Albuquerque, April, 21-28, 1997.
- [colbaugh93] Colbaugh R., Glass K., and Seraji H. Direct adaptive control of robotics systems. In *American Control Conf.*, pages 1138–1143, San Francisco, June, 2-4, 1993.
- [collard2005] Collard J-F., Fisette P., and Duysinx P. Contribution to the optimization of closed-loop multibody systems: application to parallel manipulators. *Multibody System Dynamics*, 13:69–84, 2005.
- [collins95] Collins C.L. and Long G.L. On the duality of twist/wrench in serial and parallel chain robot manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 526–531, Nagoya, May, 25-27, 1995.
- [collins95-1] Collins C.L. and Long G.L. The singularity analysis of an in-parallel hand controller for force-reflected teleoperation. *IEEE Trans. on Robotics and Automation*, 11(5):661–669, October 1995.
- [collins98] Collins C.L. and McCarthy J.M. The quartic singularity surfaces of planar platforms in the Clifford algebra of the projective plane. *Mechanism and Machine Theory*, 33(7):931–944, October 1998.
- [collins2002] Collins C.L. Forward kinematics of planar parallel manipulators in the Clifford algebra of P<sup>2</sup>. Mechanism and Machine Theory, 37(8):799–813, August 2002.
- [comin95] Comin F. Six degree-of-freedom scanning supports and manipulators based on parallel robots. Review of Scientific Instruments, 66(2):1665–1667, February 1995.
- [company99] Company O. and Pierrot F. A new 3T-1R parallel robot. In *ICAR*, pages 557–562, Tokyo, November 1999.
- [company2000-phd] Company O. Machines-outils rapides à structure parallèle. Méthodologie de conception, applications et nouveaux concepts. Ph.D. Thesis, Université Montpellier II, Montpellier, December, 5, 2000. **Keywords:** mechanical architecture, machine-tool.

- [company2002] Company O. and Pierrot F. Modelling and design issues of a 3-axis parallel machine-tool. *Mechanism and Machine Theory*, 37(11):1325–1345, November 2002.
- [company2003] Company O., Marquet F., and Pierrot F. A new high speed 4-dof parallel robot. Synthesis and modeling issues. *IEEE Trans. on Robotics and Automation*, 19(3):411–420, June 2003.
- [company2005] Company O., Pierrot F., and Fauroux J-C. A method for modeling analytical stiffness of a lower mobility parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3243–3248, Barcelona, April, 19-22, 2005.
- [company2007] Company O., , Krut S., and Pierrot F. Analysis of a high resolution planar PKM. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [cone85] Cone L.L. Skycam: an aerial robotic camera system. Byte, 10(10), 1985.
- [cong2008] Cong S. and others. Parallel manipulators, New Developments, chapter Kinematic parameters auto-calibration of redundant planar 2-dof parallel manipulator, pages 241–268. ITECH, April 2008. **Keywords:** calibration, redundant robot, 2 dof robot, planar robot.
- [constantinescu2000] D. Constantinescu and others . Haptic rendering of planar rigid-body motion using a redundant parallel mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 2440–2445, San Francisco, April, 24-28, 2000.
- [conti98] Conti J.P. and others . Workspace variation of a a hexapod machine-tool. Research Report 6135, NIST, Gaitherburg, March 1998.
- [coppola2014] Coppola G., Zhang D., and Liu K. A 6-dof reconfigurable hybrid parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 30:99–106, 2014.
- [corbel2008] Corbel D., Company O., and Pierrot F. Optimal design of a 6-dof parallel measurement mechanism integrated in a 3-dof parallel machine-tool. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1970–1976, Nice, France, September, 22-26, 2008.
- [corbel2010] Corbel D. and others. Towards 100G with PKM. is actuation redundancy a good solution for pick-and-place? In *IEEE Int. Conf. on Robotics and Automation*, pages 4675–4682, Anchorage, May, 3-8, 2010.
- [corinaldi2018] Corinaldi D. and others . Rotational mobility analysis of the 3-RFR class of spherical parallel robot. In ARK, Bologna, July, 1-5, 2018.
- [coronado2017] Coronado L.E. and others . Vision-based control of a Delta parallel robot via linear camera-space manipulation. *J. of Intelligent and Robotic Systems*, 85:93–106, 2017.
- [corradini2004] Corradini C. and others . Evaluation of a 4-degree of freedom parallel manipulator stiffness. In 11th IFToMM World Congress on the Theory of Machines and Mechanisms, Tianjin, April, 1-4, 2004.
- [corral2010] Corral J. and others . Structural dynamic analysis of low-mobility parallel manipulators. In 3rd European Conf. on Mechanism Science (Eucomes), pages 387–394, Cluj-Napoca, September, 14-17, 2010.
- [corral2012] Corral J. and others . Dynamic capabilities of a parallel robot based routing machine. In ARK, pages 165–172, Innsbruck, June, 25-28, 2012.
- [corrigan94] Corrigan T.R.J. and Dubowsky S. Emulating micro-gravity in laboratory studies of space robotics. In ASME Design Automation Technical Conference, pages 109–116, Minneapolis, September, 11-14, 1994.
- [cortes-2003-phd] Cortés J. Motion planning algorithms for general closed-chain mechanisms. Ph.D. Thesis, Institut National Polytechnique de Toulouse, Toulouse, December, 16, 2003. **Keywords:** trajectory planning.
- [cortes2002] Cortés J., Siméon T., and Laumond J-P. A random loop generator for planning the motions of closed kinematic chains using PRM methods. In *IEEE Int. Conf. on Robotics and Automation*, pages 2141–2146, Washington, May, 11-15, 2002.
- [cortes2003] Cortés J. and Siméon T. Probabilistic motion planning for parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 4354–4359, Taipei, September, 14-19, 2003.

- [costanza2016] Costanza A.D. and others . Parallel force/position control of an epicardial parallel wire robot. *IEEE Robotics and Automation Letters*, 1(2), 2016.
- [coste2012] Coste M. Asymptotic singularities of planar parallel 3-RPR manipulators. In ARK, pages 35–42, Innsbruck, June, 25-28, 2012.
- [coste2012-1] Coste M., Chablat D., and Wenger P. Perturbation of symmetric  $3 R\underline{P}R$  manipulators and asymptotic singularities. In 4th European Conf. on Mechanism Science (Eucomes), pages 23–32, Santander, September, 19-21, 2012.
- [coste2014] Coste M., Chablat D., and Wenger P. Non singular change of assembly mode without any cusp. In ARK, pages 105–112, Ljulbjana, June 29- July 3, 2014.
- [coste2015] Coste M. and Moussa S. On the rationality of the singularity locus of a Gough–Stewart platform biplanar case. *Mechanism and Machine Theory*, 87:82–92, 2015.
- [coulombe2013] Coulombe J. and Bonev I.A. A new rotary hexapod for micropositioning. In *IEEE Int. Conf. on Robotics and Automation*, pages 877–880, Karlsruhe, May, 6-10, 2013.
- [cox89] Cox D.J. and Tesar D. The dynamic model of a three-degree-of-freedom parallel robotic shoulder module. In 4th ICAR, pages 475–487, Colombus, Ohio, June, 13-15, 1989.
- [crapo73] Crapo H. A combinatorial perspective on algebraic geometry. In *Colloquio Int. sulle Teorie Combinatorie*, Rome, September, 3-15, 1973.
- [craver89] Craver W.M. Structural analysis and design of a three-degree-of-freedom robotic shoulder module. Master's thesis, The University of Texas, Austin, 1989. **Keywords:** spherical robot, mechanical architecture, 3 dof robot.
- [cruzruiz2014] Cruz Ruiz A.L. and others . ARACHNIS: analysis of robots actuated by cables with handy and neat interface software. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 293–306, Duisburg, August, 24-27, 2014.
- [cuan-urquizo2013] Cuan-Urquizo E. and Rodriguez-Lea E. Kinematic analysis of the 3-CUP parallel mechanism. Robotics and Computer-Integrated Manufacturing, 29(5):382–395, October 2013.
- [cuan2013] Cuan-Urquizo E. and Rodrigrez-Leal E. Kinematic analysis of the 3-CUP parallel mechanism. *Robotics* and Computer-Integrated Manufacturing, 29(5):382–395. October 2013.
- [cuevas2017] Cuevas J.I.A.., Laroche E., and Piccin O. Assumed-mode-based dynamic model for cable robots with non-straight cables. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [cui-x2014] Cui X. and others . A novel customized cable-driven robot for 3-dof wrist and forearm motion training. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Chicago, September, 14-18, 2014.
- [cui2005] Cui H. and others . Kinematic analysis and error modeling of TAU parallel robot. *Robotics and Computer-Integrated Manufacturing*, 21(6):497–505, December 2005.
- [cui2007] Cui H. and Zhu Z. *Industrial Robotics, Theory, Modelling and Control*, chapter Error modeling and accuracy of parallel industrial robots, pages 573–646. pro literatur Verlag, January 2007. **Keywords:** accuracy, design.
- [cui2008] Cui H. and others . *Parallel manipulators, New Developments*, chapter Error modeling and accuracy of TAU robot, pages 269–282. ITECH, April 2008. **Keywords:** accuracy, jacobian.
- [culla2018] Culla D. and others . Full production plant automation in industry using cable robotics with high load capacities and position accuracy. In ROBOT 2017: Third Iberian Robotics Conference, 2018.
- [culpepper 2002] Culpepper M.L., Anderson G., and Petri P. Hexflex: a planar mechanism for six-axis manipulation and alignment. In ASPE 17th Annual Meeting, St Louis, October, 20-25, 2002.
- [culpepper 2002-1] Culpepper M.L., Araque C., and Rodriguez M. Design of accurate and repeatable kinematic couplings. In ASPE 17th Annual Meeting, St Louis, October, 20-25, 2002.
- [culpepper 2003] Culpepper M.L. and Chen S-C. Design of precision manipulator using binary actuation and differential compliant mechanisms. In ASPE 18th Annual Meeting, Portland, October, 26-31, 2003.

- [culpepper 2004] Culpepper M.L. and Anderson G. Design of a low-cost nano-manipulator which utilizes a monolithic, spatial compliant mechanism. *Journal of Precision Engineering*, 28(4):469–482, October 2004.
- [culpepper2004-1] Culpepper M.L. and Kim S. A framework and design synthesis tool used to generate and evaluate and optimize compliant mechanism concepts for research and education activities. In *ASME Design Engineering Technical Conference*, Salt Lake City, September 28- October 2, 2004.
- [culpepper 2005] Culpepper M.L., Kartik M.V., and DiBiasio C. Design of integrated mechanisms and exact constraint fixtures for micron-level repeatability and accuracy. *Journal of Precision Engineering*, 29(1):65–80, January 2005.
- [cunningham2009] Cunninghamm D. and Asada H.H. The Winch-Bot: a cable-suspended under-actuated robot utilizing parametric self-excitation. In *IEEE Int. Conf. on Robotics and Automation*, pages 1844–1850, Kobe, May, 14-16, 2009.
- [cunningham2010] Cunninghamm D. and Asada H.H. Continuous path tracing by a cable-suspended, under-actuated robot; the Winch-Bot. In *IEEE Int. Conf. on Robotics and Automation*, pages 1255–1260, Anchorage, May, 3-8, 2010.
- [cuvillon2020] Cuvillon L., Weber X., and Gangloff J. Modal control for active vibration damping of cable-driven parallel robots. J. of Mechanisms and Robotics, 12(5), October 2020.
- [cvetanovic2014] Cvetanovic C. and Laroche E. Towards DAE methodology for the control of cable-driven parallel robots. In *IEEE Int. Conf. on Control Applications*, Antibes, October, 8-10, 2014.
- [czapalay2019] Czapalay E. and others . Wrench analysis of cable-suspended parallel robots actuated by quadrotors UAVs. J. of Mechanisms and Robotics, 11(2), 2019.
- [czwielong2002] Czwielong T. and Zarske W. Pegasus: incorporating PKM into woodworking. In 2nd NCG Application Conf. on Parallel Kinematics Machine, pages 843–856, Chemnitz, April, 23-25, 2002.
- [dadarlat2012] Dadarlat R. and others. Workspace and singularity point analysis of a 6-dof parallel mechanism with two kinematic chains for platform guidance. In 4th European Conf. on Mechanism Science (Eucomes), pages 33–41, Santander, September, 19-21, 2012.
- [dafaoui94] Dafaoui M., Amirat Y., Pontnau J., and Francois C. Manipulateur parallèle à six degrés de liberté: modèles et volume de travail. Revue d'Automatique et de Productique Appliquée, 7(2):195–220, 1994.
- [dafaoui98] Dafaoui M., Amirat Y., Pontnau J., and Francois C. Analysis and design of a six-dof parallel manipulator, modeling, singular configurations and workspace. *IEEE Trans. on Robotics and Automation*, 14(1):78–92, February 1998.
- [dagalakis89] Dagalakis N.G. and others . Robot Crane Technology (final report). Research Report 1267, NIST, July 1989.
- [dagalakis89-1] Dagalakis N.G. and others . Stiffness study of a parallel link robot crane for shipbuilding applications. J. of Offshore Mechanics and Arctic Engineering, 111(3):183–193, August 1989.
- [dagalakis2001] Dagalakis N.G. and Amatucci F. Kinematic modeling of a 6 degree-of-freedom tri-stage micropositionner. In ASPE 16th Annual Meeting, Cristal City, November, 10-15, 2001.
- [dahmouche2010] Dahmouche R. and others . Efficient high-speed vision-based computed torque control of the Orthoglide parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 644–649, Anchorage, May, 3-8, 2010.
- [dahmouche2020] Dahmouche R., Wen K., and Gosselin C. Transferability in an 8-dof parallel robot with a configurable platform. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October, 25-29, 2020.
- [dai-h2019] Dai H., Izan G., and Tedrake R. Global inverse kinematics via mixed-integer convex optimization. *Int. J. of Robotics Research*, 38(12-13):1420–1441, 2019.
- [dai-hs2004] Dai H.S., Zhao T., and Nester C. Sprained ankle physiotherapy based mechanism synthesis and stiffness analysis of a robotic rehabilitation device. *Autonomous Robots*, 16(1):207–218, July 2004.

- [dai2006] Dai J.S. and Ding X. Compliance analysis of a three-legged rigidly-connected platform device. ASME J. of Mechanical Design, 128(4):755–764, July 2006.
- [dallalibera2014] Dallalibera F. and Ishiguro H. Non-singular transitions between assembly modes of 2-dof planar parallel manipulators with a passive leg. *Mechanism and Machine Theory*, 77:182–197, 2014.
- [dallefrate 2002] Dallefrate D. and others . A feed rate optimization technique for high-speed CNC machining with parallel manipulators. In 3rd Chemnitzer Parallelkinematik Seminar, pages 371–388, Chemnitz, April, 23-25, 2002.
- [dallej2006-1] Dallej T., Andreff N., and Martinet P. 3d pose visual servoing relieves parallel robotcontrol from joint sensing. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Beijing, October, 9-15, 2006.
- [dallej2006] Dallej T., Andreff N., and Martinet P. Kinematic calibration of a Gough-Stewart platform using an omnidirectional camera. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Beijing, October, 9-15, 2006.
- [dallej2007] Dallej T., Andreff N., and Martinet P. Toward a generic kinematic model for vision-based control of parallel kinematic machines. In 2nd Int. Congress, Design and Modelling of mechanical systems, Monastir, March, 19-21, 2007.
- [dallej2007-1] Dallej T., Andreff N., and Martinet P. Image-based visual servoing of the I4R parallel robot without proprioceptive sensors. In *IEEE Int. Conf. on Robotics and Automation*, pages 1709–1714, Roma, April, 10-14, 2007.
- [dallej2007-2] Dallej T., Andreff N., and Martinet P. Towards a generic image-based visual servoing of parallel robots using legs observation. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [dallej2011] Dallej T. and others. Towards vision-based control of cable-driven parallel robots. In *IEEE Int. Conf.* on *Intelligent Robots and Systems (IROS)*, San-Francisco, September, 25-30, 2011.
- [dallej2012] Dallej T. and others . Vision-based modeling and control of large dimension cable-driven parallel robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1581–1586, Vilamoura, October, 7-12, 2012.
- [dallej2018] Dallej T., Andreff N., and Martinet P. Contribution to generic modeling and vision-based control of a broad class of fully parallel robots. *Robotica*, 36:1874–1896, 2018.
- [dalvand2012] Dalvand M.M. and Shirinzadeh B. Remote centre-of-motion control algorithms of 6-RRCRR parallel robot assisted surgery system. In *IEEE Int. Conf. on Robotics and Automation*, pages 3401–3406, Saint Paul, May, 14-18, 2012.
- [dandurand84] Dandurand A. The rigidity of compound spatial grid. Structural Topology 10, pages 43–55, 1984.
- [danescu94] Danescu G. and Dahan M. to be checked, January, 3, 1994. Prol'egomènes n° 6 (INRIA). **Keywords:** forward kinematics.
- [danescu94-1] Danescu G., Jacquet P., and Dahan M. A method for the design of parallel structures. In 2nd Japan-France Congress on Mechatronics, pages 671–674, Takamatsu, November, 1-3, 1994.
- [danescu94-2] Danescu G., Jacquet P., and Dahan M. A solution for the spatial mechanism design. In *IASTED Int. Conf.*, Applied Modeling and Simulation, Lugano, June, 20-22, 1994.
- [danescu95] Danescu G. Une méthode algébrique de synthèse et conception de mécanismes articulés. Ph.D. Thesis, Université de Franche-Comté, Besançon, June, 22, 1995. **Keywords:** design theory, structural synthesis.
- [daney98] Daney D. Mobility constraints on the legs of a parallel robot to improve the kinematic calibration. In New machine concepts for handling and manufacturing devices on the basis of parallel structures, pages 187–200, Braunschweig, November, 10-11, 1998.
- [daney99] Daney D. Self calibration of Gough platform using leg mobility constraints. In 10th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 104–109, Oulu, June, 20-24, 1999.

- [daney2000-phd] Daney D. Etalonnage géométrique des robots parallèles. Ph.D. Thesis, Université de Nice, Nice, February, 2, 2000. **Keywords:** calibration.
- [daney2001] Daney D. and Emiris I.Z. Variable elimination for reliable parallel robot calibration. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 133–144. EJCK, May, 20-22, 2001. **Keywords:** calibration.
- [daney2001-1] Daney D. and Emiris I.Z. Robust parallel robot calibration with partial information. In *IEEE Int. Conf. on Robotics and Automation*, pages 3262–3267, Seoul, May, 23-25, 2001.
- [daney2002] Daney D. Optimal measurement configurations for Gough platform calibration. In *IEEE Int. Conf. on Robotics and Automation*, pages 147–152, Washington, May, 11-15, 2002.
- [daney2003] Daney D. Kinematic calibration of the Gough platform. Robotica, 21(6):677–690, December 2003.
- [daney2004] Daney D., Papegay Y., and Neumaier A. Interval methods for certification of the kinematic calibration of parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 1913–1918, New Orleans, April, 28-30, 2004.
- [daney2004-1] Daney D. and Emiris I.Z. Algebraic elimination for parallel robot calibration. In 11th IFToMM World Congress on the Theory of Machines and Mechanisms, Tianjin, April, 1-4, 2004.
- [daney2005] Daney D., Andreff N., and Papegay Y. Interval method for calibration of parallel robots: a vision-based experimentation. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [daney2005-1] Daney D., Papegay Y., and Madeline B. Choosing measurement poses for robot calibration with the local convergence method and Tabu search. *Int. J. of Robotics Research*, 24(6):501–518, June 2005.
- [daney2006] Daney D. and others. Calibration of parallel robots: on the elimination of pose-dependent parameters. In 1st European Conf. on Mechanism Science (Eucomes), Obergurgl, February, 21-26, 2006.
- [daney2006-1] Daney D., Andreff N., Chabert G., and Papegay Y. Interval method for calibration of parallel robots: a vision-based experimentation. *Mechanism and Machine Theory*, 41(8):929–944, August 2006.
- [daney2016-h] Daney D. De l'amélioration des performances des robots manipulateurs, June, 20, 2016. Habilitation à diriger les recherches, Université de Nice. **Keywords:** calibration.
- [dangella2011] D'Angella S. and others . Modeling and control of a parallel robot for needle surgery. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [daniali93] Daniali H.R.M., Zsombor-Murray P.J., and Angeles J. The kinematics of a 3 d.o.f. planar and spherical double-triangular parallel manipulators. In J. Angeles P. Kovacs, G. Hommel, editor, *Computational Kinematics*, pages 153–164. Kluwer, 1993. **Keywords:** forward kinematics.
- [daniali95] Daniali H.R.M., Zsombor-Murray P.J., and Angeles J. Singularity analysis of a general class of planar parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1547–1552, Nagoya, May, 25-27, 1995.
- [daniel93] Daniel R.W., Fischer P.J., and Hunter B. A high performance parallel input device. In SPIE, Telemanipulator Technology and Space Telerobotics, pages 272–281, Boston, September, 3-9, 1993.
- [daniel2006] Daniel R. and Dunlop R. A geometrical interpretation of 3-3 mechanism singularity. In ARK, pages 285–294, Ljubljana, June, 26-29, 2006.
- [dasgupta94] Dasgupta B. and Mruthyunjaya T.S. A canonical formulation of the direct position kinematics for a general 6-6 Stewart platform. *Mechanism and Machine Theory*, 29(6):819–827, August 1994.
- [dasgupta96] Dasgupta B. and Mruthyunjaya T.S. A constructive predictor-corrector algorithm for the direct position kinematic problem for a general 6-6 Stewart platform. *Mechanism and Machine Theory*, 31(6):799–811, August 1996.
- [dasgupta98] Dasgupta B. and Mruthyunjaya T.S. Singularity-free path planning for the Stewart platform manipulator. *Mechanism and Machine Theory*, 33(6):711–725, August 1998.

- [dasgupta98-1] Dasgupta B. and Mruthyunjaya T.S. Force redundancy in parallel manipulators: theoretical and practical issues. *Mechanism and Machine Theory*, 33(6):727–742, August 1998.
- [dasgupta98-2] Dasgupta B. and Mruthyunjaya T.S. Closed-form dynamic equations of the general Stewart platform through the Newton-Euler approach. *Mechanism and Machine Theory*, 33(7):993–1011, October 1998.
- [dasgupta98-3] Dasgupta B. and Mruthyunjaya T.S. A Newton-Euler formulation for the inverse dynamics of the Stewart platform manipulator. *Mechanism and Machine Theory*, 33(8):1135–1152, November 1998.
- [dasgupta99] Dasgupta B. and Choudhury P. A general strategy based on the Newton-Euler approach for the dynamic formulation of parallel manipulators. *Mechanism and Machine Theory*, 34(6):801–824, August 1999.
- [dasgupta2000] Dasgupta B. and Mruthyunjaya T.S. The Stewart platform manipulator: a review. *Mechanism and Machine Theory*, 35(1):15–40, February 2000.
- [dash2002] Dash A.K. and others. Workspace analysis and singularity-free path planning of parallel manipulators. In *Int. Conf. on Mechatronics Technology (ICMT)*, pages 457–462, Fukuoka, September 29- October 3, 2002.
- [dash2003] Dash A.K. and others . Singularity-free path planning of parallel manipulators using clustering algorithm and line geometrie. In *IEEE Int. Conf. on Robotics and Automation*, pages 761–766, Taipei, September, 14-19, 2003.
- [dash2004] Dash A.K. and others. Instantaneous kinematics and singularity analysis of three-legged parallel manipulators. *Robotica*, 22(2):189–203, March 2004.
- [dash2005] Dash A.K. and others . Workspace generation and planning singularity-free path for parallel manipulators. *Mechanism and Machine Theory*, 40(7):778–805, July 2005.
- [dasilva2010] Da Silva M.M. and others . Integrating structural and input design of a 2-dof high-speed parallel manipulator: a flexible model-based approach. *Mechanism and Machine Theory*, 45(11):1509–1519, November 2010.
- [dasilva2024] Da Silva M.M. and others . Hybrid vision/strain-based control strategy for a parallel manipulator with flexible links. *Mechanism and Machine Theory*, 191, 2024.
- [dastjerdi2020] Dasterji A.H., Sheikhi M.M., and Masoulet M.T. A complete analytical solution for the dimensional synthesis of 3-dof delta parallel robot for a prescrib e d workspace. *Mechanism and Machine Theory*, 153, 2020.
- [davis-cm2015] Davis C.M., Park K., and Desai J.P. Design and analysis of an under-actuated xy-theta stage for automated tissue indentation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 4331–4336, Hamburg, Germany, September 28- October 2, 2015.
- [davis93] Davis A.T. and Bradshaw A. Solution and transputer computation of the forward geometry of a manipulator with fully parallel architecture. In Warwick K., editor, *Robotics: applied mathematics and computational aspects*, pages 391–402. Oxford University Press, 1993. **Keywords:** forward kinematics, hardware.
- [davliakos2008] Davliakos I. and Papadopoulos E. Model-based control of a 6-dof electrohydraulic Stewart-Gough platform. *Mechanism and Machine Theory*, 43(11):1385–1400, November 2008.
- [davliakos2009] Davliakos I. and Papadopoulos E. Impedance model-based control for an electrohydraulic stewart platform. European Journal of Control, 5:560–567, 2009.
- [deblaise2005] Deblaise D. and Maurinne P. Effective geometrical calibration of a delta parallel robot used in neuro-surgery. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Edmonton, August, 2-6, 2005.
- [deblaise2006] Deblaise D. and Maurinne P. Analytical modeling of redundant PKM stiffness using matrix structural analysis. In 5th Chemnitzer Parallelkinematik Seminar, pages 155–174, Chemnitz, April, 25-26, 2006.
- [deblaise2006-1] Deblaise D., Hernot X., and Maurinne P. A systematic analytical method for PKM stiffness matrix calculation. In *IEEE Int. Conf. on Robotics and Automation*, pages 4213–4219, Orlando, May, 16-18, 2006.
- [dedieu90] Dedieu J-P and Norton G.H. Stewart varieties: a direct algebraic method for Stewart platforms. SigSam, 24(4):42–59, October 1990.

- [degani2006] Degani A. and Wolf A. Graphical singularity analysis of 3-dof planar parallel manipulators. In ARK, pages 229–238, Ljubljana, June, 26-29, 2006.
- [degani2006-1] Degani A. and Wolf A. Graphical singularity analysis of planar parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 751–758, Orlando, May, 16-18, 2006.
- [degirmenci2015] Degirmency A. and others . Design and control of a parallel linkage wrist for robotic microsurgery. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, September 28- October 2, 2015.
- [degre88] Degré Y. Robot ∇ 6. Research report, ENSAIT, Roubaix, France, August, 9, 1988.
- [degre93] Degré Y. and Castelain J-M. Conception d'un robot à trois degré de liberté et huit liaisons mécaniques axiales. In 11eme Congrès Français de Mécanique, pages 373–376, Lille, 1993.
- [dehghani2008] Dehghani M. and others. Parallel manipulators, New Developments, chapter Neural network solutions for forward kinematics problem of HEXA parallel robot, pages 296–314. ITECH, April 2008. **Keywords:** forward kinematics, neurons networks.
- [dehghani2008-1] Dehghani M. and others . Neural network solutions for forward kinematics problem of HEXA parallel robot. In *American Control Conference*, Washington, June, 11-13, 2008.
- [dehkordi2012] Dehkordi M.B. and others . A new algorithm for gravity compensation of a 3-UPU parallel manipulator. In RoManSy, pages 32–40, Paris, June, 12-15, 2012.
- [deidda2010] Deidda R., Marian A., and Ruggiu M. On the kinematics of the 3-RRUR spherical parallel manipulator. Robotica, 28(6):821–832, October 2010.
- [dejuan2010] De-Juan A. and others . Multi-objective optimization of parallel manipulators. In 3rd European Conf. on Mechanism Science (Eucomes), pages 633–644, Cluj-Napoca, September, 14-17, 2010.
- [deng2023] Deng Z., Zhang Y., and Yan S. Type synthesis of metamorphic and axisymmetric parallel mechanisms using singularity for deployment and latch. *Mechanism and Machine Theory*, 189, 2023.
- [denkena2006] Denkena B. and others . Force calculation of a statically overdetermined parallel kinematic design of an adaptronic spindle system. In 5th Chemnitzer Parallelkinematik Seminar, pages 307–324, Chemnitz, April, 25-26, 2006.
- [denkena2006-1] Denkena B. and Holz C. Advanced position and force control concepts for the linear direct driven hexapod PaLiDA. In 5th Chemnitzer Parallelkinematik Seminar, pages 359–378, Chemnitz, April, 25-26, 2006.
- [derijk2018] De Rijk R., Rushton M., and Khajepour A. Out-of-plane vibration control of a planar cable-driven parallel robot. *IEEE/ASME Trans. on Mechatronics*, 23(4), 2018.
- [desapio2006] De Sapio V., Holzbaur K., and Oussama K. The control of kinematically constrained shoulder complexes: Physiological and humanoid examples. In *IEEE Int. Conf. on Robotics and Automation*, pages 2952–2959, Orlando, May, 16-18, 2006.
- [detweiler 2006] Detweiler C. and others . Hierarchical control for self-assembling mobile trusses with passive and active links. In *IEEE Int. Conf. on Robotics and Automation*, pages 1483–1490, Orlando, May, 16-18, 2006.
- [devaquet92] Devaquet G. and Brauchli H. A simple mechanical model for the Delta-robot. *Robotersysteme*, 8(4):193–199, 1992.
- [devita2007] De Vita L.M., Plante J.S., and Dubowsky S. The design of high precision parallel mechanisms using binary actuation and elastic averaging: With application to MRI cancer treatment. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [dhingra2000] Dhingra A.K., Almadi A.N., and Kohli D. A Gröbner-Sylvester hybrid method for closed-form displacement analysis of mechanisms. *ASME J. of Mechanical Design*, 122(4):431–438, December 2000.
- [dhingra92] Dhingra A., Kohli D., and Xu Y.X. Direct kinematic of general Stewart platforms. In 22nd Biennial Mechanisms Conf., pages 107–112, Scottsdale, September, 13-16, 1992.

- [diao2006] Diao X. and Ma O. Workspace analysis of a 6-dof cable robot for hardware-in-the-loop dynamic simulation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Beijing, October, 9-15, 2006.
- [diao2007] Diao X. and Ma O. A method for verifying force-closure condition for general cable manipulators with seven cables. *Mechanism and Machine Theory*, 42(12):1563–1576, December 2007.
- [diao2007-1] Diao X. and Ma O. Force-closure analysis of general 6-dof cable manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3931–3936, San Diego, September, 22-26, 2007.
- [diao2008] Diao X. and Ma O. Workspace determination of general 6 d.o.f. cable manipulators. *Advanced Robotics*, 22(2-3):261–278, 2008.
- [diao2008-1] Diao X., Ma O., and Lu Q. Singularity analysis of planar cable-driven parallel robots. In *IEEE Conference on Robotics, Automation and Mechatronics*, pages 272–277, Chengdu, September 2008.
- [diao2009] Diao X. and Ma O. Force closure analysis of 6 dof cable manipulators with seven or more cables. *Robotica*, 27(2):209–215, March 2009.
- [diao2015] Diao X. Singularity analysis of fully-constrained cable-driven parallel robots with seven cables. In *IEEE International Conference on Mechatronics and Automation (ICMA)*, pages 1537–1541, Beijing, August 2015.
- [diaz-rodriguez2008] Díaz-Rodríguez M. and others . Identifiability of the dynamic parameters of a class of parallel robots in the presence of measurement noise and modeling discrepancy. *Mechanics Based Design of Structures and Machines*, 36(4):478–498, 2008.
- [diaz-rodriguez2009] Díaz-Rodríguez M. and others . On the experiment design for direct dynamic parameter identification of parallel robots. *Advanced Robotics*, 23(3):329–348, 2009.
- [diaz-rodriguez2010] Díaz-Rodríguez M. and others . A methodology for dyname parameters identification of a 3-dof parallel robot in terms of relevant parameters. *Mechanism and Machine Theory*, 45(9):1337–1356, October 2010.
- [diaz-rodriguez2012] Díaz-Rodríguez M. and others . On the conditioning of the observation matrix for dynamic parameters identification of parallel robots. In *RoManSy*, Paris, June, 12-15, 2012.
- [diaz-rodriguez2013] Díaz-Rodríguez M. and others . Model-based control of a 3-DOF parallel robot based on identified relevant parameters. *IEEE/ASME Trans. on Mechatronics*, 18(6), 2013.
- [diaz-rodriguez2016] Díaz-Rodríguez M., Carretero J.A., and Bautista-Quintero R. Solving the dynamic equations of a 3-prs parallel manipulator for efficient model-based designs. *Mechanical Sciences*, 7:1337–1356, 2016.
- [dibakar99] Dibakar S. and Mruthyunjaya T.S. A computational geometry approach for determination of boundary of workspaces of planar manipulators with arbitrary topology. *Mechanism and Machine Theory*, 34(1):149–169, January 1999.
- [didrit97] Didrit O. Analyse par intervalles pour l'automatique; Résolution globale et garantie de problèmes non linéaires en robotique et en commande robuste. Ph.D. Thesis, Université Paris XI Orsay, Paris, June, 30, 1997. **Keywords:** forward kinematics.
- [didrit98] Didrit O., Petitot M., and Walter E. Guaranteed solution of direct kinematic problems for general configurations of parallel manipulator. *IEEE Trans. on Robotics and Automation*, 14(2):259–266, April 1998.
- [dierichs2019] Dierichs K. and others . Construction robotics for designed granular materials: in situ construction with designed granular materials at full architectural scale using a cable-driven parallel robot. *Construction Robotics*, October 2019.
- [dietmaier94] Dietmaier P. An inverse force analysis of a spatial three-spring system. In ARK, pages 261–270, Ljubljana, July, 4-6, 1994.
- [dietmaier96] Dietmaier P. Forward kinematics and mobility of one type of symmetric Stewart-Gough platforms. In ARK, pages 379–388, Portoroz-Bernadin, June, 22-26, 1996.
- [dietmaier98] Dietmaier P. The Stewart-Gough platform of general geometry can have 40 real postures. In ARK, pages 7–16, Strobl, June 29- July 4, 1998.

- [dietrich2010] Dietrich F. and others . An autonomous and safe homing strategy for parallel kinematic five-bar manipulators. In ARK, pages 501–508, Piran, June 28- July 1, 2010.
- [dietrich2012] Dietrich F., Grüner S., and Raatz A. A generic software architecture for control of parallel kinematics designed for reduced computing hardware. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Vilamoura, October, 7-12, 2012.
- [diezinger2023] Diezinger M., Tamadazte B., and Laurent G.J. Trirod: A 3-RF continuum parallel robot for shape-based load estimation. *IEEE Robotics and Automation Letters*, 8(11):7265–7272, November 2023.
- [digregorio98] Di Gregorio R. and Parenti-Castelli V. A translationnal 3-dof parallel manipulator. In ARK, pages 49–58, Strobl, June 29- July 4, 1998.
- [digregorio2000] Di Gregorio R. and Parenti-Castelli V. Mobility analysis of the 3-PSP mechanism. In 13th RoManSy, pages 113–120, Zakopane, July, 3-6, 2000.
- [digregorio2001] Di Gregorio R. A new parallel wrist using only revolute pairs: the 3-RUU wrist. *Robotica*, 19(3):305–309, May 2001.
- [digregorio2001-1] Di Gregorio R. and Parenti-Castelli V. Position analysis in analytical form of the 3-PSP mechanism. ASME J. of Mechanical Design, 123(1):51–55, March 2001.
- [digregorio2001-2] Di Gregorio R. and Parenti-Castelli V. Kinematics of a six-dof fixation device for long-bone fracture reduction. *J. of Robotic Systems*, 18(12):715–722, 2001.
- [digregorio2001-3] Di Gregorio R. Analytic formulation of the 6-3 fully-parallel manipulator's singularity determination. *Robotica*, 19(6):663–667, September 2001.
- [digregorio2002] Di Gregorio R. and Parenti-Castelli V. Mobility analysis of the 3-UPU parallel mechanism assembled for a pure translational motion. ASME J. of Mechanical Design, 124(2):259–264, June 2002.
- [digregorio2002-1] Di Gregorio R. and Parenti-Castelli V. Geometric error effects on the performances of a parallel wrist. In 3rd Chemnitzer Parallelkinematik Seminar, pages 1011–1024, Chemnitz, April, 23-25, 2002.
- [digregorio2002-2] Di Gregorio R. Translational parallel manipulators: new proposals. *J. of Robotic Systems*, 19(12):595–603, 2002.
- [digregorio2002-3] Di Gregorio R. Singularity locus expression of a class of parallel mechanisms. *Robotica*, 20(3):323–328, 2002.
- [digregorio2002-4] Di Gregorio R. Dynamic performance indices for 3-dof parallel manipulators. In ARK, pages 11–20, Caldes de Malavalla, June 29- July 2, 2002.
- [digregorio2002-5] Di Gregorio R. A new family of spherical parallel manipulators. *Robotica*, 20(4):353–358, July 2002.
- [digregorio2002-6] Di Gregorio R. and Parenti-Castelli V. Dynamics of a class of parallel wrists. In ASME 27th Biennial Mechanisms and Robotics Conf., Montréal, September 29- October 2, 2002.
- [digregorio2002-7] Di Gregorio R. and Parenti-Castelli V. The 3-RRS wrist: a new, very simple and not overconstrained sperical parallel wrist. In ASME 27th Biennial Mechanisms and Robotics Conf., Montréal, September 29-October 2, 2002.
- [digregorio2002-8] Di Gregorio R. Rotation singularities in the Delta-like manipulators. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [digregorio2003] Di Gregorio R. and Zanforlin R. Workspace analytic determination of two similar translational parallel manipulators. *Robotica*, 21(5):555–566, October 2003.
- [digregorio2003-1] Di Gregorio R. Inverse position analysis, workspace and position synthesis of parallel manipulators with 3-RSR topology. *Robotica*, 21(6):627–632, December 2003.
- [digregorio2003-2] Di Gregorio R. Kinematics of the 3-UPU wrist. *Mechanism and Machine Theory*, 38(3):253–263, March 2003.

- [digregorio2003-3] Di Gregorio R. Kinematics of the 3-RSR wrist. In 11th ICAR, pages 1769–1774, Coimbra, June 30- July 3, 2003.
- [digregorio2003-4] Di Gregorio R. Direct kinematics of a class of 3-dof parallel manipulators. In 11th ICAR, pages 550–555, Coimbra, June 30- July 3, 2003.
- [digregorio2003-5] Di Gregorio R. and Parenti-Castelli V. On the multiple solutions of the direct position analysis of parallel mechanisms. In RAAD, Cassino, May, 7-10, 2003.
- [digregorio2003-6] Di Gregorio R. Static analysis and performance indices of the 3-RRS wrist. In *RAAD*, Cassino, May, 7-10, 2003.
- [digregorio2004] Di Gregorio R. Kinematics of the 3-RSR wrist. *IEEE Trans. on Robotics*, 20(4):750–754, August 2004.
- [digregorio2004-1] Di Gregorio R. and Parenti-Castelli V. Dynamics of a class of parallel wrists. ASME J. of Mechanical Design, 126(3):436–441, May 2004.
- [digregorio2004-2] Di Gregorio R. Forward problem singularities of manipulators which become PS-2RS or 2PS-RS structures when the actuators are locked. ASME J. of Mechanical Design, 126(4):640–645, July 2004.
- [digregorio2004-3] Di Gregorio R. Statics and singularity loci of the 3-UPU wrist. *IEEE Trans. on Robotics*, 20(4):630–635, August 2004.
- [digregorio2004-4] Di Gregorio R. Kinematics of the translational 3-URC mechanism. ASME J. of Mechanical Design, 126(6):1113-1117, November 2004.
- [digregorio2004-5] Di Gregorio R. On the direct problem singularities of a class of 3-DOF parallel manipulators. *Robotica*, 22(4):389–394, 2004.
- [digregorio2004-6] Di Gregorio R. Determination of singularities in Delta-like manipulators. *Int. J. of Robotics Research*, 23(1):89–96, January 2004.
- [digregorio2005] Di Gregorio R. Forward problem singularities in parallel manipulators which generate SX-YS-ZS structures. *Mechanism and Machine Theory*, 40(5):600–612, May 2005.
- [digregorio2006] Di Gregorio R. and Parenti-Castelli V. Dynamic performance evaluation and design of 3 and less-than-3 degrees of freedom parallel manipulators. In 5th Chemnitzer Parallelkinematik Seminar, pages 213–231, Chemnitz, April, 25-26, 2006.
- [digregorio2006-1] Di Gregorio R. and Parenti-Castelli V. Parallel mechanisms for knee orthoses with selective recovery action. In *ARK*, pages 167–176, Ljubljana, June, 26-29, 2006.
- [digregorio2006-2] Di Gregorio R. Analytic form solution of the forward position analysis of three-legged parallel mechanisms generating SR-PS-RS structures. *Mechanism and Machine Theory*, 41(9):1062–1071, September 2006.
- [digregorio2006-3] Di Gregorio R. Closure to "discussion of 'Kinematics of the 'translational 3-URC mechanism"' (2006,asme j. mech. des.,128,pp 812-813). ASME J. of Mechanical Design, 128(4):814, July 2006.
- [digregorio2006-4] Di Gregorio R. Analytic form solution of the direct position analysis of a wide family of three-legged parallel manipulators. ASME J. of Mechanical Design, 128(1):264–271, January 2006.
- [digregorio2006-5] Di Gregorio R. Forward position analysis of the SP-PS-RS architecture. *Int. J. of Robotics and Automation*, 21(4):295–301, 2006.
- [digregorio2007] Di Gregorio R. Industrial Robotics, Theory, Modelling and Control, chapter Parallel manipulator with lower mobility, pages 557–572. pro literatur Verlag, January 2007. **Keywords:** structural synthesis, state of the art.
- [digregorio2010] Di Gregorio R. Singularity locus of 6-4 fully-parallel manipulators. In ARK, pages 437–448, Piran, June 28- July 1, 2010.

- [digregorio2012] Di Gregorio R. Classification of the singularity loci of m-n fully-parallel manipulators. In ARK, pages 43–50, Innsbruck, June, 25-28, 2012.
- [digregorio2014] Di Gregorio R. A deployable parallel wrist with simple kinematics. In ARK, pages 51–59, Ljulbjana, June 29- July 3, 2014.
- [digregorio2014-1] Di Gregorio R. Position analysis, path planning and kinetostatic of single loop  $\underline{R}U (nS)\underline{P}U$  wrists. Mechanism and Machine Theory, 74:117–133, 2014.
- [digregorio2017] Di Gregorio R. Kinematics analysis and singularities of novel decoupled parallel manipulators with simplified architecture. *Robotica*, 35:961–979, 2017.
- [dindorf2019] Dindorf R. and Wos P. Control of integrated electro-hydraulic servo-drives in a translational parallel manipulator. *Journal of Mechanical Science and Technology*, 33(11):5437–5448, 2019.
- [ding-h2015] Ding H. and others. Computer aided structure synthesis of 5-dof parallel mechanisms and the establishment of kinematic structure databases. *Mechanism and Machine Theory*, 83:14–30, 2015.
- [ding-y2020] Ding Y. and others . A human-guided vision-based measurement system for multi-station robotic motion platform based on V-Rep. *Robotica*, 38:1227–1241, 2020.
- [ding2013] Ding B. and others. Active preload control of a redundantly actuated Stewart platform for backlash prevention. In *IEEE Int. Conf. on Robotics and Automation*, pages 1900–1907, Karlsruhe, May, 6-10, 2013.
- [ding2015] Ding B. and others . Active preload control of a redundantly actuated Stewart platform for backlash prevention. *Robotics and Computer-Integrated Manufacturing*, 32:11–24, April 2015.
- [dion-gauvin2017] Dion-Gauvin P. and Gosselin C. Trajectory planning for the static to dynamic transition of point-mass cable-suspended parallel mechanisms. *Mechanism and Machine Theory*, pages 158–178, July 2017.
- [do88] Do W.Q.D. and Yang D.C.H. Inverse dynamic analysis and simulation of a platform type of robot. *J. of Robotic Systems*, 5(3):209–227, 1988.
- [dohner96] Dohner J.L. Active chatter suppression in an octahedral hexapod milling machine. *Proc. of the SPIE*, 2721:316–325, 1996.
- [dombre2001] Pierrot F. and Merlet J-P. Analyse et modélisation des robots manipulateurs, chapter Modélisation des robot parallèles, pages 93–144. Hermès, Paris, 2001. sous la direction d'E. Dombre.
- [dominjon2007] Dominjon L., Perret J., and Lécuyer A. Novel devices and interaction techniques for human-scale haptics. *Visual Computer*, 23(4):257–266, April 2007.
- [donelan 2007] Donenlan P.S. Singularity-theoretic methods in robot kinematics. *Robotica*, 25(6):641–659, November 2007.
- [dong-c2018] Dong C. and others . Stiffness modeling and analysis of a novel 5-DOF hybrid robot. *Mechanism and Machine Theory*, 125:80–93, July 2018.
- [dong-g-2016] Dong G. and others . Mobility analysis and kinematic synthesis of a novel 4-dof parallel manipulator. Robotica, 34:1010-1025, 2016.
- [dong-j2008] Dong J., Salapaka S.M., and Ferreira P.M. Robust control of a parallel kinematic nanopositionner. ASME J. of Dynamic Systems, Measurement and Control, 130(4):041007–1/15, July 2008.
- [dong-y2016] Dong Y., Gao F., and Yue Y. Modeling and experimental study of a novel 3-RPR parallel micromanipulator. *Robotics and Computer-Integrated Manufacturing*, 37:115–124, February 2016.
- [dong2005] Dong W., Du Z., and Sun L. Conceptional design and kinematics modeling of a wide-range flexure hinge-based parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 4042–4047, Barcelona, April, 19-22, 2005.
- [dongsheng2018] Dongsheng Z.and others. Design of a novel 5-dof hybrid serial-parallel manipulator and theoretical analysis of its parallel part. *Robotics and Computer-Integrated Manufacturing*, 53:228–239, 2018.

- [donohoe2016] Donohoe S.P. and others . Mechatronic implementation of a force optimal underconstrained planar cable robot. *IEEE/ASME Trans. on Mechatronics*, 21(1), 2016.
- [dorsey92] Dorsey J.T., Sutter T.R., and Wu K.C. Structurally adaptive space crane concept for assembling space systems on orbit. Research Report TP-3307, NASA Research Center, Langley, November 1992.
- [douady91] Douady D. Contribution à la modélisation des robots parallèles: conception d'un nouveau robot à 3 liaisons et six degrés de liberté. Ph.D. Thesis, Université Paris VI, Paris, December, 9, 1991. **Keywords:** mechanical architecture,6 dof robot,kinematics,singularity,design.
- [douat2010] Douat L.R. and others . Flexible model identification of the parallel robot Par2. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Taipei, October, 18-22, 2010.
- [dovat2008] Dovat L. and others. HandCARE: a cable-actuated rehabilitation system to train hand function after stroke. *IEEE Trans. on Neural Systems and Rehabilitation Engineering*, 16(6), 2008.
- [downing 2002] Downing D.M., Samuel A.E., and Hunt K.H. Identification of the special configurations of the octahedral manipulators using the pure condition. *Int. J. of Robotics Research*, 21(2):147–159, February 2002.
- [dressler2007] Dressler I., Robertsson A., and Johansson R. Accuracy of kinematic and dynamic models of a Gantry-Tau parallel kinematic robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 883–888, Roma, April, 10-14, 2007.
- [dressler2008] Dressler I., Robertsson A., and Johansson R. Automatic kinematic calibration of a modular Gantry-Tau parallel robot from a kinematics point of view. In *IEEE Int. Conf. on Robotics and Automation*, pages 1282–1287, Pasadena, May, 19-23, 2008.
- [dressler2010] Dressler I., Brogardh T., and Robertson A. A kinematic error model for a parallel Gantry-Tau manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3709–3714, Anchorage, May, 3-8, 2010.
- [drosdol85] Drosdol J. and Panik F. The Daimler-Benz driving simulator. A tool for vehicle development, February 25- March 1, 1985. SAE Technical Paper Series. **Keywords:** applications, simulator, hardware.
- [du-h2015] Du H. and others . Advancing computer-assisted orthopaedic surgery using a hexapod device for closed diaphyseal fracture reduction. *Int J Med Robotics Comput Assist Surg*, 11:348–359, 2015.
- [du-j2012] Du J., Ding W., and Bao H. Cable vibration analysis for large workspace cable-driven parallel manipulators. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [du-j2014] Du J., Bao H., and Cui C. Stiffness and dexterous performances optimization of large workspace cable-driven parallel manipulators. *Advanced Robotics*, 28:187–196, 2014.
- [du-x2019] Du X. and Chen Y. The design and analysis of UPR-UPU-UR vector propulsion mechanism. In *International Conference on Robotics and Biomimetics (ROBIO)*, 2019.
- [du-x2021] Du X. and others . Design and optimization of solar tracker with U-PRU-PUS parallel mechanism. *Mechanism and Machine Theory*, 155, 2021.
- [du-z2014] Du Z., Shi R., and Dong W. A piezo actuated high precision flexible parallel pointing mechanism: conceptual design, development and experiments. *IEEE Trans. on Robotics*, 30(1):131–138, February 2014.
- [du2007] Du Z-C., Yu Y-Q., and Yang J-X. Dynamic model of a flexible 5R parallel robot. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [duan-q2010] Duan Q. and others. Modeling of variable length cable driven parallel robot. In *IEEE/ASME International Conference on Mechatronic and Embedded Systems and Applications*, 2010.
- [duan 2011] Duan X. and others. Motion prediction and supervisory control of the macro-micro parallel manipulator system. Robotica, 29(7):1005–1015, December 2011.
- [duan2011-1] Duan X. and others . Real-time motion planning for the macro-micro parallel manipulator system. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.

- [duan2016] Duan X. and others. On the mechatronic servo bandwidth of a Stewart platform for active vibration isolating in a super antenna. Robotics and Computer-Integrated Manufacturing, 40:66–77, August 2016.
- [duanqj2014] Duan Q.J. and Duan X. Workspace calculation and quantification calculations of cable-driven parallel robots. Advances in Mechanical Engineering, 2014, 2014.
- [dubowsky94] Dubowsky S. and others . The design and implementation of a laboratory test bed for space robotics: the VES mod. II. In *ASME Design Automation Conf.*, pages 99–108, Minneapolis, September, 11-14, 1994.
- [dubowsky94-1] Dubowsky S. and others . A laboratory test bed for space robotics: the VES mod. II. In *IROS*, pages 1562–1569, München, September, 12-16, 1994.
- [duchaine 2007] Duchaine S., V.and Bouchard and Gosselin C. Computationally efficient predictive robot control. *IEEE/ASME Trans. on Mechatronics*, 12(5):570–578, 2007.
- [duffy96] Duffy J. Statics and Kinematics with Applications to Robotics. Cambridge University Press, New-York, 1996. **Keywords:** planar robot, statics, kinematics, stiffness.
- [duffy98] Duffy J., Crane C., Knight B., and Rooney J. An investigation of a special motion of an octahedron manipulator using screw theory. In ARK, pages 307–316, Strobl, June 29- July 4, 1998.
- [dunlop94] Dunlop G.R., Jones T.P., and Lintott A.B. Three DOF parallel robots for linear and spherical positioning. In *ISRAM*, pages 655–660, Hawaï, August, 15-17, 1994.
- [dunlop96] Dunlop G.R. and Jones T.P. Gravity counter balancing of a parallel robot for antenna aiming. In 6th ISRAM, pages 153–158, Montpellier, May, 28-30, 1996.
- [dunlop97] Dunlop G.R. and Jones T.P. Position analysis of a 3-dof parallel manipulator. *Mechanism and Machine Theory*, 32(8):903–920, November 1997.
- [dunlop99] Dunlop G.R. and Jones T.P. Position analysis of a two DOF parallel mechanism- the Canterbury tracker. Mechanism and Machine Theory, 34(4):599–614, May 1999.
- [dunlop2002] Dunlop R. and Garcia A.C. A Nitinol wire actuated Stewart platform. In *Australasian Conf. on Robotics and Automation*, pages 122–127, Auckland, November, 27-29, 2002.
- [dunlop2006] Dunlop R. and others . A singularity free parallel robotic mechanism for aiming antennas and cameras. In RoManSy, Warsaw, 2006.
- [duplessis2002] Du Plessis L.J. and Snyman J.A. Design and optimum operation of a reconfigurable planar Gough-Stewart machining platform. In 3rd Chemnitzer Parallelkinematik Seminar, pages 729–749, Chemnitz, April, 23-25, 2002.
- [duplessis2006] Du Plessis L.J. and Snyman J.A. Determination of optimum geometrie for a planar reconfigurable machining platform using the LFOPC optimization algorithm. *Mechanism and Machine Theory*, 41(3):307–333, March 2006.
- [duplessis2006-1] Du Plessis L.J. and Snyman J.A. An optimaly reconfigurable planar Gough-Stewart machining platform. *Mechanism and Machine Theory*, 41(3):334–357, March 2006.
- [durrbaum2002] A. Dürrbaum and others . Comparison of automatic and symbolic differentation in mathematical modeling and computer simulation.  $Multibody\ System\ Dynamics,\ 7(4):331-355,\ May\ 2002.$
- [durschmied2002] Dürschmied F. and Hestermann J.O. Achieving technical and economic potential with xxx components. In 3rd Chemnitzer Parallelkinematik Seminar, pages 263–275, Chemnitz, April, 23-25, 2002.
- [dutre97] Dutré S., Bruyninckx H., and De Schutter J. The analytical jacobian and its derivative for a parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 2961–2966, Albuquerque, April, 21-28, 1997.
- [dutta2019] Dutta A. T. and others . Sensorless full body active compliance in a 6 DOF parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 59:278–290, 2019.

- [dwolastzki89] Dwolastzki B. and Thornton G.S. The GEC Tetrabot-A serial-parallel topology robot: control design aspects. In *IEE Int. Workshop on Robot Control*, pages 426–431, Oxford, April, 11-12, 1989.
- [earl83] Earl C.F. and Rooney J. Some kinematics structures for robot manipulator designs. *J. of Mechanisms, Transmissions and Automation in Design*, 105(1):15–22, March 1983.
- [eastwood2009] Eastwood S. and Webbb P. Compensation of thermal deformation of a hybrid parallel kinematic machine. *Robotics and Computer-Integrated Manufacturing*, 25(1):81–90, February 2009.
- [eastwood2009-1] Eastwood S. and Webbb P. Error significance analysis and compensation for hpkms. *Industrial Robot*, 36(1):27–35, 2009.
- [eastwood2010] Eastwood S. and Webbb P. A gravitational deflection compensation strategy for HPKMs. *Robotics* and Computer-Integrated Manufacturing, 26(6):694–702, December 2010.
- [eberharter 2007] Eberharter J.K. Synthesis of spatial parallel mechanisms with initial conditions using line geometry. Mechanism and Machine Theory, 42(10):1289,1297, October 2007.
- [ebert96] Ebert-Uphoff I. and Chirikjian G.S. Inverse kinematics of discretely actuated hyper-redundant manipulators using workspace densities. In *IEEE Int. Conf. on Robotics and Automation*, pages 139–145, Minneapolis, April, 24-26, 1996.
- [ebert98] Ebert-Uphoff I. and Gosselin C.M. Static balancing of a class of spatial parallel platform mechanisms. In ASME Design Engineering Technical Conferences, Atlanta, September, 13-16, 1998.
- [ebert98-1] Ebert-Uphoff I. and Gosselin C.M. Kinematic study of a new type of spatial parallel platform mechanism. In ASME Design Engineering Technical Conferences, Atlanta, September, 13-16, 1998.
- [ebert2000] Ebert-Uphoff I., Gosselin C.M., and Laliberté T. Static balancing of spatial parallel platform-revisited. ASME J. of Mechanical Design, 122(1):43–51, March 2000.
- [ebert2002] Ebert-Uphoff I. and Johnson K. Practical considerations for the static balancing of mechanisms of parallel architecture. *Proc. Instn Mech Engrs, Part K: J. Multi-body dynamics*, 216(1):73–85, March 2002.
- [ebert2002-1] Ebert-Uphoff I., Lee J-K., and Lipkin H. Characteristic tetrahedron of wrench singularities for parallel manipulators with three legs. *Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science*, 216(1):81–93, January 2002.
- [ebert2004] Ebert-Uphoff I. and Voglewede P.A. On the connections between cable-driven robots, parallel manipulators and grasping. In *IEEE Int. Conf. on Robotics and Automation*, pages 4521–4526, New Orleans, April, 28-30, 2004.
- [ebrahimi2007] Ebrahimi I., Carretero J.A., and Boudreau R. Actuation scheme for a 6-dof kinematically redundant planar parallel manipulator. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [ebrahimi2007-1] Ebrahimi I., Carretero J.A., and Boudreau R.  $3 \underline{PRRR}$  redundant planar parallel manipulator: inverse displacement, workspace and singularity analyses. *Mechanism and Machine Theory*, 42(8):1007–1016, August 2007.
- [ebrahimi2008] Ebrahimi I., Carretero J.A., and Boudreau R. A family of kinematically redundant planar parallel manipulators. ASME J. of Mechanical Design, 130(6):062306-1/062306-8, June 2008.
- [ebrahimi2008-1] Ebrahimi I., Carretero J.A., and Boudreau R. Kinematic analysis and path planning of a new kinematically redundant planar parallel manipulator. *Robotica*, 26(3):405–413, May 2008.
- [ecorchard2005] Ecorchard G. and Maurine P. Self-calibration of Delta parallel robots with elastic deformation compensation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Edmonton, August, 2-6, 2005.
- [ecorchard2006] Ecorchard G., Neugebauer R., and Maurine P. Self-calibration of a redundantly actuated parallel kinematic machine-tool. In 5th Chemnitzer Parallelkinematik Seminar, pages 477–496, Chemnitz, April, 25-26, 2006.

- [ecorchard2010] Ecorchard G., Neugebauer R., and Maurine P. Elasto-geometrical modeling and calibration of redundantly actuated PKMs. *Mechanism and Machine Theory*, 45(5):795–810, May 2010.
- [eden2016] Eden J. and others . Available acceleration set for the study of motion capabilities for cable-driven robots. Mechanism and Machine Theory, 105:320–336, 2016.
- [eden2017] Eden J. and others . CASPR-ROS: a generalized cable-robot software for ROS. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [eden2019] Eden J. and others. Unilateral manipulability quality indices: generalized manipulability measures for unilaterally actuated robots. ASME J. of Mechanical Design, 141(9), 2019.
- [eftekhari2015] Eftekhari M., Eftekhari M., and Karimpour H. Neuro-fuzzy adaptive control of a revolute Stewart platform carrying payloads of unknown inertia. *Robotica*, 36:588–606, 2018.
- [eftekhari2018] Eftekhari M. and Karimpour H. Emulation of pilot control behavior across a stewart platform simulator. *Robotica*, 36:697–714, 2018.
- [egner96] Egner S. Semi-numerical solution to 6/6-Stewart-platform kinematics based on symmetry. Applicable Algebra in Engineering, Communication and Computing, 7(6):449–468, 1996.
- [ejima2013] Ejima T. and others . Development of microhand utilizing singularity of parallel mechanism. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Tokyo, November, 3-7, 2013.
- [elghazali2014] El-Ghazali G., Gouttefarde M., and Creuze V. Adaptive terminal sliding mode control of redundantly actuated cable-driven parallel manipulator:CoGiRo. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 3–16, Duisburg, August, 24-27, 2014.
- [elghazali2016] El-Ghazali G., Gouttefarde M., Creuze V., and Pierrot F. Maximum wrench feasible payload in cable-driven parallel robots equipped with a serial robot. In *IEEE Int. Conf. on Advanced Intelligent Mechatronics*, Banff, July, 12-15, 2016.
- [elhraiech2020] El Hraiech S. and others . Genetic algorithm coupled with the Krawczyk method for multi-objective design parameters optimization of the 3-UPU manipulator. *Robotica*, 38:1138–1154, 2020.
- [eljjouaoui2022] El Jjouaoui H. and others . Modeling of a remote center of motion spherical parallel tensegrity mechanism for percutaneous interventions. In ARK, Bilbao, June, 26-30, 2022.
- [elkadi2008] Elkadi A. and others . *Parallel manipulators, Towards new applications*, chapter Cartesian parallel manipulator. Modeling, control and simulation, pages 270–294. INTECH, April 2008. **Keywords:** 3 dof robot,dynamics,control.
- [elkhasawneh98] El-Khasawneh B. and Ferreira P.M. The Tetrahedral tripod. In First European-American Forum on Parallel Kinematic Machines, pages 419–430, Milan, August 31- September 1, 1998.
- [elkhasawneh99] El-Khasawneh B. and Ferreira P.M. Computation of stiffness and stiffness bounds for parallel manipulators. Int. J. of Machine Tools & Manufacture, 39(2):321–342, February 1999.
- [ellwood2010] Ellwood R.J. and others . Calibration and validation of a rigid body kinematic model of flexure hinges. In ARK, pages 3–10, Piran, June 28- July 1, 2010.
- [ellwood2010-1] Ellwood R.J., Schütz D., and Raatz A. Incorporating flexure hinges in the kinematic model of a planar  $3-\underline{P}RR$  parallel robot. In 3rd European Conf. on Mechanism Science (Eucomes), pages 683–690, Cluj-Napoca, September, 14-17, 2010.
- [emmens2014] Emmens A.R., S.A.J. Spanjer, and Herder J.L. Modeling and control of a large-span redundant surface contrained cable robot with a vision sensor on the platform. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 249–262, Duisburg, August, 24-27, 2014.
- [endo2010] Endo G. and others . A passive weight compensation mechanism with a non-circular pulley and a spring. In *IEEE Int. Conf. on Robotics and Automation*, pages 3843–3848, Anchorage, May, 3-8, 2010.
- [enferadi2009] Enferadi J. and Tootoonchi A.A. A novel spherical parallel manipulator: forward position problem, singularity analysis, and isotropy design. *Robotica*, 27(5):663–676, 2009.

- [enferadi2010] Enferadi J. and Tootoonchi A.A. A novel approach for forward position analysis of a double-triangle spherical parallel manipulator. *European Journal of Mechanics A/Solids*, 29(3):348–355, May June , 2010.
- [enferadi2011] Enferadi J. and Tootoonchi A.A. Accuracy and stiffness analysis of a 3-RRP spherical parallel manipulator. *Robotica*, 29(2):193–200, March 2011.
- [enferadi2015] Enferadi J. and Shahi A. A closed-form solution for the position analysis of a novel fully spherical parallel manipulator. *Robotica*, 33(10):2114–2136, December 2015.
- [enferadi2016] Enferadi J. and Shahi A. On the position analysis of a new spherical parallel robot with orientation applications. *Robotics and Computer-Integrated Manufacturing*, 37:151–161, 2016.
- [erlbacher97] Erlbacher E.A. Automated scarfing and surface finishing apparatus for complex composite structures, 1997. Contract report SBIR N 00421-97-C-1207. **Keywords:** applications.
- [erskine2019] Erskine J., Chriette A., and Caro S. Control and configuration planning of an aerial cable towed system. In *IEEE Int. Conf. on Robotics and Automation*, Montréal, May, 20-24, 2019.
- [erastova2022] Erastova K. Effective workspaces of parallel robots. Robotica, 40:4308–4325, 2022.
- [erwin2017] Erwin A. and others . Kinesthetic feedback during 2dof wrist movements via a novel MR-compatible robot. *IEEE Trans. on Neural Systems and Rehabilitation Engineering*, 25(9):1489–1499, 2017.
- [escorcia2020] Escorcia-Hernandez J.M. and others . A new solution for machining with RA-PKMs: modelling, control and experiments. *Mechanism and Machine Theory*, 150, 2020.
- [eskandary2018] Eskandary P.K. and Angeles J. The dynamics of a parallel Schönflies-motion generator. *Mechanism and Machine Theory*, 119:119–129, 2018.
- [essomba2016] Essomba T. and others . Optimal synthesis of a spherical parallel mechanism for medical application. *Robotica*, 34:671–686, 2016.
- [esteban2006] Esteban I. and Heisel U. Analysis of the component requirements and the feasible mechanical properties of hexapod machine tools. In 5th Chemnitzer Parallelkinematik Seminar, pages 97–113, Chemnitz, April, 25-26, 2006.
- [eugster 2018] Eugster M. and others . A parallel robotic mechanism for the stabilization and guidance of an endoscope tip in laser osteotomy. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Madrid, October, 1-5, 2018.
- [eugster 2021] Eugster M., Merlet J-P., Gerig N., Cattin P. C., and Rauter G. Miniature parallel robot with submillimeter positioning accuracy for minimally invasive laser osteotomy. *Robotica*, pages 1–28, 2021.
- [everett89] Everett L.J. Forward calibration of closed-loop jointed manipulators. Int. J. of Robotics Research, 8(4):85–91, August 1989.
- [fajardo95] Fajardo P. and Rey-Bakaikoa V. Control of six degree-of-freedom manipulators for synchrotron radiation applications. *Review of Scientific Instruments*, 66(2):1758–1761, February 1995.
- [fan-s2019] Fan S. and Fan S. Approximate stiffness modelling and stiffness defect identification for a heavy-load parallel manipulator. *Robotica*, 37:1120–1142, 2019.
- [fan2013] Fan C., Liu H., and Zhang Y. Type synthesis of 2T2R,1T2R and 2R parallel manipulators. *Mechanism and Machine Theory*, 61:184–190, April 2013.
- [fang97] Fang Y. and Huang Z. Kinematics of a three-degree-of-freedom in-parallel actuated manipulator mechanism. Mechanism and Machine Theory, 32(7):789–796, October 1997.
- [fang2004] Fang Y. and Tsai L-W. Structure synthesis of a class of 3-DOF rotational parallel manipulators. *IEEE Trans. on Robotics and Automation*, 20(1):117–121, February 2004.
- [fang2004-1] Fang Y. and Tsai L-W. Analytical identification of limb structure for translational parallel manipulator. J. of Robotic Systems, 21(5):209–218, 2004.

- [fangh2005] Fang H. and Merlet J-P. Multi-criteria optimal design of parallel manipulators based on interval analysis. Mechanism and Machine Theory, 40(2):151–171, February 2005.
- [fangh2019] Fang H., Tang T., and Zhang J. Kinematic analysis and comparison of a 2R1T redundantly actuated parallel manipulator and its non-redundantly actuated forms. *Mechanism and Machine Theory*, 142, 2019.
- [fangh2022] Fang H. and others . A novel hybrid machine tool integrating a symmetrical redundantly actuated parallel mechanism: Design, kinematics, prototype and experiment. *Mechanism and Machine Theory*, 176, 2022.
- [fanghella2006] Fanghella P., Galletti C., and Giannetti E. Parallel robots that change their group of motion. In ARK, pages 49–56, Ljubljana, June, 26-29, 2006.
- [farajtabar2017] Farajtabar M., Daniali H.M., and Varedi S.M. Pick and place trajectory planning of planar 3-RRR parallel manipulator in the presence of joint clearance. *Robotica*, 35:241–253, 2017.
- [fard2014] Fard B.M., Padargani T., and Saki S. Optimum determination of motor mount locations for a cable-driven rehabilitation robot. In Second RSI/ISM International Conference on Robotics and Mechatronics (ICRoM), pages 864–869, 2014.
- [farhat2007] Farhat N., Diaz M-A., and Mata V. Dynamic parameter identification of parallel robots considering physical feasibility and nonlinear friction models. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [farhat2008] Farhat N. and others . Identification of dynamic parameters of a 3-dof RPS parallel manipulator. *Mechanism and Machine Theory*, 43(1):1–17, January 2008.
- [farhat2010] Farhat N. and others . Dynamic simulation of a parallel robot: Coulomb friction and stick–slip in robot joints. *Robotica*, 28(1):35–45, January 2010.
- [faschingbauer2015] Faschingbauer M. and others . Accuracy of a hexapod parallel robot kinematics based external fixator. *Int J Med Robotics Comput Assist Surg*, 11:424–435, 2015.
- [fasse99] Fasse E.D. and Gosselin C.M. Spatio-geometric impedance control of Gough-Stewart platforms. *IEEE Trans. on Robotics and Automation*, 15(2):281–288, April 1999.
- [fassi2002] Fassi I. and Legnani G. Automatic identification of a minimum, complete and parametrically continuous model for the geometrical calibration of parallel robots. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, pages 204–214, Québec, October, 3-4, 2002.
- [fassi2005] Fassi I., Legnani G., and Tosi D. Geometrical condition for the design of partial or full isotropic hexapods. J. of Robotic Systems, 22(10):507–518, 2005.
- [fatehi2011] Fatehi M.H. and others . Kinematic analysis of 3-PRS parallel robot for using in satellites tracking system. In 2nd International Conference on Control, Instrumentation and Automation (ICCIA), Shiraz, 2011.
- [fattah2000] Fattah A. and Kasei G. Kinematics and dynamics of a parallel manipulator with a new architecture. *Robotica*, 18(5):535–543, September 2000.
- [fattah2001] Fattah A. and Jazi S.H. Optimal design of parallel manipulators. In *ICAR*, pages 645–650, Budapest, August, 22-25, 2001.
- [fattah2002] Fattah A. and Hasan Ghasemi A.M. Isotropic design of spatial parallel manipulators. *Int. J. of Robotics Research*, 21(9):811–824, September 2002.
- [fattah2002-1] Fattah A. and Agrawal S.K. Workspace and design analysis of cable-suspended planar parallel robots. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [fattah2005] Fattah A. and Agrawal S.K. On the design of cable-suspended planar parallel robots. ASME J. of Mechanical Design, 127(5):1021–1028, September 2005.
- [faugere95] Faugère J.C. and Lazard D. The combinatorial classes of parallel manipulators. *Mechanism and Machine Theory*, 30(6):765–776, August 1995.

- [faugere2006] Faugère J.C., Merlet J-P., and Rouillier F. On solving the direct kinematics problem for parallel robots. Research Report 5923, INRIA, June 2006.
- [faulring2004] Faulring E.L., Colgate J.E., and Peshkin M.A. A high performance 6-dof haptic Cobot. In *IEEE Int. Conf. on Robotics and Automation*, pages 1980–1985, New Orleans, April, 28-30, 2004.
- [faulring2006] Faulring E.L., Colgate J.E., and Peshkin M.A. The Cobotic hand controller: design, control and performance of a novel haptic display. *Int. J. of Robotics Research*, 25(11):1099–1119, November 2006.
- [fazenda-carrico2006] Fazenda Carrico N.R. Calibration of high-precision flexure parallel robots. Ph.D. Thesis, EPFL, Lausanne, 2006. **Keywords:** calibration, flexible robot.
- [fazenda2006] Fazenda N. and others . Calibration of the 6 dof high-precision flexure parallel robot Sigma 6. In 5th Chemnitzer Parallelkinematik Seminar, pages 379–398, Chemnitz, April, 25-26, 2006.
- [fei2019] Fei D. and others . Dynamic modeling and simulation of underwater parallel robot. In 4th Int. Conf. on Advanced Robotics and Mechatronics (ICARM), 2019.
- [feng-j2012"] Feng J., Gao F., and Zhao X. Calibration of a six-dof parallel manipulator for chromosome dissection. Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science, 226(4):1084–1096, April 2012.
- [feng96] Feng G. and others. A physical model of the solution space and the atlas of the reachable workspace for 2-dof parallel planar manipulators. *Mechanism and Machine Theory*, 31(2):173–184, February 1996.
- [feng96-1] Feng G. and others . Physical model of the solution space of 3-dof parallel planar manipulators. *Mechanism and Machine Theory*, 31(2):161–171, February 1996.
- [fengchun2019] Fengchun L. and others . A calibration method for overconstrained spatial translational parallel manipulators. Robotics and Computer-Integrated Manufacturing, 57:241–254, 2019.
- [fenyi93] Fenyi S.E. Die Stewart platform als kraft-und momentensensor, das modilisierte Föppl fachwerk als kraftsensor. Research Report 52/01/02P10A, Kernforschungzentrum Karlsruhe, March 1993.
- [fenyi95] Fenyi S.E. Stewart platform based 6-axis force and torque transducers. In J-P. Merlet B. Ravani, editor, Computational Kinematics, pages 221–230. Kluwer, 1995. **Keywords:** applications, force sensor.
- [ferlay2008] Ferlay F. and Gosselin F. A new cable-actuated haptic interface design. In EuroHaptic, 2008.
- [ferrand98] Ferrand A. and Renaud M. Analyse des points morts d'une plate-forme dite de Stewart. *Mechanism and Machine Theory*, 33(4):409–424, May 1998.
- [ferraresi95] Ferraresi C., Montacchini G., and Sorli M. Workspace and dexterity evaluation of 6 d.o.f. spatial mechanisms. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 57–61, Milan, August 30- September 2, 1995.
- [ferraresi95-1] Ferraresi C., Pastorelli S., Sorli M., and Zhmud N. Static and dynamic behavior of a high stiffness Stewart platform-based force/torque sensor. *J. of Robotic Systems*, 12(10):883–893, 1995.
- [ferraresi2004] Ferraresi C. and others . A new 6-dof parallel robotic structure actuated by wires: The WiRo-6.3. *J. of Robotic Systems*, 21(11):581–595, November 2004.
- [ferraresi2007] Ferraresi C., Paoloni M., and F. Pescarmona. A new methodology for the determination of the workspace of six-dof redundant parallel structures actuated by nine wires. *Robotica*, 25(1):113–120, January 2007.
- [ferraresi2010] Ferraresi C. and Pescarmona F. Cable driven devices for telemanipulation. In *Remote and Telerobotics*, chapter 10. IntechOpen, 2010. **Keywords:** wire robot, kinematics, workspace.
- [ferraris2006] Ferraris E. and others. Development of a mini PKM. In 5th Chemnitzer Parallelkinematik Seminar, pages 695–710, Chemnitz, April, 25-26, 2006.
- [ferravante2019] Ferravante V. and others . Dynamic analysis of high precision construction cable-driven parallel robots. *Mechanism and Machine Theory*, 135:54–64, 2019.

- [fesharakifard2008-phd] Fesharakifard R. Conception et réalisation d'une interface à retour d'effort pour les environnements virtuels à échelle humaine. Ph.D. Thesis, Ecole des Mines, Paris, January, 23, 2008. **Keywords:** wire robot.
- [fettig2000] Fettig H., Hubbard T., and Kujath M. Simulation and modeling of compliant micro-mechanisms. In *IX Int. Microscale System Symp.*, pages 12–18, Floride, June, 8, 2000.
- [fichter80] Fichter E.F. and McDowell E.D. A novel design for a robot arm. In *Proc. Int. Computer Technical Conf.*, pages 250–255, San Francisco, 1980.
- [fichter84] Fichter E.F. Kinematics of a parallel connection manipulator. In ASME Design Engineering Technology Conference, pages 1–8, Cambridge (MA), October, 7-12, 1984.
- [fichter86] Fichter E.F. A Stewart platform based manipulator: general theory and practical construction. *Int. J. of Robotics Research*, 5(2):157–181, Summer 1986.
- [fijani2012] Fijani A. and Fried G. Novel algorithm for computation of inverse kinematics and inverse dynamics of Gough-Stewart platform. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1573–1580, Vilamoura, October, 7-12, 2012.
- [filipovic2012] Filipovic M. The importance of modelling an aerial robotic camera. *Scientific Technical Review*, 62(1), 2012.
- [filipovic2012-1] Filipovic M., Djuric A., and Kevac L. Contribution to the modeling of cable-suspended parallel robot hanged on the four points. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Vilamoura, October, 7-12, 2012.
- [filipovic2014] Filipovic M. and Djuria A. Mathematical model of the aerial robotic camera base on its geometric relationship. *FME Trans.*, 42, 2014.
- [filipovic2014-1] Filipovic M. and others . The elastic f-type cable-suspended parallel robot in the service of parents. In *Medical and Service Robotics International Workshop*, Lausanne, 2014.
- [filipovic2016] Filipovic M., Djuria A., and Kevac LJ. The rigid S-type cable-suspended parallel robot design, modeling and analysis. *Robotica*, 34(9):1948–1960, September 2016.
- [finistauri2008] Finistauri A.D., Xi F., and Petz B. *Parallel manipulators, Towards new applications*, chapter Architecture design and optimization of an on-the-fly reconfigurable parallel robot, pages 379–404. ITECH, April 2008. **Keywords:** mechanical architecture, modular robot.
- [finistauri2013] Finistauri A.D. and Xi F. Reconfiguration analysis of a fully reconfigurable parallel robot. *J. of Mechanisms and Robotics*, 5(4), November 2013.
- [fink2009] Fink J. and others . Planning and control for cooperative manipulation and transportation with aerial robots. In 14th ISRR, Lucerne, August 31- September 3, 2009.
- [fioretti94] Fioretti A. Implementation-oriented kinematics analysis of a 6 dof parallel robotic platform. In 4th IFAC Symp. on Robot Control, Syroco, pages 43–50, Capri, September, 19-21, 1994.
- [fiorio2017] Fiorio L. and others. A parallel kinematic mechanism for the torso of a humanoid robot: design, construction and validation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Vancouver, September, 24-28, 2017.
- [firmani2004] Firmani F. and Podhorodeski R.P. Force unconstrained poses for a redundantly-actuated planar parallel manipulator. *Mechanism and Machine Theory*, 39(5):459–476, May 2004.
- [firmani2007] Firmani F. and Podorodeski R-P. Singularity loci of revolute-jointed planar parallel manipulators with redundant actuated branches. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [firmani2008] Firmani F. and others . Wrench capabilities of planar parallel manipulators. Part I: wrench polytopes and performance indices. *Robotica*, 26(6):791–802, November 2008.

- [firmani2008-1] Firmani F. and others . Wrench capabilities of planar parallel manipulators. Part II: redundancy and wrench workspace analysis. *Robotica*, 26(6):803–815, November 2008.
- [firmani2008-2] Firmani F. and others. Parallel manipulators, Towards new applications, chapter Wrench capabilities of planar parallel manipulators and their effects under redundancy, pages 109–120. ITECH, April 2008. **Keywords:** planar robot, redundant robot, statics, performance analysis.
- [firmani2009] Firmani F. and Podhorodeski R.P. Singularity analysis of planar parallel manipulators based on forward kinematic solutions. *Mechanism and Machine Theory*, 44(8):1386–1399, 2009.
- [firoozhbadi2015] Firoozhabadi A.E., Ebrahimi S., and Amirian G. Dynamic characteristics of a 3-RPR parallel manipulator with flexible intermediate links. *Robotica*, 33(9):1909–1925, November 2015.
- [firoozhbadi2017] Firoozhabadi A.E., Ebrahimi S., and Font-Liagunes J.M. A comparative study of elastic motions in trajectory tracking of flexible RPR planar manipulators moving with high speed. *Robotica*, 35(7):1523–1540, 2017.
- [fleischer 2005] Fleischer J., Schmidt-Ewig J.P., and WEeule H. Innovative machine kinematics for combined handling and machining of three-dimensional curved lightweight extrusion structures. *Annals of the CIRP*, 54(1):317–320, 2005.
- [fleischer 2006] Fleischer J. and Schmidt-Ewig J.P. Combination of a parallel and a serial kinematic for the integrated handling and machining of lightweight extrusion structure. In 5th Chemnitzer Parallelkinematik Seminar, pages 289–306, Chemnitz, April, 25-26, 2006.
- [flores2007] Flores F.G., Kecskeméthy A., and Pöttker A. Workspace analysis and maximal force calculation of a face-shovel excavator using kinematical transformers. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [fluckiger98] Flückiger L. A robot interface using virtual reality and automatic kinematics generator. In 27th Int. Symposium on Robotics, pages 123–126, Birmingham, April 24- May 1, 1998.
- [fomin2018] Fomin A. and Glazunov V. A novel rotary positioner with single drive: structural anlysis and kinematic design. In ARK, Bologna, July, 1-5, 2018.
- [fontana2006] Fontana M. and others . Kinematics of a new 2-dof wrist with high angulation capability. In *IEEE Int. Conf. on Robotics and Automation*, pages 1524–1529, Orlando, May, 16-18, 2006.
- [fontes2016] Fontes J.V. and Da Silva M.M. On the dynamic performance of parallel kinematic manipulators with actuation and kinematic redundancies. *Mechanism and Machine Theory*, 103:148–166, 2016.
- [fontes2022] Fontes J.V. and others . Model-based joint and task space control strategies for a kinematically redundant parallel manipulator. *Robotica*, 40:1570–1586, 2022.
- [fortin-cote2014] Fortin-Côté A., Cardou P., and Gosselin C. An admittance control scheme for haptic interfaces based on cable-driven parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 819–825, Hong-Kong, 7 May 31- June, 2014.
- [fortin-cote2016] Fortin-Côté A., Cardou P., and Campeau-Lecours A. Improving cable driven parallel robot accuracy through angular position sensors. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 4350–4355, Daejeon, October, 9-14, 2016.
- [fortin-cote2016-1] Fortin-Côté A., Cardou P., and Gosselin C. A tension distribution algorithm for cable-driven parallel robots operating beyond their wrench-feasible workspace. In 6th International Conference on Control, Automation and Systems (ICCAS), Gyeongju, October, 16-19, 2016.
- [fortin-cote2017] Fortin-Côté A. and others . On the design of a novel cable-driven parallel robot capable of large rotation about one axis. In 3rd Int. Conf. on cable-driven parallel robots (Cable Con), Québec, 2017.
- [foshage96] Foshage J. and others . Hybrid active/passive actuation for spacecraft vibration isolation and suppression. *Proc. of the SPIE*, 2865:104–121, 1996.
- [foucault2002] Foucault S. and Gosselin C.M. On the development of a planar 3-dof reactionless parallel mechanism. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.

- [fraczek2001] Fraczek J., Busko Z., and Morecki A. Laser calibration and kinematical analysis and synthesis of robots. Selected problems. In 2nd Int. Workshop on Robot Motion and Control (RoMoCo), pages 19–25, Bukowy Dworek, October, 18-20, 2001.
- [franci2008] Franci R., Parenti-Castelli V., and Sanciso N. A three-step procedure for the modelling of human diarthrodial joints. In *RAAD*, Technical University of Marche Region, 2008.
- [franke2002] Franke H.J., Otremba R., and Janicke T. Methodical development of optimized passive joints. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 119–130, Braunschweig, May, 29-30, 2002.
- [franke2005] Franke H.J. and others . Knowledge based development environment. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 221–236, Braunschweig, May, 10-11, 2005.
- [frayssinet2006] Frayssinet H. and others . Improving the accuracy of the 5-axis parallel kinematic machine-tool HITA-STT (Stiffness Tracking Technology). In 5th Chemnitzer Parallelkinematik Seminar, pages 585–601, Chemnitz, April, 25-26, 2006.
- [french2004] French C.W. and others . Multi-axial subassemblage testing (Mast) system: description and capabilities. In 13th World Conf. on Earthquake Engineering, page No. 2146, Vancouver, August, 1-6, 2004.
- [fried96] Fried G. and others . A 3-D sensor for parallel robot calibration. A parameter perturbation analysis. In ARK, pages 451-460, Portoroz-Bernadin, June, 22-26, 1996.
- [frigola2008] Frigola R. and others . A wrench-sensitive touch pad based on a parallel structure. In *IEEE Int. Conf.* on Robotics and Automation, pages 3449–3454, Pasadena, May, 19-23, 2008.
- [frindt98] Frindt F., Kerle H., and Plitea N. PENTA- Vorstellung eines parallelen maschinenkonzepts mit fünf bewegungsfreiheiten. In *New machine concepts for handling and manufacturing devices on the basis of parallel structures*, pages 15–34, Braunschweig, November, 10-11, 1998.
- [frisoli2000] Frisoli A. and others . Synthesis by screw algebra of translating in-parallel actuated mechanisms. In ARK, Piran, June, 25-29, 2000.
- [frisoli2007] Frisoli A. and others . A new method for the estimation of position accuracy in parallel manipulators with joint clearances. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [frisoli2008] Frisoli A., Solazzi M., and Bergamasco M. A new method for the estimation of position accuracy in parallel manipulators with joint clearances by screw theory. In *IEEE Int. Conf. on Robotics and Automation*, pages 837–844, Pasadena, May, 19-23, 2008.
- [frisoli2011] Frisoli A. and others . A new screw theory method for the estimation of position accuracy in spatial parallel manipulators with revolute joint clearances. *Mechanism and Machine Theory*, 46:1929–1949, 2011.
- [fu-j-2016] Fu J. and others . Kinematic accuracy research of a novel six-degree-of-freedom parallel robot with three legs. *Mechanism and Machine Theory*, 102:86–102, 2016.
- [fu2007] Fu S., Yao Y., and Wu Y. Comment on 'a newton-euler formulation for the inverse dynamics of the Stewart platform manipulator' by s. dasgupta and t.s. mruthyunjaya [mech. mac. theory 33 (1998) 1135-1152]. *Mechanism and Machine Theory*, 42(12):1668–1671, December 2007.
- [fujimoto91] Fujimoto K. and others. Derivation and analysis of equations of motion for a 6 d.o.f. direct drive wrist joint. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 779–784, Osaka, November, 3-5, 1991.
- [fumagali2009] Fumagali A. and Massarati P. Real-time inverse dynamics control of parallel manipulators using general-purpose multibody software. *Multibody System Dynamics*, 22:47–68, 2009.
- [funabashi91] Funabashi H. and others . Development of spatial parallel manipulators with 6 d.o.f. JSME Int. J., Serie III, Vibration, 34(3):387–392, 1991.
- [funabashi94] Funabashi H. In parallel actuated mechanisms as a new robotic mechanism. *Advanced Robotics*, 8(6):535–544, December 1994.

- [funabashi95] Funabashi H. and Takeda Y. Determination of singular points and their vicinity in parallel manipulators based on the transmission index. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1977–1981, Milan, August 30- September 2, 1995.
- [gabaldo2022] Gabaldo S., Ida E., and Carricato M. Sensitivity of the direct kinematics of underactuated cable-driven parallel robots to redundant sensor-measurement errors. In ARK, Bilbao, June, 26-30, 2022.
- [gabardi2018] Gabardi M., Solazzi M., and Frisoli A. An optimization procedure based on kinematics analysis for the design parameters of a 4-UPU parallel manipulator. *Mechanism and Machine Theory*, 133:211–228, 2018.
- [gabellieri2020] Gabellieri C. and others . Compliance control of a cable-suspended aerial manipulator using hierarchical control framework. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October, 25-29, 2020.
- [gadfly83] Gadfly . The answer to electronic component assembly. Assembly Automation, pages 20–22, February 1983.
- [gagliardini2014] Gagliardini L. and others . Optimal design of cable-driven parallel robots for large industrial structures. In *IEEE Int. Conf. on Robotics and Automation*, pages 5744–5749, Hong-Kong, 7 February 31- June , 2014.
- [gagliardini2014-1] Gagliardini L. and others. A reconfigurable cable-driven parallel robot for sandblasting and painting of large structure. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 3–16, Duisburg, August, 24-27, 2014.
- [gagliardini2015] Gagliardini L., Gouttefarde M., and Caro S. Dimensioning of cable-driven parallel robot actuators, gearboxes and winches according to the twist feasible workspace. In *IEEE International Conference on Automation Science and Engineering (CASE)*, Gothenburg, August, 24-28, 2015.
- [gagliardini2015-1] Gagliardini L., Caro S., and Gouttefarde M. Optimal path planning and reconfiguration strategy for reconfigurable cable-driven parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, Seattle, May, 26-30, 2015.
- [gagliardini2016] Gagliardini L., Gouttefarde M., and Caro S. Determination of a dynamic feasible workspace for cable-driven parallel robot. In ARK, Grasse, June, 27-30, 2016.
- [gagliardini2016-1] Gagliardini L., Gouttefarde M., and Caro S. Discrete reconfiguration planning of cable-driven parallel robots. *Mechanism and Machine Theory*, 100, 2016.
- [gagliardini2016-phd] Gagliardini L. Discrete reconfiguration of cable-driven parallel robots. Ph.D. Thesis, Ecole Centrale de Nantes, Nantes, September, 19, 2016. **Keywords:** wire robot,dynamics,workspace,mechanical architecture,modular robot.
- [gallant-m2018] Gallant M. and Gosselin C. Singularities of a planar  $3-R\underline{P}R$  parallel manipulator with joint clearance. *Robotica*, 36:1098-1109, 2018.
- [gallant2012] Gallant A., Boudreau R., and Gallant M. Geometric determination of the dextrous workspace of n-<u>RR</u>RR and n<u>R</u>R<u>P</u>R manipulators. *Mechanism and Machine Theory*, 51:159–171, 2012.
- [gallardo2003] Gallardo J. and others . Dynamics of parallel manipulators by means of screw theory. *Mechanism and Machine Theory*, 38(11):1113–1131, November 2003.
- [gallardo2006] Gallardo-Alvarado J., Rico-Martínez J.M., and Alici G. Kinematics and singularity analyses of a 4-dof parallel manipulator using screw theory. *Mechanism and Machine Theory*, 41(9):1048–1061, September 2006.
- [gallardo2007] Gallardo-Alvarado J. and others . Kinematics of a class of parallel manipulators which generates structures with three limbs. *Multibody System Dynamics*, 17:27–46, 2007.
- [gallardo2008] Gallardo-Alvarado J. and others . Analytical solution of the forward position analysis of parallel manipulators that generates 3-RS structures. *Advanced Robotics*, 22(2-3):215–234, 2008.
- [gallardo2008-1] Gallardo-Alvarado J. and others . Kinematics and dynamics of 2-(3-RPS) manipulators by means of screw theory and the principle of virtual work. *Mechanism and Machine Theory*, 43(10):1281–1294, October 2008.

- [gallardo2008-2] Gallardo J. and others . A family of spherical parallel manipulators with two legs. *Mechanism and Machine Theory*, 43(2):201–216, February 2008.
- [gallardo2008-3] Gallardo J. and others . Parallel manipulators, New Developments, chapter Acceleration analysis of 3-RPS parallel manipulators by means of screw theory, pages 315–330. ITECH, April 2008. **Keywords:** dynamics,3 dof robot.
- [gallardo2010] Gallardo J., Orozco-Mendoza H., and Rico-Martinez J.M. A novel five-degrees of freedom decoupled robot. *Robotica*, 28(6):909–917, June 2010.
- [gallardo2010-1] Gallardo-Alvarado J. and others. Kinematics of an asymmetrical three-legged parallel manipulator by means of the screw theory. *Mechanism and Machine Theory*, 45(8):1013–1023, August 2010.
- [gallardo2011] Gallardo J. DeLiA: a new redundant partially decoupled robot. Advanced Robotics, 25(9-10):1297–1310, 2011.
- [gallardo2012] Gallardo J. and others . A novel three degrees of freedom partially decoupled robot with linear actuators. Robotica, 30(3):467-475, May 2012.
- [gallardo2013] Gallardo J., Garcia-Murillo M.A., and Castillo-Castaneda E. A 2(3-RRPS) parallel manipulator inspired by Gough-Stewart platform. *Robotica*, 31(3):381–388, May 2013.
- [gallardo2014] Gallardo J. A simple method to solve the forward displacement analysis of the general six-legged parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 30(1):55–61, February 2014.
- [gallardo2019] Gallardo J., Abedinnasab M.H., and Islam Md. N. A simple method to solve the instantaneous kinematics of the 5-RPUR parallel manipulator. *Robotica*, 37:5143–1157, 2019.
- [gallardo2022] Gallardo J., Garcia-Murillo M., and Rodrigues-Castro R. Kinematics of a nine-legged in-parallel manipulator with configurable platform. *Robotica*, 40(12):4455–4474, 2022.
- [gallina2002] Gallina P. and Rosati G. Manipulability of a planar wire driven haptic device. *Mechanism and Machine Theory*, 37(2):215–228, 2002.
- [gallot2007] Gallot G., Ibrahim O., and Khalil W. Dynamic modeling and simulation of a 3-D hybrid structure eel-like robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 1486–1491, Roma, April, 10-14, 2007.
- [gan-d2016] Gan D., Dias J., and Seneviratne L. Unified kinematics and optimal design of a 3rRPS metamorphic parallel mechanism with a reconfigurable revolute joint. *Mechanism and Machine Theory*, 96:239–254, 2016.
- [gan-j2017] Gan J. and others . Full closed-loop controls of micro/nano positioning system with nonlinear hysteresis using micro-vision system. Sensors and Actuators A, 257:125–133, 2017.
- [gan2009] Gan D. and others . Forward displacement analysis of the general 6-6 Stewart mechanism using Groebner bases. Mechanism and Machine Theory, 44(9):1640-1647, September 2009.
- [gan2010] Gan D.M., Dai J.S., and Caldwelll D.G. Constraint-screw system based synthesis of limb arrangement of the 3-PUP parallel mechanism. In *ARK*, pages 485–492, Piran, June 28- July 1, 2010.
- [gan2010-1] Gan D.M., Dai J.S., and Caldwelll D.G. Design and kinematics analysis of a 3CCC parallel mechanism. *Robotica*, 28(7):1065–1072, December 2010.
- [gan2010-2] Gan D.M., Dai J.S., and Liao Q. Constraint analysis on mobility change of a novel metamorphic parallel mechanism. *Mechanism and Machine Theory*, 45(12):1864–1976, December 2010.
- [gan2013] Gan D.M. and Dai J.S. Geometry constraint and branch motion evolution of 3-PUP parallel mechanism with bifurcated motion. *Mechanism and Machine Theory*, 61:168–183, March 2013.
- [gan2013-1] Gan D.M. and others. Unified kinematics and singularity analysis of a metamorphic parallel mechanism with bifurcated motion. J. of Mechanisms and Robotics, 5(3), August 2013.
- [ganesh2017] Ganesh M. and others . Determination of the closed-form workspace area expression and dimensional optimization of planar parallel manipulators. *Robotica*, 35:2056–2075, 2017.

- [ganesh2021] Ganesh M. and others . Static characteristic analysis of spatial (non-planar) links in planar parallel manipulator. *Robotica*, 39(1):88–105, 2021.
- [ganovski2004] Ganovski I., Fisette P., and Samin J.C. Piecewise overactuation of parallel mechanisms following singular trajectories: modeling, simulation and control. *Multibody System Dynamics*, 12:317–343, 2004.
- [gao-b2011] Gao B. and others. Combined kinematic and static analysis of a cable-driven manipulator with a spring spine. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [gao-g2019] Gao G. and Ye M., M.and Zhang. Synchronous robust sliding mode control of a parallel robot for automobile electro-coating conveying. *IEEE Access*, 2019.
- [gao-l2017] Gao L. and Wu W. Forward kinematics modeling of spatial parallel linkage mechanisms based on constraint equations and the numerical solving method. *Robotica*, 35:293–309, 2017.
- [gao-xz-2005] Gao X-Z. and others . Generalized Stewart-Gough platforms and their direct kinematics. *IEEE Trans. on Robotics*, 21(2):141–151, April 2005.
- [gao-z2010] Gao Z., Zhang D., and Ge Y. Design optimization of a spatial six-degree-of-freedom parallel manipulator based on artificial intelligence approaches. *Robotics and Computer-Integrated Manufacturing*, 26(2):180–189, April 2010.
- [gao-z2010-1] Gao Z. and others . Design, analysis, and stiffness optimization of a three degree of freedom parallel manipulator. *Robotica*, 28(3):349–357, May 2010.
- [gao98] Gao F. and Liu X. Performance evaluation of two-degree-of-freedom planar parallel robots. *Mechanism and Machine Theory*, 33(6):661–668, August 1998.
- [gao2001] Gao F., Liu X-J., and Chen X. The relation ships between the shapes of the workspaces and the link lengths of 3-DOF symmetrical planar parallel manipulators. *Mechanism and Machine Theory*, 36(2):205–220, February 2001.
- [gao2002] Gao F. and others. New kinematic structures for 2-,3-,4- and 5-dof parallel manipulator designs. *Mechanism and Machine Theory*, 37(11):1395–1411, November 2002.
- [gao2005] Gao F., Zhang Y., and Li W. Type synthesis of 3-dof reducible translational mechanisms. *Robotica*, 23(2):239–245, 2005.
- [gao2007] Gao F. and others . The design and applications of f/t sensor based on Stewart platform. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [gaponenko2019] Gaponenko E.V., Malyshev D.I., and Behera L. Determination of output link positioning error of tripod module using numerical method. *Journal of Physics: Conference Series*, 1353:012083, November 2019.
- [garant2017] Garant X. and others. Improving the forward kinematics of cable-driven parallel robots through cable angle sensors. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [garcia-p2018] Garcia P. and others . Access systems to maritime energy production units. Review and new challenges. In *EUCOMES*, pages 181–188, Aachen, September, 4-6, 2018.
- [garcia2002] Garcia E., Zago L., and Gallieni D. Special and innovative aspects of the GTC M2 drive mechanism. In SPIE Astronomical Telescopes and Instrumentation, pages 448–455, Hawaii, August, 22-28, 2002.
- [garcia2011] Garcia C., Saltaren R., and Aracil R. Experiences in the development of a teleoperated parallel robot for aerial line maintenance. *Robotica*, 29(6):873–881, September 2011.
- [garcimurillo2014] Garcia-Murillo A.A. and others . Kinematic and dynamics of a  $3 \underline{RPSR}$  parallel robot used as a pipe-bending machine. In ARK, Ljulbjana, June 29- July 3, 2014.
- [gassert2006] Gassert R. and others . A 2-dof MRI compatible haptic interface to investigate the neural control of arm movements. In *IEEE Int. Conf. on Robotics and Automation*, pages 3825–3831, Orlando, May, 16-18, 2006.
- [gassner2017] Gassner M., Cielewski T., and Scaramuzza D. Dynamic collaboration without communication: vision-based cable-suspended load transport with two quadrotors. In *IEEE Int. Conf. on Robotics and Automation*, Singapore, 2017.

- [gayral2013] Gayral T., Daney D., and Ducarne J. Flexure joints modeling for micrometer accuracy of an active 6-pus space telescope through experimental calibration. In *IEEE Int. Conf. on Robotics and Automation*, pages 4610–4615, Karlsruhe, May, 6-10, 2013.
- [gayral2013-1] Gayral T. and Daney D. Necessary condition for calibration and observation issues. In *Computational Kinematics*, Barcelona, May, 12-15, 2013.
- [gayral2013-2] Gayral T., Daney D., and Bernot M. Model discrepancy in robotic calibration: Its influence on the experimental parameter identification of a parallel space telescope. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 5803–5808, Tokyo, November, 3-7, 2013.
- [gayral2013-phd] Gayral T. Étalonnage d'un télescope d'observation spatial actif. Ph.D. Thesis, Université de Nice-Sophia Antipolis, Nice, November, 29, 2013. **Keywords:** calibration, applications.
- [geike2003] Geike T. and McPhee J. Inverse dynamics analysis of parallel manipulators with full mobility. *Mechanism and Machine Theory*, 38(6):549–562, June 2003.
- [geng-rr-2016] Geng R.R., Mills J.K., and Yao Z-Y. Design and analysis of a novel 3-DOF spatial parallel microgripper driven by lums. *Robotics and Computer-Integrated Manufacturing*, 42:147–155, 2016.
- [geng-rr2016] Geng R-R., Mills J.K., and Yao Z-Y. Design and analysis of a novel 3-dof spatial parallel micromanipulator driven by LUMs. *Robotics and Computer-Integrated Manufacturing*, 42:147–159, 2016.
- [geng-x-2020] Geng X. and others. Analytical tension-distribution computation for cable-driven parallel robots using hypersphere mapping algorithm. *Mechanism and Machine Theory*, 145, 2020.
- [geng90] Geng Z., Haynes L.S., and Carroll R.L. Direct forward kinematic solution of a general Stewart platform. In ISRAM, volume 3, pages 11–17, Burnaby, July, 18-20, 1990.
- [geng91] Geng Z. and Haynes L.S. Neural network for the forward kinematics problem of a Stewart platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 2650–2655, Sacramento, April, 11-14, 1991.
- [geng92] Geng Z. and Haynes L.S. On the dynamic model and kinematic analysis of a class of Stewart platforms. Robotics and Autonomous Systems, 9(4):237–254, 1992.
- [geng93] Geng Z. and Haynes L.S. Six-degree-of-freedom active vibration isolation using a Stewart platform mechanism. J. of Robotic Systems, 10(5):725–744, July 1993.
- [geng94] Geng Z. and Haynes L.S. An effective kinematics calibration method for Stewart platform. In *ISRAM*, pages 87–92, Hawaï, August, 15-17, 1994.
- [geng94-1] Geng Z. and Haynes L.S. A 3-2-1 kinematic configuration of a Stewart platform and its application to six degree of freedom pose measurements. *Robotics and Computer-Integrated Manufacturing*, 11(1):23–34, March 1994.
- [geng94-2] Geng Z. and others . Six degree-of-freedom active vibration isolation and suppression experiments. In 5th Int. Conf. on Adaptive Structures, pages 285–294, Sendai, December, 5-7, 1994.
- [germain2012] Germain C. and others . Constraint singularity-free design of IRSBot-2. In ARK, pages 341–348, Innsbruck, June, 25-28, 2012.
- [germain2012-1] Germain C. and others . IRSBot-2: a novel two-dof parallel robot for high-speed operations. In 35th Mechanisms and Robotics Conference, Parts A and B, 2012.
- [germain2013] Germain C. and others . Singularity-free design of the translational parallel manipulator IRSBot-2. *Mechanism and Machine Theory*, 64:262–285, June 2013.
- [germain2013-phd] Germain C. Conception d'un robot parallèle à deux degrés de liberté pour des opérations de prise et de dépose. Ph.D. Thesis, Ecole Centrale de Nantes, Nantes, December, 9, 2013. **Keywords:** 2 dof robot, mechanical architecture, singularity.
- [germain2015] Germain C. and others . Natural frequency computation of parallel robots. ASME Journal of Computational and Nonlinear Dynamics, 10, 2015.

- [gertlet2013] Gertler I., Shapiro Y., and Wolf A. A haptic surface scanning and machining parallel manipulator for registration-free bone resurfacing during arthroplasty. In *IEEE Int. Conf. on Robotics and Automation*, pages 2339–2344, Karlsruhe, May, 6-10, 2013.
- [gezgin2019] Gezgin E. and others . Structural design of a positioning spherical parallel manipulator to be utilized in brain biopsy. Int J Med Robotics Comput Assist Surg, 15, 2019.
- [gharatappeh2015] Gharatappeh S. and others . Control of cable-driven parallel robot for gait rehabilitation. In 12th International Conference on Ubiquitous Robots and Ambient Intelligence (URAI), Goyang, October, 28-30, 2015.
- [gharatappeh2016] Gharatappeh S. and others. Design of a novel assist-as-needed controller for gait rehabilitation using a cable-driven robot. In 13th International Conference on Ubiquitous Robots and Ambient Intelligence (URAI), Xian, August, 19-22, 2016.
- [ghasemi2008] Ghasemimi A., Eghtesad M., and Farid M. Workspace analysis of planar and spatial redundant cable robots. In *Annual American Control Conference (ACC)*, Seattle, June, 11-13, 2008.
- [ghasemi2008-1] Ghasemimi A., Farid M., and Eghtesad M. Interference free workspace analysis of redundant 3d cable robots. In 2008 World Automation Congress, 2008.
- [ghasemi2008-2] Ghasemimi A., Eghtesad M., and Farid M. Workspace analysis of redundant cable robots. In 2008 World Automation Congress, 2008.
- [ghasemi2010] Ghasemimi A., Eghtesad M., and Farid M. Neural network solution for forward kinematics problem of cable robots. *J. of Intelligent and Robotic Systems*, 60:201–215, 2010.
- [gherman2012] Gherman B. and others . Development of inverse dynamic model for a surgical hybrid parallel robot with equivalent lumped masses. *Robotics and Computer-Integrated Manufacturing*, 28:402–415, 2012.
- [gherman2014] Gherman B. and others . On the kinematics of an innovative parallel robot for brachytherapy. In ARK, Ljulbjana, June 29- July 3, 2014.
- [gherman 2018] Gherman B. and others. A kinematic characterization of a parallel robotic system for lower limb rehabilitation. In 7tht European Conf. on Mechanism Science (Eucomes), Aachen, September, 4-6, 2018.
- [ghobakhloo2005] Ghobakhloo A., , and Eghtesad M. Neural network solution for the forward kinematics problem of a redundant hydraulic shoulder. In 31st Annual Conference of IEEE Industrial Electronics Society, 2005. IECON 2005, 2005.
- [gholami2008] Gholami P., Aref M.M., and Taghirad H.D. On the control of the KNTU CDRPM: A cable driven redundant parallel manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2404—2409, Nice, France, September, 22-26, 2008.
- [ghorbel94] Ghorbel F., Chetélat O., and Longchamp R. A reduced model for constrained rigid bodies with application to parallel robots. In 4th IFAC Symp. on Robot Control, Syroco, pages 57–62, Capri, September, 19-21, 1994.
- [ghorbel2001] Ghorbel F. and others . Experimental validation of a reduced model based tracking control of parallel robots. In *IEEE Int. Conf. on Control Applications*, pages 375–381, Mexico, September, 5-7, 2001.
- [ghosal2001] Ghosal A. and Ravani B. A differential-geometric analysis of singularities of point trajectories of serial and parallel manipulators. ASME J. of Mechanical Design, 123(1):80–89, March 2001.
- [ghosh2016] Ghosh S. and Gan D. Design of passive 3-PRR planar parallel manipulators for self-alignment of exoskeleton axes. In 40th Mechanisms and Robotics Conference, August 2016.
- [giberti2001] Giberti H., Righettini P., and Tasora A. Design and experimental test of a pneumatic translational 3 dof parallel manipulator. In RAAD, Vienna, May, 16-18, 2001.
- [gil2014] Gil A. and others . Implementation and assessment of a virtual laboratory of parallel robots developed for engineering students.  $IEEE\ Trans.\ on\ Education,\ 57(2),\ May\ 2014.$
- [girone 2001] Girone M. and others . A Stewart platform-based system for ankle telerehabilitation.  $Autonomous\ Robots$ , 10(2):203-212, March 2001.

- [glazunov89] Glazunov V.A., Koliskor A.Sh., and Model B.I. Determination of positions of output link of l-coordinate mechanisms. *Soviet Machine Science (Mashinovedenie)*, (3):49–53, 1989.
- [glazunov90] Glazunov V.A. and others. Classification principles and analysis methods for parallel-structure spatial mechanisms. J. of Machinery Manufacture and Reliability, (1):41–49, 1990.
- [glazunov2006] Glazunov V.A. Twists of movements of parallel mechanisms inside their singularities. *Mechanism and Machine Theory*, 41(9):1185–1195, September 2006.
- [glazunov2007] Glazunov V.A. and others. Representations of constraints imposed by kinematic chains of parallel mechanisms. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [glazunov2009] Glazunov V.A. and others. On new class of parallel-cross mechanisms. In *Computational Kinematics*, pages 93–100, Duisburg, May, 6-8, 2009.
- [glazunov2012] Glazunov V.A., Laryushkin P., and Kheylo S. 3-dof translational and rotational parallel manipulators. In 4th European Conf. on Mechanism Science (Eucomes), pages 199–207, Santander, September, 19-21, 2012.
- [gloss2000] Glöss R. Hexapod parallel kinematics with sub-micrometer accuracy. In 2nd Chemnitzer Parallelkinematik Seminar, pages 397–404, Chemnitz, April, 12-13, 2000.
- [glozman2009] Glozman D. and Shoham M. Novel 6-dof parallel manipulator with large workspace. *Robotica*, 27(6):891–895, 2009.
- [godhole2017] Godhole H.A., Caverly R.J., and Forbes J.R. Modelling of flexible cable-drivent parallel robots using a Rayleigh-Ritz approach. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [gogu2004] Gogu G. Structural synthesis of fully-isotropic translational parallel robots via theory of linear transformations. European Journal of Mechanics A/Solids, 23:1021–1039, 2004.
- [gogu2005] Gogu G. Mobility criterion and overconstraints of parallel manipulators. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [gogu2005-1] Gogu G. Fully-isotropic over-constrained parallel wrists with two degrees of freedom. In *IEEE Int. Conf.* on Robotics and Automation, pages 4025–4030, Barcelona, April, 19-22, 2005.
- [gogu2005-2] Gogu G. Mobility of mechanisms: a critical review. *Mechanism and Machine Theory*, 40(10):1068–1097, October 2005.
- [gogu2005-3] Gogu G. Mobility and spatiality of parallel robots revisited via theory of linear transformations. European Journal of Mechanics A/Solids, 24:670–711, 2005.
- [gogu2005-4] Gogu G. Chebychev-Grübler-Kutzbach's criterion for mobility calculation of multi-loop mechanisms revisited via theory of linear transformations. *European Journal of Mechanics A/Solids*, 24:6427-441, 2005.
- [gogu2006] Gogu G. Fully-isotropic parallel manipulators with Schönflies motions and complex legs with rhombus loops. In *IEEE Int. Conf. on Robotics and Automation*, pages 1147–1152, Orlando, May, 16-18, 2006.
- [gogu2006-1] Gogu G. Fully-isotropic parallel manipulators with five degrees of freedom. In *IEEE Int. Conf. on Robotics and Automation*, pages 1141–1146, Orlando, May, 16-18, 2006.
- [gogu2006-2] Gogu G. Fully-isotropic hexapods. In ARK, Ljubljana, June, 26-29, 2006.
- [gogu2007] Gogu G. Fully-isotropic three-degree-of-freedom parallel wrists. In *IEEE Int. Conf. on Robotics and Automation*, pages 895–900, Roma, April, 10-14, 2007.
- [gogu2007-1] Gogu G. Fully-isotropic T2R3-type redundantly-actuated parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3937–3942, San Diego, September, 22-26, 2007.
- [gogu2007-2] Gogu G. Reangularity: cross-coupling kinetostatic index for parallel robots. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [gogu2007-3] Gogu G. Structural synthesis of fully-isotropic parallel robots with Schönflies motions via theory of linear transformations and evolutionary morphology. European Journal of Mechanics A/Solids, 26:242–269, 2007.

- [gogu2008-1] Gogu G. Structural Synthesis Of Parallel Robots, Part 1: Methodology. Kluwer, Dordrecht, 2008. Keywords: structural synthesis.
- [gogu2008] Gogu G. Constraint singularities and the structural parameters of parallel robots. In ARK, pages 21–28, Batz/mer, June, 23-26, 2008.
- [gogu2008-2] Gogu G. Kinematic criteria for structural synthesis of maximally regular parallel robots with planar motion on the moving platform. In 1st Conf. on Interdisciplinary Applications in Kinematics, Lima, January, 9-11, 2008.
- [gogu2009] Gogu G. Structural Synthesis Of Parallel Robots, Part 2: Translational topologies with two and three degrees of freedom. Kluwer, Dordrecht, 2009. **Keywords:** structural synthesis.
- [gogu2009-1] Gogu G. Branching singularities in kinematotropic parallel mechanisms. In *Computational Kinematics*, Duisburg, May, 6-8, 2009.
- [gogu2010] Gogu G. Structural Synthesis Of Parallel Robots, Part 3: Topologies with planar motion of the moving platform. Kluwer, Dordrecht, 2010. **Keywords:** structural synthesis.
- [gogu2012] Gogu G. T2R1-type parallel manipulators with bifurcated planar-spatial motion. European Journal of Mechanics A/Solids, 33:1–41, 2012.
- [gojtan2013] Gojtan G.E.E., Furtado G.P., and Hess-Coelho T.A. Error analysis of a 3-dof parallel mechanism for milling applications. *J. of Mechanisms and Robotics*, 5(3), August 2013.
- [goldsmith2002] Goldsmith P.B. Kinematics and stiffness of a symmetrical 3-UPU translational parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 4102–4106, Washington, May, 11-15, 2002.
- [goldsmith2003] Goldsmith P.B. Design and kinematics of a three-legged parallel manipulator. *IEEE Trans. on Robotics and Automation*, 19(4):727–731, August 2003.
- [goldsztejn2016] Goldsztejn A., Caro S., and Chabert G. A three-step methodology for dimensional tolerance synthesis of parallel manipulators. *Mechanism and Machine Theory*, 105:213–234, 2016.
- [goncalves2008] Gonçalves R.S. and Mendes Carvalho J.C. Stiffness analysis of parallel manipulator using matrix structural analysis. In 2nd European Conf. on Mechanism Science (Eucomes), Cassino, September, 17-20, 2008.
- [gong2007] Gong J., Zhang Y., and Gao F. Type synthesis of parallel robot based on the kinematic element. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [gonzales-rodriguez2017] Gonzales-Rodriguez A. and others . On the effect of the design of cable-driven robot on kinematics. *Mechatronics*, 43:18–27, 2017.
- [gonzales2013] Gonzales-Hernandez A. and Castillo-Castaneda E. Stiffness estimation of a parallel manipulator using image camera calibration techniques. *Robotica*, 31(4):657–667, April 2013.
- [gorguulu2020] Görgulü I., Carbone G., and Can Dede M.I. Time efficient stiffness model computation for a parallel haptic mechanism via the virtual joint method. *Mechanism and Machine Theory*, 143, 2020.
- [gorman2001] Gorman J.J., Jablokow K.W., and Cannon D.J. The Cable Array Robot: theory and experiment. In *IEEE Int. Conf. on Robotics and Automation*, pages 2804–2810, Seoul, May, 23-25, 2001.
- [gosh2015] Gosh B.B., Sarkar B.K., and Saha R. Realtime performance analysis of different combinations of fuzzy-PID and bias controllers for a two degree of freedom electrohydraulic parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 34:62–69, August 2015.
- [gosselin-f-2001] Gosselin F. and Lallemand J-P. A new insight into the duality between serial and parallel non-redundant and redundant manipulators. *Robotica*, 19(4):365–370, July 2001.
- [gosselin-f-2008] Gosselin F. and others . Large workspace haptic devices for human-scale interaction: a survey. In EuroHaptic, 2008.

- [gosselin-f-2011] Gosselin F. and others . Specification and design of a new haptic interface for maxillo facial surgery. In *IEEE Int. Conf. on Robotics and Automation*, pages 737–744, Shangai, May, 9-13, 2011.
- [gosselin88] Gosselin C. and Angeles J. The optimum kinematic design of a planar three-degree-of-freedom parallel manipulator. J. of Mechanisms, Transmissions and Automation in Design, 110(1):35–41, March 1988.
- [gosselin88-phd] Gosselin C. Kinematic analysis optimization and programming of parallel robotic manipulators. Ph.D. Thesis, McGill University, Montréal, June, 15, 1988. **Keywords:** mechanical architecture, optimal design, planar robot, kinematics, spherical robot, workspace.
- [gosselin89] Gosselin C. Determination of the workspace of 6-dof parallel manipulators. In ASME Design Engineering Technical Conference, pages 321–326, Montréal, September, 17-20, 1989.
- [gosselin89-1] Gosselin C. and Angeles J. The optimum kinematic design of a spherical three-degree-of-freedom parallel manipulator. J. of Mechanisms, Transmissions and Automation in Design, 111(2):202–207, 1989.
- [gosselin90] Gosselin C. Stiffness mapping for parallel manipulators. *IEEE Trans. on Robotics and Automation*, 6(3):377–382, June 1990.
- [gosselin90-1] Gosselin C. Determination of the workspace of 6-dof parallel manipulators. ASME J. of Mechanical Design, 112(3):331–336, September 1990.
- [gosselin90-2] Gosselin C. and Angeles J. Singularity analysis of closed-loop kinematic chains. *IEEE Trans. on Robotics and Automation*, 6(3):281–290, June 1990.
- [gosselin90-3] Gosselin C. and Angeles J. Kinematic inversion of parallel manipulators in the presence of incompletely specified tasks. ASME J. of Mechanical Design, 112(4):494–500, December 1990.
- [gosselin92] Gosselin C., Sefrioui J., and Richard M.J. Solution polynomiale au problème de la cinématique directe des manipulateurs parallèles plans à 3 degrés de liberté. *Mechanism and Machine Theory*, 27(2):107–119, March 1992.
- [gosselin92-1] Gosselin C. and Lavoie E. Spherical parallel manipulators: dexterity and isotropy. In ARK, pages 143–149, Ferrare, September, 7-9, 1992.
- [gosselin92-2] Gosselin C. and Sefrioui J. Determination of the singular loci of spherical 3 d.o.f parallel manipulators. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 329–336, Scottsdale, September, 13-16, 1992.
- [gosselin92-3] Gosselin C., Lavoie E., and Toutant P. An efficient algorithm for the graphical representation of the three-dimensional workspace of parallel manipulators. In 22nd Biennial Mechanisms Conf., pages 323–328, Scottsdale, September, 13-16, 1992.
- [gosselin92-4] Gosselin C., Sefrioui J., and Richard M.J. On the direct kinematics of a class of spherical three-degree-of-freedom parallel manipulators. In 22nd Biennial Mechanisms Conf., pages 13–19, Scottsdale, September, 13-16, 1992.
- [gosselin92-5] Gosselin C., Sefrioui J., and Richard M.J. On the direct kinematics of general spherical three-degree-of-freedom parallel manipulators. In 22nd Biennial Mechanisms Conf., pages 7–11, Scottsdale, September, 13-16, 1992.
- [gosselin93] Gosselin C.M and Lavoie E. On the kinematic design of spherical three-degree-of-freedom parallel manipulators. *Int. J. of Robotics Research*, 12(4):394–402, August 1993.
- [gosselin94] Gosselin C. and Merlet J-P. On the direct kinematics of planar parallel manipulators: special architectures and number of solutions. *Mechanism and Machine Theory*, 29(8):1083–1097, November 1994.
- [gosselin94-1] Gosselin C. and Hamel J.-F. The Agile Eye: A high performance three-degree-of-freedom cameraorienting device. In *IEEE Int. Conf. on Robotics and Automation*, pages 781–787, San Diego, May, 8-13, 1994.
- [gosselin94-2] Gosselin C. and Hamel J.-F. Development and experimentation of a fast three-degree-of-freedom spherical parallel manipulator. In *ISRAM*, pages 229–234, Hawaï, August, 14-18, 1994.

- [gosselin94-3] Gosselin C., Perreault T., and Vaillancourt C. Smaps: a computer-aided design package for the analysis and optimization of a spherical parallel manipulators. In *ISRAM*, pages 115–120, Hawaï, August, 14-18, 1994.
- [gosselin94-4] Gosselin C., Sefrioui J., and Richard M.J. On the direct kinematics of spherical three-degree-of-freedom parallel manipulators with a coplanar platform. ASME J. of Mechanical Design, 116(2):587–593, June 1994.
- [gosselin94-5] Gosselin C., Cloutier C., and Rancourt D. Kinematic analysis of spherical two degree-of-freedom parallel manipulators. In ASME 23rd Biennal Mechanisms Conf., pages 255–262, Minneapolis, September, 11-14, 1994.
- [gosselin94-6] Gosselin C., Sefrioui J., and Richard M.J. On the direct kinematics of spherical three-degree-of-freedom parallel manipulators of general architecture. ASME J. of Mechanical Design, 116(2):594–598, June 1994.
- [gosselin95] Gosselin C. and Gagné M. A closed-form solution for the direct kinematics of a special class of spherical three-degree-of-freedom parallel manipulators. In J-P. Merlet B. Ravani, editor, *Computational Kinematics*, pages 231–240. Kluwer, 1995. **Keywords:** spherical robot, forward kinematics, 3 dof robot, wrist.
- [gosselin95-1] Gosselin C. and Wang J. Singularity loci of planar parallel manipulator. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1982–1986, Milan, August 30- September 2, 1995.
- [gosselin95-2] Gosselin C., Perreault L., and Vaillancourt C. Simulation and computer-aided kinematic design of three-degree-of-freedom spherical parallel manipulators. *J. of Robotic Systems*, 12(12):857–869, 1995.
- [gosselin96] Gosselin C. Kinematische und statische analysis eines ebenen parallelen manipulators mit dem freiheitgrad zwei. *Mechanism and Machine Theory*, 31(2):149–160, February 1996.
- [gosselin96-1] Gosselin C., Lemieux S., and Merlet J-P. A new architecture of planar three-degree-of-freedom parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3738–3743, Minneapolis, April, 24-26, 1996.
- [gosselin96-2] Gosselin C. Parallel computational algorithms for the kinematics and dynamics of planar and spatial parallel manipulators. ASME J. of Dynamic Systems, Measurement and Control, 118(1):22–28, March 1996.
- [gosselin97] Gosselin C. and Wang J. Singularity loci of planar parallel manipulators with revolute actuators. *Robotics and Autonomous Systems*, 21(4):377–398, October 1997.
- [gosselin97-1] Gosselin C. and St-Pierre E. Development and experimentation of a fast 3-dof orienting device. *Int. J. of Robotics Research*, 16(15):619–630, October 1997.
- [gosselin98] Gosselin C. and Wang J. On the design of gravity-compensated six-degree-of-freedom parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 2287–2294, Louvain, May, 18-20, 1998.
- [gosselin98-1] Gosselin C. and Wang J. On the design of statically balanced motion bases for flight simulators. In AIAA, Flight Simulation Technologies Conference, pages 272–282, Boston, August, 21-24, 1998.
- [gosselin99] Gosselin C.M. and others . On the design of a statically balanced 6-dof parallel manipulator. In 10th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1045–1050, Oulu, June, 20-24, 1999.
- [gosselin99-1] Gosselin C.M. Static balancing of spherical 3-dof parallel mechanisms and manipulators. *Int. J. of Robotics Research*, 18(8):812–829, August 1999.
- [gosselin2000] Gosselin C.M. and Wang J. Static balancing of spatial six-degree-of-freedom parallel mechanisms with revolute actuators. *J. of Robotic Systems*, 17(3):159–170, 2000.
- [gosselin2002] Gosselin C.M. and Wu Y. On the development of reactionless spatial 3-dof parallel-piped mechanisms. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [gosselin2002-1] Gosselin C.M. and Wang J. Singulariti loci of a special class of spherical three degree-of-freedom parallel mechanism with revolute actuators. *Int. J. of Robotics Research*, 21(7):649–659, July 2002.
- [gosselin2004] Gosselin C.M. and others . Synthesis and design of reactionless three-degree-of-freedom mechanisms.  $IEEE\ Trans.\ on\ Robotics\ and\ Automation,\ 20(2):191-199,\ April\ 2004.$

- [gosselin 2007] Gosselin C.M. and others. Parallel mechanisms of the Multipteron family: kinematic architectures and benchmarking. In *IEEE Int. Conf. on Robotics and Automation*, pages 555–560, Roma, April, 10-14, 2007.
- [gosselin2010] Gosselin C., Lefrancois S., and Zoso N. Underactuated cable-driven robots: machine, control and suspended bodies. In *Brain, Body and Machine*, pages 311–323, McGill, 2010.
- [gosselin2011] Gosselin C. and Grenier M. On the determination of the force distribution in overconstrained cable-driven parallel mechanisms. *Meccanica*, 46:3–15, 2011.
- [gosselin2012] Gosselin C.M., Ren P., and Foucault S. Dynamic trajectory planning of a two-dof cable-suspended parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 1476–1481, Saint Paul, May, 14-18, 2012.
- [gosselin2012-1] Gosselin C.M. Global planning of dynamically feasible trajectories for three-dof spatial cable-suspended parallel robots. In 1st Int. Conf. on cable-driven parallel robots (CableCon), pages 3–22, Stuttgart, September, 3-4, 2012.
- [gosselin2014] Gosselin C.M. and Foucault S. Experimental determination of the accuracy of a three-dof cable-suspended parallel robot performing dynamic trajectories. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 3–16, Duisburg, August, 24-27, 2014.
- [gosselin2015] Gosselin C., Laliberté T., and Veillette A. Singularity-free kinematically redundant planar parallel mechanism with unlimited rotational capability. *IEEE Trans. on Robotics*, 31(2):457–467, April 2015.
- [gosselin2014-1] Gosselin C. Cable-driven parallel mechanisms: state of the art and perspectives. Bulletin of the JSME, 1(1), 2014.
- [gosselin2016] Gosselin C. and Schreiber L-T. Kinematically redundant spatial parallel mechanisms for singularity avoidance and large orientational workspace. *IEEE Trans. on Robotics*, 32(2):286–300, April 2016.
- [gosselin2016-1] Gosselin C. and others. Workspace and sensitivity analysis of a novel nonredundant parallel scara robot featuring infinite tool rotation. *IEEE Robotics and Automation Letters*, 1(2), 2016.
- [gosselin2018] Gosselin C and Schreiber L-T. Redundancy in parallel mechanisms: A review. *Applied Mechanics Reviews*, 70(1), January 2018.
- [goswami91] Goswami A. and Peshkin M.A. A task-space formulation of passive force control. In *IEEE Int. Symp.* on *Intelligent Control*, pages 95–100, Arlington, August, 13-15, 1991.
- [goswami99] Goswami A. and Peshkin M.A. Mechanically implementable accommodation matrices for passive force control. *Int. J. of Robotics Research*, 18(7), 1999.
- [gotelli<br/>2022] Gotelli A. and others . A Gazebo simulator for continuum parallel robots. In<br/> ARK, Bilbao, June, 26-30, 2022.
- [goudali95] Goudali A., Lallemand J-P., and Zeghloul S. Espace de travail de la nouvelle structure 2-Delta. Revue d'Automatique et de Productique Appliquée, 8(2-3):205–210, 1995.
- [goudali96] Goudali A., Lallemand J-P., and Zeghloul S. Modeling of the 2-Delta 6-dof decoupled parallel robot. In 6th ISRAM, pages 243–248, Montpellier, May, 28-30, 1996.
- [gough56] Gough V.E. Contribution to discussion of papers on research in automobile stability, control and tyre performance, 1956-1957. Proc. Auto Div. Inst. Mech. Eng. **Keywords:** mechanical architecture, applications.
- [gough62] Gough V.E. and Whitehall S.G. Universal tyre test machine. In *Proceedings 9th Int. Technical Congress F.I.S.I.T.A.*, volume 117, pages 117–135, London, May 1962.
- [gouttefarde2004] Gouttefarde M. and Gosselin C.M. On the properties and determination of the wrench-closure workspace of planar parallel cable-driven manipulator. In ASME Design Engineering Technical Conference, Salt Lake City, September 28- October 2, 2004.
- [gouttefarde2005-phd] Gouttefarde M. Analyse de l'espace des poses polyvalentes des mécanismes paralleèles entraînés par câbles. Ph.D. Thesis, Université Laval, Québec, 2005. **Keywords:** wire robot, workspace.

- [gouttefarde2006] Gouttefarde M., Merlet J-P., and Daney D. Determination of the wrench-closure workspace of 6-dof parallel cable-driven mechanisms. In ARK, pages 315–322, Ljubljana, June, 26-29, 2006.
- [gouttefarde2006-1] Gouttefarde M. and Gosselin C.M. Analysis of the wrench-closure workspace of planar parallel cable-driven mechanisms. *IEEE Trans. on Robotics*, 22(3):434–445, 2006.
- [gouttefarde 2007] Gouttefarde M., Merlet J-P., and Daney D. Wrench-feasible workspace of parallel cable-driven mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 1492–1497, Roma, April, 10-14, 2007.
- [gouttefarde2011] Gouttefarde M., Daney D., and Merlet J-P. Interval-analysis based determination of the wrench-feasible workspace of parallel cable-driven robots. *IEEE Trans. on Robotics*, 27(1):1–13, February 2011.
- [gouttefarde2014] Gouttefarde M., Nguyen D.Q., and Baradat C. Kinetostatics analysis of cable-driven parallel robots with consideration of sagging and pulleys. In ARK, pages 213–221, Ljulbjana, June 29- July 3, 2014.
- [gouttefarde 2015] Gouttefarde M., Collard J.F., Riehl N., and Baradat C. Geometry selection of a redundantly actuated cable-suspended parallel robot. *IEEE Trans. on Robotics*, 31(2):501–510, April 2015.
- [gouttefarde 2015-1] Gouttefarde M. and others . A versatile tension distribution algorithm for n-dof parallel robots driven by n+2 cables. *IEEE Trans. on Robotics*, 31(6), December 2015.
- [gouttefarde2016-h] Gouttefarde M. Analysis and synthesis of large-dimension cable-driven parallel robots, November, 21, 2016. Habilitation à diriger les recherches, Université Montpellier. **Keywords:** wire robot.
- [gouttefarde2010] Gouttefarde M. and Krut S. Characterization of parallel manipulator available wrench set facets. In ARK, pages 475–484, Piran, June 28- July 1, 2010.
- [gouttefarde2012] Gouttefarde M. and others . Simplified static analysis of large-dimension parallel cable-driven robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 2299–2305, Saint Paul, May, 14-18, 2012.
- [grace93] Grace K.W. and others . A six degree of freedom micromanipulator for opthalmic surgery. In *IEEE Int. Conf. on Robotics and Automation*, pages 630–635, Atlanta, May, 2-6, 1993.
- [graf97] Graf R. and Dillmann R. Active acceleration using a Stewart-platform on a mobile robot. In 2nd EUROMI-CRO Workshop on Advanced Mobile Robots, pages 59–64, Brescia, October, 22-24, 1997.
- [graf98] Graf R., Vierling R., and Dillmann R. A flexible controller for a Stewart platform. In 2nd Int. Conf. on knowledge-based intelligent electronic Systems, pages 52–59, Adelaide, April, 21-23, 1998.
- [graham2006] Graham A.E. and others. Design of a parallel long bone fracture reduction robot with planning treatment tool. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Beijing, October, 9-15, 2006.
- [grandon2007] Grandón C., Daney D., Papegay Y., and others . Certified pose determination under uncertainties. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [grant95] Grant D. and Hayward V. Design of shape memory alloy actuator with high strain and variable structure control. In *IEEE Int. Conf. on Robotics and Automation*, pages 2305–2312, Nagoya, May, 25-27, 1995.
- [griffis89] Griffis M. and Duffy J. A forward displacement analysis of a class of Stewart platform. *J. of Robotic Systems*, 6(6):703–720, 1989.
- [griffis94] Griffis M., Crane C., and Duffy J. A smart kinestatic interactive platform. In ARK, pages 459–464, Ljubljana, July, 4-6, 1994.
- [grimbert87] Grimbert D. and Marchal P. Dynamic testing of a docking system. In First European In-Orbit Operations Technology Symposium, pages 281–288, Darmstadt, September, 7-9, 1987.
- [grimstad2017] Grimstad L. and others . Kinematic modeling and control design of a novel single-rail parallel arm. In 20th IFAC World Congress, 2017.
- [gronbach2002] Gronbach H. Tricenter- a universal milling machine with hybrid kinematics. In 3rd Chemnitzer Parallelkinematik Seminar, pages 595–608, Chemnitz, April, 23-25, 2002.

- [grosch2010] Grosh P. and others. Motion planning for a novel reconfigurable parallel manipulator with lockable revolute joints. In *IEEE Int. Conf. on Robotics and Automation*, pages 4697–4702, Anchorage, May, 3-8, 2010.
- [grosch2013] Grosh P. and Thomas F. A bilinear formulation for the planning of non holonomic parallel orienting platform. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 953–958, Tokyo, November, 3-7, 2013.
- [grosch2016] Grosch P. and Thomas F. Geometric path planning without maneuvers for nonholonomic parallel orienting robots. *IEEE Robotics and Automation Letters*, 1(2), 2016.
- [grosch2016-phd] Grosh P. Parallel robots with unconventional joints to achieve under-actuation and reconfigurability. Ph.D. Thesis, Universitat Politècnica de Catalunya, Barcelone, June 2016. **Keywords:** mechanical architecture.
- [grotjahn2004] Grotjahn M., Heimann B., and Abdellatif H. Identification of friction and rigid-body dynamics of parallel kinematic sructures for model-based control. *Multibody System Dynamics*, 11(3):273–294, April 2004.
- [grunewald84] Grunewald P. Car body painting with the spine spray system. In 14th Int. Symp. on Industrial Robots (ISIR), pages 633–641, Gothenburg, 1984.
- [guay2013] Guay F. and otehrs. Measuring how well a structure supports varying external wrenches. In Second Conference on Mechanisms, Transmissions and Applications (MeTrApp 2013), Bilbao, October 2013.
- [guegan2002] Guégan S. and Khalil W. Dynamic modeling of the Orthoglide. In ARK, pages 387–396, Caldes de Malavalla, June 29- July 2, 2002.
- [guegan2003-phd] Guégan S. Contribution à la modélisation et l'identification dynamique des robots parallèles. Ph.D. Thesis, Ecole Centrale de Nantes, Nantes, December, 5, 2003. **Keywords:** dynamics, calibration.
- [gueners2020] Gueners D., Chanal H., and Bouzgarrou B.C. Stiffness optimization of a cable driven parallel robot for additive manufacturing. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [guglielmetti94] Guglielmetti P. and Longchamp R. A closed-form inverse dynamics model of the Delta parallel robot. In 4th IFAC Symp. on Robot Control, Syroco, pages 51–56, Capri, September, 19-21, 1994.
- [guglielmetti94-phd] Guglielmetti P. Model-Based control of fast parallel robots: a global approach in operational space. Ph.D. Thesis, EPFL, Lausanne, March, 24, 1994. **Keywords:** dynamics,hardware.
- [guo-f2019] Guo F. and others . Interior singularity analysis for a (2(3HUS+S) parallel manipulator with descending matrix rank method. *International Journal of Advanced Robotic Systems*, 2019.
- [guo-f2021] Guo F., Cheng G., and Yuan X. Fatigue life and reliability analysis of a parallel hip joint simulator. *Robotica*, 39:2079–2093, 2021.
- [guo-h2008] Guo H. and others . Cascade control of a hydraulically driven 6-dof parallel robot manipulator based on a sliding mode. *Control Eng. Practice*, 16(9):1055–1068, September 2008.
- [guo-j2008] Guo J. and others . Analysis and the processing of the dexterity of parallel robot based on Matlab. In *ICIRA*, pages 208–215, Wuhan, October, 15-17, 2008.
- [guo-j2014] Guo J. and others. A ship active vibration isolation system based on a novel 5-dof parallel mechanism. In *International Conference on Information and Automation (ICIA)*, 2014.
- [guo-k2016] Guo K. and others . A monolithic adjusting mechanism for optical element using a modified 6-PSS parallel mechanism. Sensors and Actuators A, 251:1–9, 2016.
- [guo-s2016] Guo S. and others . A serial of novel four degrees of freedom parallel mechanisms with large rotational workspace. Robotica, 34(4):764-776, April 2016.
- [guo2006] Guo Z., McInroy J.E., and Jafari F. Realization of micromanipulating Gough-Stewart platforms with desired dynamics. In *IEEE Int. Conf. on Robotics and Automation*, pages 655–660, Orlando, May, 16-18, 2006.

- [guozhen92] Guozhen W. Forward displacement analysis of a class of the 6-6 Stewart platforms. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 113–117, Scottsdale, September, 13-16, 1992.
- [gupta2008] Gupta A. and others . Design, control and performance of RiceWrist: a force feedback wrist exoskeleton for rehabilitation and training. *Int. J. of Robotics Research*, 27(2):233–251, February 2008.
- [gwinnett31] Gwinnett J.E. Amusement device, January, 20, 1931. United States Patent n° 1,789,680. **Keywords:** applications, patent.
- [hadden-2001] Hadden S. and others. Ultraquiet platform for active vibration isolation. In *SPIE Smart structures* and *Materials*, pages 171–182, Newport Beach, March, 4-8, 2001.
- [hadorn2002] Hadorn M. Concept and application of a model-based control input compensation for parallel-kinematic machine tools. In 3rd Chemnitzer Parallelkinematik Seminar, pages 351–369, Chemnitz, April, 23-25, 2002.
- [hafez2003] Hafez M., Lichter M.D., and Dubowsky S. Optimized binary modular reconfigurable robotic devices. IEEE/ASME Trans. on Mechatronics, 8(1):152–162, March 2003.
- [hahn-h2005"] Hahn H. Mathematical modeling, control, computer simulation and laboratory experiments of a spatial servopneumatic parallel robot part i mathematical models, controllers, and computer simulations. *Nonlinear Dynamics*, 40:387–417, 2005.
- [hahn-h2006"] Hahn H. and Neumann M. Mathematical modeling, control, computer simulation and laboratory experiments of a spatial servopneumatic parallel robot part ii: Robot construction and laboratory experiments. *Nonlinear Dynamics*, 45:207–226, 2006.
- [hahn-h99"] Hahn H., Lier W., and Leimbach K-D. Nonlinear control of planar parallel robots with redundant servopneumatic actuators. Z. Angew. Math. Mech. (ZAMM), 79, 1999.
- [hahn87] Hahn S. and Kalb E. The Daimler-Benz driving simulator set-up and results of first experiments. In *Summer Computer Simulation Conf.*, pages 993–997, Montréal, July, 23-30, 1987.
- [hamid2009] Hamid S.A. and Simaan N. Design and synthesis of wire-actuated universal-joint wrists for surgical applications. In *IEEE Int. Conf. on Robotics and Automation*, pages 1807–1813, Kobe, May, 14-16, 2009.
- [hamlin94] Hamlin G.J. and Sanderson A.C. A novel concentric multilink spherical joint with parallel robotics applications. In *IEEE Int. Conf. on Robotics and Automation*, pages 1267–1272, San Diego, May, 8-13, 1994.
- [hamlin97] Hamlin G.J. and Sanderson A.C. Tetrobot: a modular approach to parallel robotics. *IEEE Robotics and Automation Magazine*, 4(1):42–50, March 1997.
- [han-c-2002] Han C. and others . Kinematic sensitivity analysis of the 3-UPU parallel manipulator. *Mechanism and Machine Theory*, 37(8):787–798, August 2002.
- [han-g2020] Han G. and others . Technology-oriented synchronous optimal design of a 4-degrees-of-freedom high-speed parallel robot. ASME J. of Mechanical Design, 142, October 2020.
- [han-h2019] Han H. and others . Kinematics analysis and testing of novel  $6 \underline{P} RR R RR$  parallel platform with offset RR-joints. Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science, 233(10), 2019.
- [han-je2013] Han J-E., Kim D., and Yun K-S. All-polymer hair structure with embedded three-dimensional piezore-sistive force sensors. *Sensors and Actuators A*, 188:89–94, December 2012.
- [han-k95] Han K., W. Chung, and Youm Y. Local structurization for the forward kinematics of parallel manipulators using extra sensor data. In *IEEE Int. Conf. on Robotics and Automation*, pages 514–520, Nagoya, May, 25-27, 1995.
- [han-k96] Han K., W. Chung, and Youm Y. New resolution scheme of the forward kinematics of parallel manipulators using extra sensor data. ASME J. of Mechanical Design, 118(2):214–219, June 1996.
- [han-l2000] Han L., Liao Q., and Liang C. Forward displacement analysis of one kind of general 5-5 parallel manipulators. *Mechanism and Machine Theory*, 35(2):271–289, February 2000.

- [han89] Han C-S, Tesar D., and Traver A. The optimum design of a 6 dof fully parallel micromanipulator for enhanced robot accuracy. In ASME Design Automation Conf., pages 357–363, Montréal, September, 17-20, 1989.
- [han91] Han C-S., Hudgens J.C., Tesar D., and Traver A.E. Modeling, synthesis, analysis and design of high resolution micromanipulator to enhance robot accuracy. In *IEEE Int. Conf. on Intelligent Robot and Systems (IROS)*, pages 1153–1162, Osaka, November, 3-5, 1991.
- [hanahara2003] Hanahara K. and Tada Y. Dynamic behavior of truss-type parallel mechanism with actuated wire members. In 11th ICAR, pages 1793–1798, Coimbra, June 30- July 3, 2003.
- [hao-j2013] Hao J. and others . Modeling, control and software implementation of astronomical tracking of focus cabin suspension of FAST. In *International Conference on Robotics and Biomimetics*, Shenzhen, December 2013.
- [hao-r2016] Hao R., Wang J., Zhao J., and Wang S. Observer-based robust control of 6-dof parallel electrical manipulator with fast friction estimation. *IEEE Trans. on Automation Science and Engineering*, 13(3):1399–1408, July 2016.
- [hao98] Hao F. and McCarthy J.M. Conditions for line-based singularities in spatial platform manipulators. *J. of Robotic Systems*, 15(1):43–55, 1998.
- [haog2014] Hao G. and Kong X. Non linear analytical modeling and characteristics analysis of symmetrical wire beam based composite compliant parallel modules for planar motion. *Mechanism and Machine Theory*, 77:122–147, 2014.
- [haog2015] Hao G. and Li H. Design of 3-legged XYZ compliant parallel manipulators with minimized parasitic rotations. *Robotica*, 33(4):787–806, May 2015.
- [haog2016] Hao G. and Yu J. Design, modelling and analysis of a completely-decoupled xy compliant parallel manipulator. *Mechanism and Machine Theory*, 102:179–185, 2016.
- [haouas 2019] Haouas W. and others. Kinematics, design and experimental validation of a novel parallel robot for two-fingered dexterous manipulation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Macau, November, 4-8, 2019.
- [hara89] Hara A. and Sugimoto K. Synthesis of parallel micromanipulators. J. of Mechanisms, Transmissions and Automation in Design, 111(1):34–39, March 1989.
- [harada2009] Harada T. and Nagase M. Configurations and mathematical models of parallel link mechanisms using multi drive linear motors. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, St Louis, October, 11-15, 2009.
- [harib-kh2012] Harib K.H., Sharrif Ullah A.M.M., and Moustafa K.A.F. Optimal design for improved hybrid kinematic machine-tools structure. In 8th CIRP International Conference on Intelligent Computation in Manufacturing Engineering, pages 109–114, Ischia, July, 18-20, 2012.
- [harib2003] Harib K. and Srinivasan K. Kinematic and dynamic analysis of Stewart platform-based machine tool structures. *Robotica*, 21(5):541–554, October 2003.
- [harris95] Harris D.M.J. A hydraulic parallel-linkage robot. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1695–1699, Milan, August 30- September 2, 1995.
- [harris95-1] Harris D.M.J. Parallel-linkage robot coordinate transformation through screw theory. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1565–1568, Milan, August 30- September 2, 1995.
- [harris2007] Harris D.M.J. Direct motion of a parallel-linkage robot through the jacobian. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [harshe2012-phd] Harshe M. Analyse et conception d'un système de rééducation de membres inférieurs reposant sur un robot parallèle à câbles. Ph.D. Thesis, Université de Nice, Nice, November 2012. **Keywords:** wire robot,medical.

- [hashimoto92] Hashimoto M. and Imamura Y. Design and simulation of a parallel link compliant wrist. In IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems, pages 439–444, Kobe, September, 16-20, 1992.
- [hashimoto94] Hashimoto M. and Imamura Y. Design and characteristics of a parallel link compliant wrist. In *IEEE Int. Conf. on Robotics and Automation*, pages 2457–2462, San Diego, May, 8-13, 1994.
- [hashimoto2007] Hashimoto K. and others . Optimization design of a Stewart platform type leg mechanism for biped walking vehicle. In 13th ISRR, pages 209–218, Hiroshima, September, 26-29, 2007.
- [haslinger 2013] Haslinger R., Leyendecker, and Seibold U. A fiberoptic force-torque-sensor for minimally invasive robotic surgery. In *IEEE Int. Conf. on Robotics and Automation*, pages 4375–4380, Karlsruhe, May, 6-10, 2013.
- [hassan2004] Hassan M. and Notash L. Analysis of active joint failure in parallel robot manipulators. ASME J. of Mechanical Design, 126(6):959–968, November 2004.
- [hassan2005] Hassan M. and Notash L. Design modification of parallel manipulators for optimum fault tolerance to joint jam. *Mechanism and Machine Theory*, 40(5):559–577, May 2005.
- [hassan2007] Hassan M. and Notash L. Optimizing fault tolerance to joint jam in the design of parallel robot manipulators. *Mechanism and Machine Theory*, 42(10):1401–1417, October 2007.
- [hassan2007-1] Hassan M. and Khajepour A. Minimum-norm solution for the actuator forces in cable-based parallel manipulators based on convex optimization. In *IEEE Int. Conf. on Robotics and Automation*, pages 1498–1503, Roma, April, 10-14, 2007.
- [hassan2008] Hassan M. and Khajepour A. Layout and force optimisation in cable-driven parallel manipulators, chapter 5, pages 1–25. Springer, 2008. **Keywords:** wire robot, statics, optimal design.
- [hassan2008-1] Hassan M. and Khajepour A. Optimization of actuator forces in cable-based parallel manipulators using convex analysis. *IEEE Trans. on Robotics*, 34(3), June 2008.
- [hassan2011] Hassan M. and Khajepour A. Analysis of bounded cable tensions in cable-actuated parallel manipulators. *IEEE Trans. on Robotics*, 27(5), October 2011.
- [hassanzadeh2014] Hassanzadeh H.R. and others . An interval-valued fuzzy controller for complex dynamical systems with application to a 3-PSP parallel robot. Fuzzy Sets and Systems, 235:83–100, 2014.
- [hatip95] Hatip O.E. and Ozgoren M.K. Utilization of a Stewart platform mechanism as a stabilizator. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1393–1396, Milan, August 30- September 2, 1995.
- [haugh95] Haugh E.J., Adkins F.A., and Luh C.M. Domain of operation and interference for bodies in mechanisms and manipulators. In J-P. Merlet B. Ravani, editor, *Computational Kinematics*, pages 193–202. Kluwer, 1995. **Keywords:** workspace.
- [haugh98] Haugh E.J., Adkins F.A., and Luh C.M. Operational envelopes for working bodies of mechanisms and manipulators. ASME J. of Mechanical Design, 120(1):84–91, March 1998.
- [hay2000] Hay A.M. and Snyman J.A. The determination of non convex workspaces of generally constrained planar Stewart platforms. *Computers and Mathematics with Applications*, 40(8-9):1043–1060, November 2000.
- [hay2002] Hay A.M. and Snyman J.A. The optimal synthesis of parallel manipulators for desired workspace. In ARK, pages 337–346, Caldes de Malavalla, June 29- July 2, 2002.
- [hay2002-1] Hay A.M. and Snyman J.A. The synthesis of parallel mnaipulator for a prescribed workspace. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [hayawi2016] Hayawi M.J. and others . Kinematic and dexterity analysis of a 3-dof parallel manipulator. *Journal of Applied Sciences, Engineering and Technology*, 12(2):239–248, November 2000.
- [hayes96] Hayes M.J.D. and Zsombor-Murray P.J. Kinematic mapping of 3-legged planar platform with holonomic higher pair. In *ARK*, pages 421–430, Portoroz-Bernadin, June, 22-26, 1996.

- [hayes98] Hayes M.J.D. and Zsombor-Murray P.J. Inverse kinematics of a planar manipulator with holonomic higher pairs. In ARK, pages 59–68, Strobl, June 29- July 4, 1998.
- [hayes99] Hayes M.J.D., Husty M.L., and Zsombor-Murray P.J. Solving the forward kinematics of a planar three-legged platform with holonomic higher pairs. ASME J. of Mechanical Design, 121(2):212–219, June 1999.
- [hayes2000] Hayes M.J.D. and Husty M.L. Workspace characterization of planar three-legged platforms with holonomic higher pairs. In *ARK*, pages 267–276, Piran, June, 25-29, 2000.
- [hayes2003] Hayes M.J.D. and Husty M.L. On the kinematic constraint surfaces of general three-legged planar robot platforms. *Mechanism and Machine Theory*, 38(5):379–394, May 2003.
- [haynes93] Haynes L.S., Geng Z., and Teter J. A new Terfenol-D actuator design with applications to multiple DOF active vibration control. In *SPIE Smart structures and Intelligent systems*, pages 919–928, Albuquerque, February, 1-4, 1993.
- [hayward89] Hayward V. and Kurtz R. Preliminary study of serial-parallel redundant manipulator. In NASA Conference on Space Telerobotics, pages 39–48, Pasadena, January, 31, 1989.
- [hayward89-1] Hayward V. and Kurtz R. Modeling of a parallel wrist with actuator redundancy. Research Report CIM-S9-4, Université McGill, MCRCIM, Montréal, January 1989.
- [hayward90] Hayward V. and Kurtz R. Modeling of a parallel wrist with actuator redundancy. In ARK, pages 1–13, Linz, September, 10-12, 1990.
- [hayward93] Hayward V. and others . Kinematic decoupling in mechanisms and application to a passive hand controller design. *J. of Robotic Systems*, 10(5):767–790, July 1993.
- [hayward93-1] Hayward V. Design of a hydraulic robot shoulder based on a combinatorial mechanism. In *ISER*, pages 297–309, Kyoto, September, 28-30, 1993.
- [hayward94] Hayward V. Design and multi-objective optimization of a linkage for haptic interface. In ARK, pages 359–368, Ljubljana, July, 4-6, 1994.
- [hayward95] Hayward V. Toward a seven axis haptic device. In IROS, pages 133–139, Pittsburgh, August 1995.
- [he-b2014] He B. and others . Workspace analysis of a novel underactuated robot wrist based on virtual prototyping. The International Journal of Advanced Manufacturing Technology, 72:531–541, 2014.
- [he-l2023] He L., Fang H., and Zhang D. Topological relation expression and verification of symmetrical parallel mechanism based on the evolution of chemical molecule. *Robotica*, 41:3584–3607, 2023.
- [he2020] He J. and others . Kinematic design of a serial-parallel hybrid finger mechanism actuated by twisted and coiled polymer. *Mechanism and Machine Theory*, 152, 2020.
- [hebsacker 98] Hebsacker M. and Epfl A. Die auslegung des kinematik des hexaglide- Methodik für die auslegung paralleler werkzeugmaschinen. In *New machine concepts for handling and manufacturing devices on the basis of parallel structures*, pages 51–66, Braunschweig, November, 10-11, 1998.
- [heerah2002] Heerah I. and others . Workspace-based architecture selection of a 3-degree-of-freedom planar parallel manipulator. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [heerah2003] Heerah I. and others . Architecture selection and singularity analysis of a three-degree-of-freedom planar parallel manipulator. J. of Robotic Systems, 37(4):355-374, August 2003.
- [heiran 2017] Heiran F. and others. Kinematics and workspace analysis of a novel parallel mechanism with kinematic redundancy. In 5th International Conference on Control, Instrumentation, and Automation (ICCIA), 2017.
- [heisel98] Heisel U. and Hestermann J-O. Gelenkstab und gelenkeinheit-Grundelemente von maschinen und parallelkinematik. In *New machine concepts for handling and manufacturing devices on the basis of parallel* structures, pages 117–125, Braunschweig, November, 10-11, 1998.
- [heisel2002] Heisel U. and Maier W. Investigation of truss structures as light weight element for the use in parallel kinematic machines. In 3rd Chemnitzer Parallelkinematik Seminar, pages 715–728, Chemnitz, April, 23-25, 2002.

- [helinski90] Helinski A.L. Dynamic and kinematic study of a Stewart platform using Newton-Euler techniques. Research Report 13479, Tank Automotive Command, January 1990.
- [henein98] Henein S. and others . ORION: robot de haute précision à articulations flexibles. In *9ème Journées Jeunes Chercheurs en Robotique*, pages 30–34, Clermont-Fd, May, 11-12, 1998.
- [hennes2002] Hennes N. Ecospeed: an innovative machining concept for high performance 5-axis-machining of large structural component in aircraft engineering. In 2nd NCG Application Conf. on Parallel Kinematics Machine, pages 763–774, Chemnitz, April, 23-25, 2002.
- [henninger 2007] Henninger C. and Eberhard P. An investigation of pose-dependent regenerative chatter for a parallel kinematic milling machine. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [hernandez2008] Hernandez A. and others . Transitions in the velocity pattern of lower mobility parallel manipulators. Mechanism and Machine Theory, 43(6):738–753, 2008.
- [hernandez2012] Hernandez A. and others . Designing parallel manipulators: from specifications to a real prototype.  $Industrial\ Robot,\ 39(5):500-512,\ 2012.$
- [hernandez2015] Hernandez A. and others. Design optimization of a cable-based parallel tracking system by using evolutionary algorithms. *Robotica*, 33(3):599–610, March 2015.
- [hernandezmartinez2008] Hernandez-Martinez E., Carbone G., and Lopez-Cajun C. Operation feature of Milli-CaTraSys. In 2nd European Conf. on Mechanism Science (Eucomes), Cassino, September, 17-20, 2008.
- [herpe2018] Herpe X. and others. On a simplified nonlinear analytical model for the characterisation and design optimisation of a compliant XY micro-motion stage. *Robotics and Computer-Integrated Manufacturing*, 49:66–76, 2018.
- [herrero2012] Herrero S. and others . Simplified kinetostatic model of the 3-RPS manipulator. In 4th European Conf. on Mechanism Science (Eucomes), pages 375–382, Santander, September, 19-21, 2012.
- [herrero2015] Herrero S. and others. Enhancing the useful workspace of a reconfigurable parallel manipulator by grasp point optimization. *Robotics and Computer-Integrated Manufacturing*, 31:51–60, February 2015.
- [herrero 2018] Herrero S. and others . Analysis of the  $2\underline{P}RU-1\underline{P}RS$  3dof parallel manipulator: kinematics, singularities and dynamics. Robotics and Computer-Integrated Manufacturing, 51:63–72, 2018.
- [herrero2019] Herrero S. and others . Analytical procedure based on the matrix structural method for the analysis of the stiffness of the 2PRU-1PRS parallel manipulator. *Robotica*, 37:1401-1414, 2019.
- [hertel2002] Hertel A. Requirement for parallel kinematics for powertrain manufacturing in the automotive industry. In 2nd NCG Application Conf. on Parallel Kinematics Machine, pages 753–761, Chemnitz, April, 23-25, 2002.
- [hertz93] Hertz R.B. and Hughes P.C. Forward kinematics of a 3 d.o.f. variable-geometry-truss manipulators. In J. Angeles P. Kovacs, G. Hommel, editor, *Computational Kinematics*, pages 241–250. Kluwer, 1993. **Keywords:** forward kinematics, 3 dof robot, truss, mechanical architecture.
- [hertz98] Hertz R.B. and Hughes P.C. Kinematic analysis of a general double-tripod parallel manipulator. *Mechanism and Machine Theory*, 33(6):683–696, August 1998.
- [herve91] Hervé J-M. and Sparacino F. Structural synthesis of parallel robots generating spatial translation. In *ICAR*, pages 808–813, Pise, June, 19-22, 1991.
- [herve91-1] Hervé J-M. Dispositif pour le déplacement en translation spatiale d'un élément dans l'espace, en particulier pour robot mécanique, January, 11, 1991. French Patent n° 9100286. **Keywords:** mechanical architecture,3 dof robot,patent.
- [herve92] Hervé J.M. Group mathematics and parallel link mechanisms. In *IMACS/SICE Int. Symp. on Robotics*, *Mechatronics*, and *Manufacturing Systems*, pages 459–464, Kobe, September, 16-20, 1992.
- [herve92-1] Hervé J-M. and Sparacino F. Star, a new concept in robotics. In ARK, pages 176–183, Ferrare, September, 7-9, 1992.

- [herve95] Hervé J.M. Group mathematics and parallel link mechanisms. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 2079–2082, Milan, August 30- September 2, 1995.
- [herve2002] Hervé J.M. and Karouia M. The novel 3-RUU wrist with no idle pair. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, Québec, October, 3-4, 2002.
- [herve2003] Hervé J.M. The planar-spherical kinematic bond: implementation in parallel mechanisms. January, 24, 2003, http://www.parallemic.org/Reviews/Review013.html. **Keywords:** structural synthesis.
- [herve2004] Hervé J.M. Parallel mechanisms with pseudo-planar motion generators. In J. Lenarčič C. Galletti, editor, ARK, pages 431–440. Kluwer, 2004. **Keywords:** mechanical architecture, structural synthesis, design theory.
- [herve2009] Hervé J.M. Uncoupled actuation of pan-tilt wrists. IEEE Trans. on Robotics, 22(1):56-64, 2009.
- [hess-coelho2006] Hess-Coelho T.A. Topological synthesis of a parallel wrist manipulator. ASME J. of Mechanical Design, 128(1):230–235, January 2006.
- [hess-coelho2007] Hess-Coelho T.A. A redundant parallel spherical mechanism for robotic wrist applications. ASME J. of Mechanical Design, 129(8):891–895, August 2007.
- [hess-coelho2007-1] Hess-Coelho T.A. and Malvezzi F. Workspace optimization of 3 RSS+CP parallel mechanisms. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [hess-coelho2007-2] Hess-Coelho T.A. An alternative procedure for type synthesis of parallel mechanisms. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [hesselbach95] Hesselbach J. and Kerle H. Structurally adapted kinematic algorithms for parallel robots up to six degrees of freedom (dof). In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1935–1939, Milan, August 30- September 2, 1995.
- [hesselbach96] Hesselbach J., Kerle H., and Plitea N. On some aspects of parallel robots control. In 27th Int. Symp. on Industrial Robots (ISIR), pages 683–687, Milan, October, 6-8, 1996.
- [hesselbach98] Hesselbach J., Plitea N., Frindt M., and Kusiek A. A new parallel mechanism to use for cutting convex glass panels. In *ARK*, pages 165–174, Strobl, June 29- July 4, 1998.
- [hesselbach98-1] Hesselbach J. and Kusiek A. Steuerung eines parallelroboters für die mikromontage. In New machine concepts for handling and manufacturing devices on the basis of parallel structures, pages 127–144, Braunschweig, November, 10-11, 1998.
- [hesselbach98-2] Hesselbach J. and others . Manipulator for parallel structure and driving guide element, September, 17, 1998. German Patent n° DE19710171. **Keywords:** mechanical architecture,6 dof robot,patent.
- [hesselbach99] Hesselbach J. and Frindt M. Kinematic analysis of a class of parallel pick and place mechanisms using VDI 2729. In 10th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 566–571, Oulu, June, 20-24, 1999.
- [hesselbach2000] Hesselbach J. and others . Platform for machine tool consists of two parallel platforms linked by five articulated levers providing five degrees of freedom for machine tool spindle, March, 23, 2000. German Patent n° DE19840886. **Keywords:** mechanical architecture,5 dof robot,patent.
- [hesselbach2001] Hesselbach J. and others . A parallel robot with Spread-band elements. In 32th Int. Symp. on Robotics, pages 1731–1736, Seoul, April, 19-21, 2001.
- [hesselbach2002] Hesselbach J. and others. Kinematic and dynamic design of parallel robot. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 31–46, Braunschweig, May, 29-30, 2002.
- [hesselbach2002-1] Hesselbach J. and others . Dynamic modelling of plane parallel robot for control purposes. In 3rd Chemnitzer Parallelkinematik Seminar, pages 391–409, Chemnitz, April, 23-25, 2002.
- [hesselbach2002-2] Hesselbach J. and others . A new hybrid six-axis-machine for efficient cutting convex glass panels. In 3rd Chemnitzer Parallelkinematik Seminar, pages 655–669, Chemnitz, April, 23-25, 2002.

- [hesselbach2002-3] Hesselbach J. and others . Workspace optimized parallel robot for placing tools. In 3rd Chemnitzer Parallelkinematik Seminar, pages 697–713, Chemnitz, April, 23-25, 2002.
- [hesselbach2002-4] Hesselbach J. and others . Connecting assembly modes for workspace enlargement. In ARK, pages 347–356, Caldes de Malavalla, June 29- July 2, 2002.
- [hesselbach2003] Hesselbach J. and others . Compliant parallel robots with pseudo-elastic flexure hinges. In *Int. Precision Assembly Seminar IPAS'2003*, pages 41–48, Bad Hofgastein, March, 17-19, 2003.
- [hesselbach2003-1] Hesselbach J. and others . A micro-assembly-station based on a hybrid 4-dof robot. In *Int. Precision Assembly Seminar IPAS'2003*, pages 55–60, Bad Hofgastein, March, 17-19, 2003.
- [hesselbach2003-2] Hesselbach J. and others . A generic formulation of the dynamics of plane parallel robots for real-time applications. In RAAD, Cassino, May, 7-10, 2003.
- [hesselbach2003-3] Hesselbach J. and others . Workspace enlargement for parallel kinematic machines. Annals of the CIRP, 52(1):343-346, 2003.
- [hesselbach2004] Hesselbach J. and others. Passive joint-sensor applications for parallel robots. In *IEEE Int. Conf.* on *Intelligent Robots and Systems (IROS)*, Sendai, September 28- October 2, 2004.
- [hesselbach2004-1] Hesselbach J. and others . Performance of pseudo-elastic flexure hinges in parallel robots for micro-assembly tasks. *Annals of the CIRP*, 53(1):329–332, 2004.
- [hesselbach2005] Hesselbach J. and others . Parallel robot specific control functionalities. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 93–108, Braunschweig, May, 10-11, 2005.
- [hesselbach2005-1] Hesselbach J. and others . Singularity prediction for parallel robots for improvement of sensor-integrated assembly. *Annals of the CIRP*, 54(1):349–352, 2005.
- [heuer2003] Heuer K. and others . Open architecture robust control based on Matlab/Simulink and a dSPACE real time system. In *Proc. of the SPIE*, *Intelligent Manufacturing*, pages 1–9, October, 29-30, 2003.
- [heyden2002] Heyden T., Maier T., and Woernle C. Trajectory tracking control for a cable suspension manipulator. In ARK, pages 125–134, Caldes de Malavalla, June 29- July 2, 2002.
- [heyden2006] Heyden T. and Woernle C. Dynamics and flatness-based control of a kinematically undetermined cable suspension manipulator. *Multibody System Dynamics*, 16:155–177, 2006.
- [higuchi88] Higuchi T., Ming A., and Jiang-Yu J. Application of multi-dimensional wire crane in construction. In 5th Int. Symp. on Robotics in Construction, pages 661–668, Tokyo, June, 6-8, 1988.
- [hiller2005] Hiller M. and others . Analysis, realization and application of the tendon-based parallel robot SEGESTA. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 185–202, Braunschweig, May, 10-11, 2005.
- [hiller 2005-1] Hiller M. and others . Design, analysis and realization of tendon-based parallel manipulators. *Mechanism and Machine Theory*, 40(4):429–445, April 2005.
- [hirano2014] Hirano J. and others . Development of Delta robot driven by pneumatical artificial muscles. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 1400–1405, Besancon, July, 8-11, 2014.
- [hirose-t2012] Hirose T. and others . Development of hair washing robot with scrubbing fingers. In *IEEE Int. Conf. on Robotics and Automation*, pages 1970–1979, Saint Paul, May, 14-18, 2012.
- [hirose99] Hirose S. and others . Development of the light-legged dinosaur TITUS. Advanced Robotics, 13(3):237-238, 1999.
- [ho2014] KHo W.Y. and others . Haptic interaction with a cable-driven parallel robot with admittance control. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), Duisburg, August, 24-27, 2014.
- [hoevenaars 2017] Hoevenaars A.G.L. and others . A systematic approach for the jacobian analysis of parallel manipulators with two end-effectors. *Mechanism and Machine Theory*, 109:171–194, 2017.
- [hoevenaars 2020] Hoevenaars A.G.L., Krut S., and Herder J.L. Jacobian-based natural frequency analysis of parallel manipulators. *Mechanism and Machine Theory*, 148, 2020.

- [hoffman 79] Hoffman R. Dynamics and control of a flight simulator motion system. In *Canadian Conf. on Automatic Control*, pages 1–10, Montréal, May, 23-25, 1979.
- [hoffman79-1] Hoffman R. and McKinnon M.G. Vibrational modes of an aircraft simulator motion system. In 5th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 603–606, Montréal, July 1979.
- [hoffman2020] Hoffman R. and Asada H.H. Precision assembly of heavy objects suspended with multiple cables from a crane. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October, 25-29, 2020.
- [homma94] Homma K. and Arai T. Upper limb motion assist system with parallel mechanisms. In 2nd Japan-France Congress on Mechatronics, pages 388–391, Takamatsu, November, 1-3, 1994.
- [homma2003] Homma K. and others . A wire-driven leg rehabilitation system: development of a 4-dof experimental system. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 908–913, Kobe, July, 20-24, 2003.
- [honegger97] Honegger M., Codourey A., and Burdet E. Adaptive control of the Hexaglide, a 6 dof parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 543–548, Albuquerque, April, 21-28, 1997.
- [honegger 2000] Honegger M., Brega R., and Schweitzer G. Application of a nonlinear adaptive controller to a 6 dof parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 1930–1935, San Francisco, April, 24-28, 2000.
- [hong-j2009] Hong J. and Yamamoto M. A calculation method of the reaction force and moment for a Delta-type parallel link robot with a fixed frame. *Robotica*, 27(4):579–587, July 2009.
- [hong-ks2003] Hong K-S. Kinematic optimal design of a new parallel-type rolling mill: paramill. *Advanced Robotics*, 17(9):837–862, 2003.
- [hong-zhou2010] Hong-Zhou J., Jing-Feng H., and Zhi-Zhong T. Characteristics analysis of joint space inverse mass matrix for the optimal design of a 6-dof parallel manipulator. *Mechanism and Machine Theory*, 45(5):722–739, May 2010.
- [hong2000] Hong K.S. and Kim J-G. Manipulability analysis of a parallel machine tool: application to optimal link length design. *J. of Robotic Systems*, 17(8):403–415, 2000.
- [hongrui94] Hongrui W. Variable structure model reference adaptive control of robot. In 2nd Asian Conf. on Robotics and its application, pages 467–470, Beijing, October, 13-15, 1994.
- [hongrui94-1] Hongrui W. and others . Trajectory control of parallel robot based on predictive control theory. In 2nd Asian Conf. on Robotics and its application, pages 455–459, Beijing, October, 13-15, 1994.
- [hopkins2002] Hopkins B.R. and Williams II R.L. Kinematics, design and control of the 6-PSU platform. *Industrial Robot*, 29(5):443–451, 2002.
- [hopkins2002-1] Hopkins B.R. and Williams II R.L. Modified  $6 \underline{P}SU$  platform. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [horner94] Horner G.C. Variable geometry truss manipulator arm and smart materials research at the NASA Langley research center. In 5th Int. Conf. on Adaptive Structures, pages 450–457, Sendai, December, 5-7, 1994.
- [horoub2013] Horoub M.M., Hassan M., and Hawwa A. Workspace analysis of a floating cable-driven platform for marine applications. In *Int. Conf. on Mechanical Engineering and Mechatronics*, Toronto, August, 8-10, 2013.
- [horoub2018] Horoub M.M., Hassan M., and Hawwa A. Workspace analysis of a Gough-Stewart type cable marine platform subjected to harmonic water waves. *Mechanism and Machine Theory*, 120:314–325, 2018.
- [horoub2018-1] Horoub M.M., Hassan M., and Hawwa A. Influence of cables layout on the dynamic workspace of a six-dof parallel marine manipulator. *Mechanism and Machine Theory*, 129:191–201, 2018.
- [horoub2020] Horoub M.M. Dynamic analysis of a tension leg platforms (TLPs) inspired by parallel robotic manipulators. *IEEE Access*, 2020.

- [horoub2020-1] Horoub M.M. Dynamic investigation of a cable-driven marine robot (CDMR) with different cables' characteristics. In *Int. Conf. on Electrical, Communication, and Computer Engineering (ICECCE)*, Toronto, August, 8-10, 2013.
- [hosseini2011] Hosseini M.A., Daniali H-R. M., and Taghirad H.D. Dexterous workspace optimization of a Tricept parallel manipulator. *Advanced Robotics*, 25(13-14):1697–1712, 2011.
- [hosseini2015] Hosseini M.A. and Daniali H-M. Cartesian workspace optimisation of Tricept parallel manipulator with machining application. *Robotica*, 33(9):1948–1957, November 2015.
- [hosseini2015-1] Hosseini M.A. Kinematic synthesis of a novel rapid spherical CRS/PU parallel manipulator. *Mechanism and Machine Theory*, 93:26–38, November 2015.
- [hou2009] Hou Y. and others . Performance analysis and comprehensive index optimization of a new configuration of Stewart six-component force sensor. *Mechanism and Machine Theory*, 44(2):359–368, February 2009.
- [hovland2007] Hovland G. and others . Benchmark of the 3-dof Gantry-Tau parallel kinematic machine. In *IEEE Int. Conf. on Robotics and Automation*, pages 535–542, Roma, April, 10-14, 2007.
- [hu-b2010] Hu B., Lu Y., and Yu J. Dynamics analysis of some limited-degree-of-freedom parallel manipulators with n UPS active legs and a passive constraining leg. *Advanced Robotics*, 24(7):1003–1016, 2010.
- [hu-b2011] Hu B. and Lu Y. Solving stiffness and deformation of a 3-UPU parallel manipulator with one translation and two rotations. *Robotica*, 29(6):815–822, October 2011.
- [hu-b2011-1] Hu B. and others. Analysis of stiffness and elastic deformation of a 2(SP+SPR+SPU) serial-parallel manipulator. Robotics and Computer-Integrated Manufacturing, 27(2):418–425, April 2011.
- [hu-b2011-2] Hu B. and others . Solving stiffness and elastic deformation of two limited degree-of-freedom parallel manipulator with a constrained leg based on active constrained wrench.  $Advanced\ Robotics,\ 25(9-10):1331-1348,\ 2011.$
- [hu-b2014] Hu B. Formulation of unified jacobian for serial-parallel manipulators. *Robotics and Computer-Integrated Manufacturing*, 30(5):460–467, October 2014.
- [hu-b2014-1] Hu B. Complete kinematics of a serial–parallel manipulator formed by two Tricept parallel manipulators connected in serials. *Nonlinear Dynamics*, 78:2685–2698, 2014.
- [hu-b2016] Hu B. and Yu Y., J.and Lu. Inverse dynamics modeling of a (3-UPU)+(3-UPS+S) serial-parallel manipulator. *Robotica*, 34:687–702, 2016.
- [hu-b2016-1] Hu B. Kinematically identical manipulators for the Exection parallel manipulator and their comparison study. *Mechanism and Machine Theory*, 103:117–137, 2016.
- [hu-b2020] Hu B. Reconsideration of terminal constraint/mobility and kinematics of 5-dof hybrid manipulators formed by one 2R1T PM and one RR SM. *Mechanism and Machine Theory*, 149, 2020.
- [hu-h2010] Hu H. and others. The analysis of resolution for cable-driven haptic device. In *IEEE International Conference on Robotics and Biomimetics*, Tianjin, Decembre October, 14-18, 2010.
- [hu-y2018] Hu Y. and others . Kinematic calibration of a 6-dof parallel manipulator based on identifiable parameters separation (IPS). *Mechanism and Machine Theory*, 126:61–78, 2018.
- [hu99] Hu M. and others . The 3-dof in-parallel robot and its application for billet snagging. In *IFAC World Congress*, Beijing, 1999.
- [huang-c-2002] Huang C., Hung W-H., and Kao I. New conservative stiffness mapping for the Stewart-Gough platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 823–828, Washington, May, 11-15, 2002.
- [huang-g2018] Huang G. and others . Kinematic analysis and multi-objective optimization of a new reconfigurable parallel mechanism with high stiffnes. Robotica, 36:187–203, 2018.
- [huang-jy-2002] Huang J-Y. and Gau C-Y. A PC cluster high-fidelity mobile crane simulator. *Tamkang Journal of Science and Engineering*, 5(1):7–20, 2002.

- [huang-l-99] Huang L. and Notash L. Failure analysis of parallel manipulators. In 10th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1027–1032, Oulu, June, 20-24, 1999.
- [huang-s-98] Huang S. and Schimmels J.M. The bounds and realization of spatial stiffnesses achieved with simple springs connected in parallel. *IEEE Trans. on Robotics and Automation*, 14(3):466–474, June 1998.
- [huang-s-2018] Huang S. and Schimmels J.M. Geometric construction-based realization of spatial elastic behaviors in parallel and serial manipulators. *IEEE Trans. on Robotics*, 34(3), June 2018.
- [huang-t-99] Huang T., Wang J., and Whitehouse D.J. Closed form solution of hexapod-based virtual axis machine tools. ASME J. of Mechanical Design, 121(1):26–31, March 1999.
- [huang-t-2000] Huang T., Jiang B., and Whitehouse D.J. Determination of the carriage stroke of 6-PSS parallel manipulators having the specific orientation capability in a prescribed workspace. In *IEEE Int. Conf. on Robotics and Automation*, pages 2382–2385, San Francisco, April, 24-28, 2000.
- [huang-t-2001] Huang T. and others . Stiffness estimation of a Tripod-based parallel kinematic machine. In *IEEE Int. Conf. on Robotics and Automation*, pages 3280–3285, Seoul, May, 23-25, 2001.
- [huang-t-2002] Huang T., Zhao X., and Whitehouse D.J. Stiffness estimation of a Tripod-based parallel kinematic machine. *IEEE Trans. on Robotics and Automation*, 18(1):50–58, February 2002.
- [huang-t-2002-1] Huang T. and others. A time/cost effective approach for parameter identification of 6-dof parallel kinematic machines using a minimum set of pose error measurements. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, Québec, October, 3-4, 2002.
- [huang-t-2003] Huang T. and others . Identifiability of geometric parameters of 6-dof PKM systems using a minimum set of pose error-data. In *IEEE Int. Conf. on Robotics and Automation*, pages 1863–1868, Taipei, September, 14-19, 2003.
- [huang-t-2004] Huang T. and others . Optimal kinematic design of 2-dof parallel manipulators with well-shaped workspace bounded by a specific conditioning index. *IEEE Trans. on Robotics and Automation*, 20(3):538–543, June 2004.
- [huang-t-2004-1] Huang T. and others . Conceptual design and dimensional synthesis of a novel 2-DOF translational parallel robot for pick-and-place operations. ASME~J.~of~Mechanical~Design,~126(3):449-455,~May~2004.
- [huang-t-2005] Huang T. and others. A general and novel approach for parameter identification of 6-dof parallel kinematic machines. *Mechanism and Machine Theory*, 40(2):219–239, February 2005.
- [huang-t-2005-1] Huang T. and others . A method for estimating servomotor parameters of a parallel robot for rapid pick-and-place operations.  $ASME\ J.$  of  $Mechanical\ Design,\ 127(4):596-601,\ July\ 2005.$
- [huang-t-2007] Huang T. and others . Time minimum trajectory planning of a 2-dof translation parallel robot for pick-and-place operations. Annals of the CIRP, 56/1/2007:365-368, 2007.
- [huang-t-2019] Huang T. and others . A simple and visually orientated approach for type synthesis of overconstrained 1T2R parallel mechanisms. *Robotica*, 37:1161–1173, 2019.
- [huang-t-99-1] Huang T. and others . Determination of closed form solution to the 2-D orientation workspace of Gough-Stewart parallel manipulators. *IEEE Trans. on Robotics and Automation*, 15(6):1121–1125, December 1999.
- [huang-x-2010] Huang X., Liao Q., and Wei S. Closed-form forward kinematics for a symmetrical 6-6 Stewart platform using algebraic elimination. *Mechanism and Machine Theory*, 45(2):327–334, February 2010.
- [huang-y-2023] Huang Y. and others . Kinematic and dynamic analysis of a 4-DOF over-constraint parallel driving mechanism with planar sub-closed chains. *Robotica*, 41, October 2023.
- [huang-z96] Huang Z., Tao W.S., and Fang Y.F. Study on the kinematics characteristics of 3 DOF in-parallel actuated platform mechanisms. *Mechanism and Machine Theory*, 31(8):999–1007, November 1996.
- [huang-z96-1] Huang Z. and Fang Y.F. Kinematic characteristics analysis of 3 DOF in-parallel pyramid mechanisms. Mechanism and Machine Theory, 31(8):1009–1018, November 1996.

- [huang-z99] Huang Z. and others. Kinematic principle and geometrical condition of general-linear-complex special configuration of parallel manipulators. *Mechanism and Machine Theory*, 34(8):1171–1186, November 1999.
- [huang-z99-1] Huang Z. and Yao Y.L. A new closed-form kinematics of the generalized 3-dof spherical parallel manipulator. *Robotica*, 17(5):475–485, September 1999.
- [huang-z2001] Huang Z. and Wang J. Identification of principal screws of 3-DOF parallel manipulators by quadric degeneration. *Mechanism and Machine Theory*, 36(8):893–911, August 2001.
- [huang-z2002] Huang Z. and Li Q.C. Some novel minor-mobility parallel mechanisms. In 3rd Chemnitzer Parallelkine-matik Seminar, pages 895–905, Chemnitz, April, 23-25, 2002.
- [huang-z2002-2] Huang Z., Wang J., and Fang Y.F. Analysis of instantaneous motions of deficient-rank 3-RPS parallel manipulators. *Mechanism and Machine Theory*, 37(2):229–240, February 2002.
- [huang-z2002-1] Huang Z. and Li Q.C. General methodology for type synthesis of symmetrical lower-mobility parallel manipulators and several novel manipulators. *Int. J. of Robotics Research*, 21(2):131–145, February 2002.
- [huang-z2002-3] Huang Z. and Chen L.H. Singularity principle and distribution of 6-3 Stewart parallel manipulator. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [huang-z2002-4] Huang Z. and Li Q.C. Some novel lower-mobility parallel mechanisms. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [huang-z2002-5] Huang Z. and Li Q.C. Construction and kinematics properties of 3-dof parallel mechanisms. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [huang-z2003] Huang Z. and Li Q.C. Type synthesis of symmetrical lower mobility parallel mechanisms using the constraint synthesis method. *Int. J. of Robotics Research*, 22(1):59–79, January 2003.
- [huang-z2004] Huang Z. The kinematics and type synthesis of lower-mobility parallel robot manipulators. In 11th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 65–76, Tianjin, April, 1-4, 2004.
- [huang-z2004-1] Huang Z., Li S.H., and Zuo R.G. Feasible instantaneous motions and kinematic characteristics of a special 3-DOF 3-UPU parallel manipulator. *Mechanism and Machine Theory*, 39(9):959–970, 2004.
- [huang-z2005] Huang Z. and Cao Y. Property identification of the singularity of Gough-Stewart manipulators. *Int. J. of Robotics Research*, 24(8):675–685, August 2005.
- [huang-z2006] Huang Z. and others . Structure and property of the singularity loci of the 3-6 Stewart-Gough platform for general orientations. Robotica, 24(1):75-84, January 2006.
- [huang-z2008] Huang Z., Wang J., and Li S.H. Parallel manipulators, New Developments, chapter Principal screws and full-scale feasible instantaneous motions of some 3-dof parallel manipulators, pages 349–372. ITECH, April 2008. **Keywords:** mobility,3 dof robot,jacobian.
- [huang92] Huang M.Z. A note on kinematics of in-parallel actuated platform manipulators. In 2nd National Applied Mechanisms and Robotics Conf., pages IXC.6–1/IXC.6–4, Cincinnati, November, 3-6, 1992.
- [huang 93] Huang M.Z., Ling S-H., and Sheng Y. A study of velocity kinematics for hybrid manipulators with parallel-series configurations. In *IEEE Int. Conf. on Robotics and Automation*, pages 456–461, Atlanta, May, 2-6, 1993.
- [huang 94] Huang M.Z. and Ling S-H. Kinematics of a class of hybrid robotic mechanisms with parallel and series module. In *IEEE Int. Conf. on Robotics and Automation*, pages 2180–2185, San Diego, May, 8-13, 1994.
- [hubert2008] Hubert J. and Merlet J-P. Singularity analysis through static analysis. In ARK, pages 13–20, Batz/mer, June, 23-26, 2008.
- [hubert2009] Hubert J. and Merlet J-P. Static of parallel manipulators and closeness to singularity. *J. of Mechanisms and Robotics*, 1(1), February 2009.
- [hubert2009-phd] Hubert J. Singularités et manipulateurs parallèles. Ph.D. Thesis, Université de Nice, Nice, September, 28, 2009. **Keywords:** singularity.

- [huda2007] Huda S. and Takeda Y. Dimensional synthesis of 3-URU pure rotational parallel mechanism with respect to singularity and workspace. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [hudgens88] Hudgens J.C. and Tesar D. A fully-parallel six degree-of-freedom micromanipulator: kinematic analysis and dynamic control. In *ASME Proc. of the 20th Biennial Mechanisms Conf.*, pages 29–37, Kissimmee, Orlando, September, 25-27, 1988.
- [hufnagel2012] Hufnagle T., Reichert C., and Schramm D. Centralized non-linear model predictive control of a redundantly actuated parallel manipulator. In 4th European Conf. on Mechanism Science (Eucomes), pages 621–629, Santander, September, 19-21, 2012.
- [hui-l-2015] Hui L. A giant sagging-cable-driven parallel robot of FAST telescope: its tension-feasible workspace of orientation and orientation planning. In 14th IFToMM World Congress on the Theory of Machines and Mechanisms, Taipei, October, 27-30, 2015.
- [hui95] Hui R. and others . Mechanisms for haptic feedback. In *IEEE Int. Conf. on Robotics and Automation*, pages 2138–2143, Nagoya, May, 25-27, 1995.
- [hunt-j-2007] Hunt J.A. Robot kinematics and the Gantry-Tau parallel machine. *Industrial Robot*, 34(5):362–367, 2007.
- [hunt82] Hunt K.H. Geometry of robotics devices. Mechanical Engineering Transactions, 7(4):213–220, 1982.
- [hunt82-1] Hunt K.H. Structural kinematics of in parallel actuated robot arms. In *Design, and Production Engineering Technical Conference*, Washington, September, 12-15, 1982.
- [hunt83] Hunt K.H. Structural kinematics of in parallel actuated robot arms. J. of Mechanisms, Transmissions and Automation in Design, 105(4):705–712, March 1983.
- [hunt93] Hunt K.H. and Primrose E.J.F. Assembly configurations of some in-parallel actuated manipulators. *Mechanism and Machine Theory*, 28(1):31–42, January 1993.
- [hunt98] Hunt K.H. and McAree P.R. The octahedral manipulator: geometry and mobility. *Int. J. of Robotics Research*, 17(8):868–885, 1998.
- [huo-t2021] Huo T. and others . A family of novel rcm rotational compliant mechanisms based on parasitic motion compensation. *Mechanism and Machine Theory*, 156, 2021.
- [huo-x2021] Huo X. and others . Dynamic identification of a tracking parallel mechanism. *Mechanism and Machine Theory*, 155, 2021.
- [huo2017] Huo X., T. Sun., and Song Y. A geometric algebra approach to determine motion/constraint, mobility and singularity of parallel mechanism. *Mechanism and Machine Theory*, 116:273–293, 2017.
- [huo2018] Huo X. and others . Parametrized inverse kinematics of parallel mechanism based on CGA. In *EUCOMES*, pages 340–346, Aachen, September, 4-6, 2018.
- [hur2020] Hur S-M. and others. Design of a parallel haptic device with gravity compensation by using its system weight. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [huryn2010] T.P. Huryn and others . Investigating human balance using a robotic motion platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 5090–5095, Anchorage, May, 3-8, 2010.
- [husain92] Husain M. and Waldron K.J. Position kinematics of a mixed mechanism. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 41–48, Scottsdale, September, 13-16, 1992.
- [husain 92-1] Husain M. and Waldron K.J. Direct position kinematics of the 3-1-1-1 Stewart platform. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 89–97, Scottsdale, September, 13-16, 1992.
- [husain94] Husain M. and Waldron K.J. Direct position kinematics of the 3-1-1-1 Stewart platform. ASME J. of Mechanical Design, 116(4):1102–1108, December 1994.

- [hussein 2018] Hussein H., Gouttefarde M., and Pierrot F. Static modeling of sagging cables with flexural rigidity and shear forces. In ARK, Bologna, July, 1-5, 2018.
- [hussein 2018-1] Hussein H., Santos J.C., and Gouttefarde M. Geometry optimization of a large scale CDPR operating on a building facade. In *IROS*, Madrid, 2018.
- [hussein 2021] Hussein H. and others . Smallest maximum cable tension determination for cable-driven parallel robots.  $IEEE\ Trans.\ on\ Robotics,\ 37(4),\ 2021.$
- [husty94] Husty M.L. and Zsombor-Murray P. A special type of singular Stewart-Gough platform. In ARK, pages 449–458, Ljubljana, July, 4-6, 1994.
- [husty94-1] Husty M.L. An algorithm for solving the direct kinematic of Stewart-Gough-type platforms. Research Report TR-CIM-94-7, Université McGill, Montréal, June, 30, 1994.
- [husty95] Husty M.L. Kinematics mapping of planar three-legged platforms. In 15th Canadian Conf. on Applied Mechanics, pages 876–877, Victoria, May 28- June 1, 1995.
- [husty96] Husty M.L. On the workspace of planar three-legged platforms. In World Automation Congress, volume 3, pages 339–344, Montpellier, May, 28-30, 1996.
- [husty96-1] Husty M.L. An algorithm for solving the direct kinematic of Stewart-Gough-type platforms. *Mechanism and Machine Theory*, 31(4):365–380, May 1996.
- [husty2000] Husty M.L. and Karger A. Self-motions of Griffis-Duffy type parallel manipulators. In *IEEE Int. Conf.* on Robotics and Automation, pages 7–12, San Francisco, April, 24-28, 2000.
- [husty2000-1] Husty M.L. and Karger A. Architecture singular parallel manipulators and their self-motions. In ARK, pages 355–364, Piran, June, 25-29, 2000.
- [husty2001] Husty M.L. and Eberharter J. Kinematic analysis of the Hexapod telescope. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 269–278. EJCK, May, 20-22, 2001. **Keywords:** forward kinematics, singularity.
- [husty2002] Husty M., Mielczarek S., and Hiller M. Redundant spatial Stewart-Gough platform with a maximal forward kinematic solution set. In ARK, pages 147–154, Caldes de Malavalla, June 29- July 2, 2002.
- [husty2009] Husty M. Non-singular assembly mode change in 3-RPR parallel manipulators. In *Computational Kinematics*, pages 1–10, Duisburg, May, 6-8, 2009.
- [husty2012] Husty M. and others . Self-motions of 3-RPS manipulators. In 4th European Conf. on Mechanism Science (Eucomes), pages 121–130, Santander, September, 19-21, 2012.
- [husty2013] Husty M. and Zsombor-Murray P. Geometric contribution to the analysis of 2-2 wire driven cranes. In *Int. Conf. on Interdisciplinary Applications of Kinematics*, pages 1–8, Lima, September, 9-11, 2013.
- [husty2017] Husty M., Schadlbauer J., and Zsombor-Murray P. A new approach to the direct geometrico-static problem of cable suspended robots using kinematic mapping. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [husty2019] Husty M. and others . An algebraic parameterization approach for parallel robots analysis. *Mechanism and Machine Theory*, 140, 2019.
- [huynh-bp2020] Huynh B-P. and Kuo Y-L. Dynamic filtered path tracking control for a 3RRR robot using optimal recursive path planning and vision-based pose estimation. *IEEE Access*, 2020.
- [huynh-bp2020-1] Huynh B-P., Wu C-W., and Kuo Y-L. Force/position hybrid control for a Hexa robot using gradient descent iterative learning control algorithm. *IEEE Access*, 2020.
- [huynh97] Huynh P. and Arai T. Maximum velocity analysis of parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 3268–3273, Albuquerque, April, 21-28, 1997.
- [huynh2001] Huynh P. Kinematic performance comparison of linear type parallel mechanisms. Application to the design and control of a hexaslide. In 5th Int. Conf. on Mechatronics Technology, ICMT2001, Singapore, June, 6-8, 2001.

- [husty2001-1] Husty M.L., Mioelczarek S., and Hiller M. Constructing an overconstrained planar 4-RPR manipulator with maximal forward kinematics solution set. In RAAD, Vienna, 2001.
- [huynh2003] Huynh P. and Hervè J.M. Equivalent kinematic chains with planar-spherical bonds. Application to the development of a 3 dof 3-RPS parallel mechanism. In *RAAD*, Cassino, May, 7-10, 2003.
- [huynh2005] Huynh P. and Hervè J.M. Equivalent kinematic chains of three degree-of-freedom tripod mechanisms with planar-spherical bonds. ASME J. of Mechanical Design, 127(1):95–102, January 2005.
- [hwang-g-2008] Hwang G. and Hashimoto H. *Parallel manipulators*, *New Developments*, chapter Multiscale manipulations with multiple parallel mechanism manipulators, pages 331–348. ITECH, April 2008. **Keywords:** haptic device.
- [hwang-m2009] Hwang M.J. and others . Kinematic calibration of a parallel robot for small animal biopsies. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, St Louis, October, 11-15, 2009.
- [hwang-sw-2020] Hwang S. W. and others . Oscillation reduction and frequency analysis of under-constrained cable-driven parallel robot with three cables. *Robotica*, 38:375–395, 2020.
- [hwang-yk-2007] Hwang Y-K. and others . The optimum design of a 6-dof parallel manipulator with large orientation workspace. In *IEEE Int. Conf. on Robotics and Automation*, pages 163–168, Roma, April, 10-14, 2007.
- [hwang2003] Hwang T-S., Lin C-L., and Tsai R-C. Analysis and design for a parallel manipulator using linear motors. *Int. J. of Robotics and Automation*, 18(3):97–109, 2003.
- [ibarreche2012] Ibarreche J.I. and others . Structural synthesis of the families of parallel manipulators with 3 degrees of freedom. In *RoManSy*, Paris, June, 12-15, 2012.
- [ibarreche2017] Ibarreche J.I. and others. Multioperation capacity of parallel manipulators basing on generic kinematic chain approach. *Mechanism and Machine Theory*, 116:234–247, 2017.
- [ibrahim2006] Ibrahim O. Contribution à la modélisation des robots parallèles et des robots hybrides. Ph.D. Thesis, Université de Nantes, Nantes, October, 30, 2006. **Keywords:** dynamics.
- [ibrahim2007] Ibrahim O. and Khalil W. Kinematic and dynamic modeling of the 3-RPS parallel manipulator. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [ibrayev2002] Ibrayev S.M. and Nutpulla K.J. Approximate synthesis of planar cartesian manipulators with parallel structures. *Mechanism and Machine Theory*, 37(8):877–894, August 2002.
- [ida2017] Ida E. and others . Rest-to-rest trajectory planning for planar underactuated cable-driven parallel robots. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [ida2019] Ida E., Merlet J-P., and Carricato M. Automatic self-calibration of suspended under-actuated cable-driven parallel robot using incremental measurements. In 4th Int. Conf. on cable-driven parallel robots (CableCon), Cracow, June 30- July 4, 2019.
- [ida2019-1] Ida E., Bruckmann T., and Carricato M. Rest-to-rest trajectory planning for underactuated cable-driven parallel robots. *IEEE Trans. on Robotics*, 35(6), 2019.
- [ida2020] Ida E., Marian D., and Carricato M. A deployable cable-driven parallel robot with large rotational capabilities for laser-scanning applications. *IEEE Robotics and Automation Letters*, 2020.
- [ida2022] Ida E., Briot S., and Carricato M. Identification of the inertial parameters of underactuated cable-driven parallel robots. *Mechanism and Machine Theory*, 2022.
- [ider2004] Ider S.K. Actuation of parallel manipulators in the presence of drive singularities. In 11th Int. Conf. on Machine Design and Production, Ankara, October, 13-15, 2004.
- [ider2005] Ider S.K. Inverse dynamics of parallel manipulators in the presence of drive singularities. *Mechanism and Machine Theory*, 40(1):33–34, January 2005.
- [ider2008] Ider S.K. Parallel manipulators, New Developments, chapter Singularity robust inverse dynamics of parallel manipulators, pages 373–392. ITECH, April 2008. **Keywords:** singularity.

- [ider2009] Ider S.K. and Korkmaz O. Trajectory tracking control of parallel robots in the presence of joint drive flexibility. *Journal of Sound and Vibration*, 319(1-2):77–90, February 2009.
- [idle97] Idle M.K. and others . Use of a zero-gravity suspension system for testing a vibration isolation system. In 17th Aerospace testing Seminar, pages 79–84, Manhattan Beach, October, 14-16, 1997.
- [ilul2010] Ilul T., Pisla D., and Stoica A. Kinematics and design of a simple 2-dof parallel mechanism used for orientation. In 3rd European Conf. on Mechanism Science (Eucomes), Cluj-Napoca, September, 14-17, 2010.
- [in2007] In W., Bae S.J., and Kim J. Analysis of a new planar 3-dof parallel manipulator with two PPR chains. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [in2008] In W. and others . Design of a planar-type high speed parallel mechanism positioning platform with the capability of 180 degrees orientation. *Annals of the CIRP*, 57:421–424, 2008.
- [ingram2013] Ingram D. and others. A minimal set of coordinates for describing humanoid shoulder motion. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 5537–5544, Tokyo, November, 3-7, 2013.
- [ingram2016] Ingram D. and others . Modelling of the human shoulder as a parallel mechanism without constraints. Mechanism and Machine Theory, 100, 2016.
- [innocenti90] Innocenti C. and Parenti-Castelli V. Direct position analysis of the Stewart platform mechanism. *Mechanism and Machine Theory*, 25(6):611–621, 1990.
- [innocenti91] Innocenti C. and Parenti-Castelli V. Direct kinematics of the 6-4 fully parallel manipulator with position and orientation uncoupled. In *European Robotics and Intelligent Systems Conf.*, Corfou, June, 23-28, 1991.
- [innocenti91-1] Innocenti C. and Parenti-Castelli V. A novel numerical approach to the closure of the 6-6 Stewart platform mechanism. In *ICAR*, pages 851–855, Pise, June, 19-22, 1991.
- [innocenti91-2] Innocenti C. and Parenti-Castelli V. Direct kinematics of the reverse Stewart platform mechanism. In 3rd IFAC/IFIP/IMACS Symp. on Robot Control, Syroco, pages 75–80, Vienne, September, 16-18, 1991.
- [innocenti92] Innocenti C. and Parenti-Castelli V. Reduction singularities in kinematics solution of the general geometry 6-6 Stewart platform. In *IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems*, pages 451–458, Kobe, September, 16-20, 1992.
- [innocenti92-1] Innocenti C. and Parenti-Castelli V. Forward kinematics of the general 6-6 Stewart fully-parallel mechanism: an exhaustive numerical approach via a mono-dimensional search algorithm. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 545–552, Scottsdale, September, 13-16, 1992.
- [innocenti92-2] Innocenti C. and Parenti-Castelli V. Analytical form solution of the direct kinematics of a 4-4 fully in-parallel actuated six degree-of-freedom mechanism. In 9th RoManSy, pages 41–50, Udine, 1992.
- [innocenti92-3] Innocenti C. and Parenti-Castelli V. Singularity-free evolution from one configuration to another in serial and fully-parallel manipulators. In 22nd Biennial Mechanisms Conf., pages 553–560, Scottsdale, September, 13-16, 1992.
- [innocenti92-4] Innocenti C. Forward kinematics in analytical form of the topologically-symmetric 4-4 fully-parallel mechanism. In *ISRAM*, pages 411–418, Santa-Fe, November, 11-13, 1992.
- [innocenti93] Innocenti C. and Parenti-Castelli V. Echelon form solution of direct kinematics for the general fully-parallel spherical wrist. *Mechanism and Machine Theory*, 28(4):553–561, July 1993.
- [innocenti93-1] Innocenti C. and Parenti-Castelli V. Direct kinematics in analytical form of a general 5-4 fully-parallel manipulators. In J. Angeles P. Kovacs, G. Hommel, editor, *Computational Kinematics*, pages 141–152. Kluwer, 1993. **Keywords:** forward kinematics.
- [innocenti93-2] Innocenti C. and Parenti-Castelli V. Closed-form direct position analysis of a 5-5 parallel mechanism. ASME J. of Mechanical Design, 115(3):515–521, September 1993.
- [innocenti94] Innocenti C. and Parenti-Castelli V. Symbolic-form forward kinematics of a 5-4 fully-parallel manipulators. In Lenarčič J. and Ravani B., editors, ARK, pages 429–438, Ljubljana, July, 4-6, 1994. Springer-Verlag.

- [innocenti94-1] Innocenti C. private communication, January 1994. Communication personelle. **Keywords:** forward kinematics.
- [innocenti95] Innocenti C. Direct kinematics in analytical form of the 6-4 fully parallel mechanism. ASME J. of Mechanical Design, 117(1):89–95, March 1995.
- [innocenti95-1] Innocenti C. Algorithms for kinematic calibration of fully-parallel manipulators. In J-P. Merlet B. Ravani, editor, *Computational Kinematics*, pages 241–250. Kluwer, 1995. **Keywords:** calibration.
- [innocenti95-2] Innocenti C. Analytical-form direct kinematics for the second scheme of a 5-5 general-geometry fully parallel manipulator. J. of Robotic Systems, 12(10):661–676, 1995.
- [innocenti98] Innocenti C. Forward kinematics of a 6-6 fully parallel manipulator with congruent base and platform. In ARK, pages 137–146, Strobl, June 29- July 4, 1998.
- [innocenti98-1] Innocenti C. and Parenti-Castelli V. Singularity-free evolution from one configuration to another in serial and fully-parallel manipulators. ASME J. of Mechanical Design, 120(1):73–79, March 1998.
- [innocenti98-2] Innocenti C. and Parenti-Castelli V. Closed-form determination of the location of a rigid body by seven in-parallel linear transducers. ASME J. of Mechanical Design, 120(2):293–298, June 1998.
- [innocenti2001] Innocenti C. Forward kinematics in polynomial form of the general Stewart platform. ASME J. of Mechanical Design, 123(2):254–260, June 2001.
- [innocenti2006] Innocenti C. and Wenger P. Position analysis of the RRP-3(SS) multi-loop spatial structure. ASME J. of Mechanical Design, 128(1):272–278, January 2006.
- [inoue85] Inoue H., Tsusaka Y., and Fukuizumi T. Parallel manipulator. In 3rd ISRR, pages 321–327, Gouvieux, France, October, 7-11, 1985.
- [iriarte2008] Iriarte X., Diaz-Rodriguez M., and Mata V. Multicriteria approach for optimal trajectories in dynamic parameter identification of parallel robots. In 2nd European Conf. on Mechanism Science (Eucomes), Cassino, September, 17-20, 2008.
- [iriarte2017] Iriarte X. and others . Determination of the symbolic base inertial parameters of planar mechanisms.  $European\ Journal\ of\ Mechanics\ A/Solids,\ 61:82-91,\ 2017.$
- [isaksson2010] Isaksson M. and others . Improving the kinematic performance of the SCARA-Tau PKM. In *IEEE Int. Conf. on Robotics and Automation*, pages 4863–4690, Anchorage, May, 3-8, 2010.
- [isaksson2011] Isaksson M. A family of planar parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [isaksson2012] Isaksson M., Brogardh T., and Nahavandi S. Parallel manipulators with rotation-symmetric arm system. ASME J. of Mechanical Design, 134(11):114503–1/6, November 2012.
- [isaksson2015] Isaksson M., Nyhof L., and Nahavandi S. On the feasibility of utilising gearing to extend the rotational workspace of a class of parallel robots. *Robotics and Computer-Integrated Manufacturing*, 35:126–136, October 2015.
- [isaksson2016] Isaksson M., Gsselin C., and Marlow K. An introduction to utilising the redundancy of a kinematically redundant parallel manipulator to operate a gripper. *Mechanism and Machine Theory*, 101:50–59, 2016.
- [isaksson2017] Isaksson M., Gosselin C., and Marlow K. Singularity analysis of a class of kinematically redundant parallel Schönflies motion generators. *Mechanism and Machine Theory*, 112:172–191, 2017.
- [isaksson2017-1] Isaksson M. and others . Novel fault-tolerance indices for redundantly actuated parallel robots. ASME J. of Mechanical Design, 139, April 2017.
- [ismail2016] Ismail M., Lahouar S., and Romdhane L. Collision-free and dynamically feasible trajectory of a hybrid cable—serial robot with two passive links. *Robotics and Autonomous Systems*, 80:24–33, 2016.
- [ismail2016-1] Ismail M. Novel hexapod-based unidirectional testing and FEM analysis of the RNC isolator. Structural Control and Health Monitoring, 23:894–922, 2016.

- [itul2006] Itul T.P. and Pisla D.L. Workspace analysis of a three degrees of freedom parallel robot. In *International Conference on Automation, Quality and Testing, Robotics*, Cluj-Napoca, 2006.
- [itul2007] Itul T.P., Pisla D.L., and Pisla A. Dynamic model of a 6-dof parallel robot by considering friction effects. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [itul2010] Itul T.P., Pisla D.L., and Stoica A. Kinematics and design of a simple 2-dof parallel mechanism used for orientation. In 3rd European Conf. on Mechanism Science (Eucomes), Cluj-Napoca, September, 14-17, 2010.
- [iurascu2003] Iurascu C.C. and Park F.C. Geometric algorithm for kinematic calibration of robots containing closed loops. ASME J. of Mechanical Design, 125(1):23–32, March 2003.
- [iwata90] Iwara H. Artificial reality with force-feedback: development of desktop virtual space with compact master manipulator. *Computer Graphics*, 24(4):165–170, August 1990.
- [iwatsuki2005] Iwatsuki N., Hoshino R., and Morikawa K. Direct kinematics of a 3-R-R-S spatial parallel manipulator based on the kinematic analysis of R-S-S chain. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [iyun-2002] Iyun O., D.P. Borschnek, and Ellis R.E. Computer-assisted correction of bone-deformities using a 6-dof parallel spatial mechanism. In *MICCAI*, pages 232–240, Tokyo, November, 16-18, 2002.
- [izard2012] Izard J-B. and others. Integration of a parallel cable-driven robot on an existing building facade. In 1st Int. Conf. on cable-driven parallel robots (CableCon), pages 149–166, Stuttgart, September, 3-4, 2012.
- [izard2012-1] Izard J-B. and others . A reconfigurable robot for cable-driven parallel robotic research and industrial scenario proofing. In 1st Int. Conf. on cable-driven parallel robots (CableCon), pages 135–148, Stuttgart, September, 3-4, 2012.
- [izard2017] Izard J-B. and others . Large-scale 3d printing with cable-driven parallel robots. Construction Robotics, 1(1):69-76, 2017.
- [izard2017-1] Izard J-B. and others . On the improvements of a cable-driven parallel robot for achieving additive manufacturing for construction. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [jha2016-phd] Jha R. Contributions to the performance analysis of parallel robots. Ph.D. Thesis, Ecole Centrale de Nantes, Nantes, July 2016. **Keywords:** singularity.
- [jha2018] Jha R. Influence of design parameters on the singularities and workspace of a 3-RPS parallel robot. *Trans. CSME*, 42(1), 2018.
- [jha2018-1] Jha R. and others . Workspace, joint space and singularities of a family of delta-like robot. *Mechanism and Machine Theory*, 127:71–95, 2018.
- [jabbari2020] Jabbari I., Boutayeb M., and Jammazi C. Discontinuous finite-time control for cable driven parallel robots. In *Conference on Control Technology and Applications (CCTA)*, August, 24-26, 2020.
- [jaberi2013] Jaberi A. and others . Design and kinematic analysis of a 4-dof serial-parallel manipulator for urban bus driving simulator. In First RSI/ISM International Conference on Robotics and Mechatronics (ICRoM), 2013.
- [jadhao2017] Jadhao K.S. and others. Design and analysis of a novel cable-driven haptic master device for planar grasping. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [jafari2003] Jafari F. and McInroy J.E. Orthogonal Gough-Stewart platforms for micromanipulation. *IEEE Trans. on Robotics and Automation*, 19(4):595–603, August 2003.
- [jahn2022] Jahn P., Hentschel J., and Raatz A. Design and analysis of a compliant parallel robot with cardan joints for a cryogenic working environment. In ARK, Bilbao, June, 26-30, 2022.
- [jain90] Jain S. and Kramer S.N. Forward and inverse kinematics solution of the variable geometry truss robot based on N-celled tetrahedron-tetrahedron truss. ASME J. of Mechanical Design, 112(1):16–22, March 1990.
- [jakobovic2002] Jakobovic D. and Jelenkovic L. The forward and inverse kinematics problems for Stewart parallel mechanisms. In *Computer Integrated Manufacturing and High Speed Machining, CIM2002*, Brijuni, 2002.

- [jakobsen98] Jakobsen O.G. and Larsen J.A. Design of double-octahedral VGT manipulators. In *New machine concepts for handling and manufacturing devices on the basis of parallel structures*, pages 201–219, Braunschweig, November, 10-11, 1998.
- [jamshidifar2015] Jamshidifar H. and others. Adaptive vibration control of a flexible cable driven parallel robot. In 15th IFAC Symposium on Information Control Problems in Manufacturing (INCOM 2015), 2015.
- [jamshidifar2021] Jamshidifar H., Rushton M., and Khajepour A. A reaction-based stabilizer for nonmodel-based vibration control of cable-driven parallel robots. *IEEE Trans. on Robotics*, 37(2), April 2021.
- [jamwal2009] Jamwal P.K. and others . Kinematic design optimization of a parallel ankle rehabilitation robot using modified genetic algorithm. *Robotics and Autonomous Systems*, 57:1018–1027, 2009.
- [jamwal2010] Jamwal P.K. and others. Forward kinematics modelling of a parallel ankle rehabilitation robot using modified fuzzy inference. *Mechanism and Machine Theory*, 45(11):1537–1554, November 2010.
- [jamwal2010-1] Jamwal P.K. and others. Design analysis of a pneumatic muscle driven wearable parallel robot for ankle joint rehabilitation. In *IEEE/ASME International Conference on Mechatronic and Embedded Systems and Applications*, pages 403–408, Qingdao, 2010.
- [jamwal2014] Jamwal P.K. and others. An adaptive wearable parallel robot for the treatment of ankle injuries. *IEEE/ASME Trans. on Mechatronics*, 19(1), February 2014.
- [jamwal2015] Jamwal P.K. and others. Three-stage design analysis and multicriteria optimization of a parallel ankle rehabilitation robot using genetic algorithm. *IEEE Trans. on Automation Science and Engineering*, 12(4), November 2015.
- [jamwal2016] Jamwal P.K. and Hussain S. Multicriteria design optimization of a parallel ankle rehabilitation robot: Fuzzy dominated sorting evolutionary algorithm approach. *IEEE Trans. on Systems, Man, and Cybernetics Systems*, 46(5), May 2016.
- [jamwal2016-1] Jamwal P.K. and others . Impedance control of an intrinsically compliant parallel ankle rehabilitation robot. *IEEE Trans. on Industrial Electronics*, 63(6), June 2016.
- [janabi2004] Janabi-Sharifi F. and Shckokin B. A rotary parallel manipulator: modeling and workspace analysis. In *IEEE Int. Conf. on Robotics and Automation*, pages 3671–3677, New Orleans, April, 28-30, 2004.
- [jean96] Jean M. and Gosselin C. Static balancing of planar parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 3732–3737, Minneapolis, April, 24-26, 1996.
- [jeanneau2020] Jeanneau G. and others . R-min: a fast collaborative underactuated parallel robot for pick-and-place operations. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [jelenkovic2002] Jelenkovic L. and Budin L. Error analysis of a Stewart platform based manipulators. In *Int. Conf. on Intelligent Engineering Systems (INES)*, Opatija, May, 26-28, 2002.
- [jelenkovic2004] Jelenkovic L., Jakobovic D., and Budin L. Hexapod structure evaluation as web service. In *Int. Conf. on Informatics in Control, Automation and Robotics*, Setubal, August, 25-28, 2004.
- [jensen-ka-2006] Jensen K.A., Lusk C.P., and Howell L.L. An XYZ micromanipulator with three translational degrees of freedom. *Robotica*, 24(3):305–314, 2006.
- [jensen94] Jensen P.S. and others . Robotic micromanipulator for ophthalmic surgery. In 1st Int. Symp. on Medical Robotics and Computer assisted Surgery, pages 204–210, Pittsburgh, September, 22-24, 1994.
- [jeong-h2014] Jeong H. and others . Forward kinematic solution through geometry analysis for rehabilitation cable robot. In *Biomedical Engineering International Conference*, 2014.
- [jeong-ji-2002] Jeong J.I. and others . Kinematic calibration for redundantly actuated parallel mechanisms. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [jeong-ji-2004] Jeong J.I. and others . Kinematic calibration for redundantly actuated parallel mechanisms. ASME~J. of Mechanical~Design,~126(2):307–318,~March~2004.

- [jeong98] Jeong J.W., Kim S.H., and Kwak Y.K. Kinematic analysis of the wire parallel mechanism for full coordinate measuring of industrial robot. *KSME International Journal*, 12(6):1064–1072, 1998.
- [jeong99] Jeong J.W., Kim S.H., and Kwak Y.K. Kinematics and workspace analysis of a parallel wire mechanism for measuring a robot pose. *Mechanism and Machine Theory*, 34(6):825–841, August 1999.
- [jha2015] Jha R., Chablat D., Rouillier F., and Moroz G. Workspace and singularity analysis of a delta like family robot. In 4th IFToMM International Symposium on Robotics and Mechatronics, pages 121–130, Poitiers, 2015.
- [ji-j2009] Ji J., L. Sun., and Zhu Y. A novel high-speed and high-accuracy manipulator of planar five-link structure: modeling and calibration. *Advanced Robotics*, 23:89–112, 2009.
- [ji-p2000] Ji P. and Wu H.T. A fast solution to identity placement parameters for modular platform manipulators. *J. of Robotic Systems*, 17(5):251–253, 2000.
- [ji-p2001] Ji P. and Wu H.T. Algebraic solution to forward kinematics of a 3-dof spherical parallel manipulator. *J. of Robotic Systems*, 18(5):251–257, 2001.
- [ji-p2001-1] Ji P. and Wu H.T. A closed-form forward kinematics solution for the  $6-6^p$  Stewart platform. *IEEE Trans. on Robotics and Automation*, 17(4):522–526, August 2001.
- [ji-p2002] Ji P. and Wu H. An efficient approach to the forward kinematics of a planar parallel manipulator with similar platform. *IEEE Trans. on Robotics and Automation*, 18(4):647–649, August 2002.
- [ji93] Ji Z. Study of the effect of leg inertia in Stewart platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 121–126, Atlanta, May, 2-6, 1993.
- [ji94] Ji Z. Dynamic decomposition for Stewart platforms. ASME J. of Mechanical Design, 116(1):67–69, March 1994.
- [ji96] Ji Z. Analysis of design parameters in platform manipulators. ASME J. of Mechanical Design, 118(4):526–531, December 1996.
- [ji98] Ji Z. and Song P. Design of a reconfigurable platform manipulator. J. of Robotic Systems, 15(6):341–346, 1998.
- [ji98-1] Ji Z. and Leu M.C. Design, reconfiguration, and control of parallel robot machines. In *First European-American Forum on Parallel Kinematic Machines*, pages 111–129, Milan, August 31- September 1, 1998.
- [ji99] Ji Z. and Li Z. Identification of placement parameters for modular platform manipulators. *J. of Robotic Systems*, 16(4):227–236, 1999.
- [ji2003] Ji Z. Study of planer three-degree-of-freedom 2-RRR parallel manipulators. *Mechanism and Machine Theory*, 38(5):409–416, May 2003.
- [jia2020] Kia H. and others . Second-order sliding-mode-based synchronization control of cable-driven parallel robots.  $IEEE/ASME\ Trans.\ on\ Mechatronics,\ 26(1),\ February\ 2020.$
- [jiang-hz2011] Jiang H-Z. and others . Dynamic isotropic design for modified Gough-Stewart platforms lying on a pair of cicular hyperboloids. *Mechanism and Machine Theory*, 46(9):1301–1315, September 2011.
- [jiang-hz2011-1] Jiang H-Z. and others. Dynamic isotropic design of a class of Gough–Stewart parallel manipulators lying on a circular hyperboloid of one sheet. *Mechanism and Machine Theory*, 46:358–374, 2011.
- [jiang-l2015] Jiang L., Gao B., and Zhao J. Kinematic and static analysis of a cable-driven parallel robot with a flexible link spine. In *IEEE Conference on Robotics and Biomimetics*, Zhuhai, 2015.
- [jiang-q2008] Jiang Q. and Gosselin C.M. The maximal singularity-free workspace of the Gough-Stewart platform for a given orientation. ASME J. of Mechanical Design, 130(11):112304–1/8, November 2008.
- [jiang-q2008-1] Jiang Q. and Gosselin C.M. Singularity equations of Gough-Stewart platforms using a minimal set of geometrix parameters. ASME J. of Mechanical Design, 130(11):112303-1/7, November 2008.
- [jiang-q2009] Jiang Q. and Gosselin C.M. Determination of the maximal singularity-free orientation workspace for the Gough-Stewart platform. *Mechanism and Machine Theory*, 44(6):1281–1293, June 2009.

- [jiang-q2010] Jiang Q. and Kumar V. The inverse kinematics of 3-d towing. In ARK, pages 321–328, Piran, June 28-July 1, 2010.
- [jiang-q2010-1] Jiang Q. and Kumar V. The direct kinematics of objects suspended from cables. In ASME DETC, pages 193–202, Montréal, 2010.
- [jiang-q2013] Jiang Q. and Kumar V. The inverse kinematics of cooperative transport with multiple aerial robots. *IEEE Trans. on Robotics*, 29(1):136–145, July 2013.
- [jiang-s2012] Jiang S. and others . Kinematic analysis of a 5-dof hybrid-driven MRI compatible robot for minimally invasive prostatic interventions. *Robotica*, 30(7):1147–1156, December 2012.
- [jiang-s2015] Jiang S. and others . Accurate error compensation for a MR-compatible surgical robot based on a novel kinematic calibration method.  $Advanced\ Robotics,\ 29(18):1183-1194,\ 2015.$
- [jiang-x2016] Jiang X. and Gosselin C. Dynamic point-to-point planning of a three-dof cable-suspended parallel robot. *IEEE Trans. on Robotics*, 32(6):1550–1557, December 2016.
- [jiang-x2017] Jiang X. and Gosselin C. Dynamic transition trajectory planning of three-dof cable-suspended parallel robots. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [jiang-y2015] Jiang Y., Li T-M., and Wang L-P. Dynamic modeling and redundant force optimization of a 2-dof parallel kinematic machine with kinematic redundancy. *Robotics and Computer-Integrated Manufacturing*, 32:1–10, April 2015.
- [jiang-y2015-1] Jiang Y., Li T-M., and Wang L-P. The dynamic modeling, redundant-force optimization, and dynamic performance analyses of a parallel kinematic machine with actuation redundancy. *Robotica*, 33(2):241–263, February 2015.
- [jiang-y2018] Jiang Y. and others. Kinematic error modeling and identification of the over-constrained parallel kinematic machine. *Robotics and Computer-Integrated Manufacturing*, 49:105–119, 2018.
- [jiang-y2018-1] Jiang Y. and others . Improving tracking accuracy of a novel 3-dof redundant planar parallel kinematic machine. *Mechanism and Machine Theory*, 119:198–218, 2018.
- [jiang2001] Jiang H. and others . Effective envelope method for Stewart platform workspace. *Progress in Natural Science*, 11(2):129–134, February 2001.
- [jin-m-2016] Jin M. and Zhang X. A new topology optimization method for planar compliant parallel mechanisms. *Mechanism and Machine Theory*, 95:42–58, 2016.
- [jin-s2015] Jin S., Kim J., and Seo T. Optimization of a redundantly actuated 5R symmetrical parallel mechanism based on structural stiffness. *Robotica*, 33(9):1973–1980, November 2015.
- [jin-x2013] Jin X. and others . Four-cable-driven parallel robot. In 13th International Conference on Control, Automation and Systems, Gwangju, October, 20-23, 2013.
- [jin-x2014] Jin X. and others . Upper limb rehabilitation using a planar cable driven parallel robot with various rehabilitation strategy. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), Duisburg, August, 24-27, 2014.
- [jin-x2016] Jin X. and others. Geometric parameter calibration using a low cost laser distance sensor for a planar cable robot: MATLAB simulation. In 13th International Conference on Ubiquitous Robots and Ambient Intelligence (URAI), Xian, August, 19-22, 2016.
- [jin-x2017] Jin X. and others . A class of novel 2T2R and 3T2R parallel mechanisms with large decoupled output rotational angles. *Mechanism and Machine Theory*, 114:156–169, 2017.
- [jin-x2018] Jin X. and others . A class of novel 4-DOF and 5-DOF generalized parallel mechanisms with high performance. *Mechanism and Machine Theory*, 120:57–72, 2018.
- [jin-x2019] Jin X., Fang Y., and Zhang D. Design of a class of generalized parallel mechanisms with large rotational angles and integrated end-effectors. *Mechanism and Machine Theory*, 134:117–134, 2019.

- [jin-y2004] Jin Y., Chen I-M., and Yang G. Structure synthesis and singularity analysis of a parallel manipulator based on selective actuation. In *IEEE Int. Conf. on Robotics and Automation*, pages 4533–4538, New Orleans, April, 28-30, 2004.
- [jin-y2005] Jin Y. and Chen I-M. On the performance of a class of parallel manipulators with decoupled kinematic structure with stringent geometric constraints. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [jin-y2007] Jin Y., Chen I-M., and Yang G. Structure synthesis of 6-dof 3-3 decoupled parallel manipulators. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [jin2002] Jin Q. and Yang T-L. Synthesis and analysis of agroup of 3-degree-of-freedom decoupling parallel manipulators. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [jin2002-1] Jin Q. and Yang T-L. Structure synthesis of parallel manipulators with 3-dimension translation and 1-dimension rotation. In ASME 27th Biennial Mechanisms and Robotics Conf., Montréal, September 29- October 2, 2002.
- [jin2004] Jin Q. and Yang T-L. Theory for topology synthesis of parallel manipulators and its application to three-dimension-translation parallel manipulators. ASME J. of Mechanical Design, 126(1):625–639, January 2004.
- [jin2004-1] Jin Q. and Yang T-L. Synthesis and analysis of a group of 3-degree-of-freedom partially decoupled parallel manipulators. ASME J. of Mechanical Design, 126(2):301–306, March 2004.
- [jo89] Jo D.Y. and Haug E.J. Workspace analysis of closed loop mechanisms with unilateral constraints. In ASME Design Automation Conf., pages 53-60, Montréal, September, 17-20, 1989.
- [jordan-b-2007] Jordan B.L., Batalin M.A., and Kaiser W.J. NIMS RD: a rapidly deployable cable based robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 144–150, Roma, April, 10-14, 2007.
- [jordan2002] Jordan S. Approaches for minimizing tracking and vibratory errors in high-bandwidth beam steering. In 2nd Int. Workshop on Mechanical Eng. Design of Synchrotron Radiation Equipment and Instrumentation (MEDSI02), pages 299–307, Argonne, September, 5-6, 2002.
- [joshi2002] Joshi S.A. and Tsai L-W. Jacobian analysis of limited-dof parallel manipulators. ASME J. of Mechanical Design, 124(2):254–258, June 2002.
- [joshi2002-1] Joshi S.A. and Tsai L-W. A comparison study of two 3-DOF parallel manipulators: one with three and the other with four supporting legs. In *IEEE Int. Conf. on Robotics and Automation*, pages 3690–3697, Washington, May, 11-15, 2002.
- [joshi2002-2] Joshi S.A. and Tsai L-W. The kinematics of a class of 3-DOF, 4-legged parallel manipulators. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [joshi2002-3] Joshi S.A. and Tsai L-W. Jacobian analysis of limited-dof parallel manipulators. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [joshi2003] Joshi S.A. and Tsai L-W. The kinematics of a class of 3-DOF, 4-legged parallel manipulators. ASME J. of Mechanical Design, 125(1):52–60, March 2003.
- [joshi2003-1] Joshi S.A. and Tsai L-W. A comparison study of two 3-DOF parallel manipulators: one with three and the other with four supporting legs. *IEEE Trans. on Robotics and Automation*, 19(2):200–209, April 2003.
- [joshi2003-2] Joshi S.A. and Surianarayan A. Calibration of a 6-dof cable robot using two inclinometers. In *Performance Metrics for Intelligent Systems*, Gaithersburg, September, 16-18, 2003.
- [joshi2005] Joshi A. and Kim W-J. Modeling and multivariable control design methodologies for hexapod-based satellite vibration isolation. ASME J. of Dynamic Systems, Measurement and Control, 127(4):700–704, December 2005.
- [joubair 2013] Joubair A., Stamani M., and Bonev I.A. Kinematic calibration of a five-bar planar parallel robot using all working modes. *Robotics and Computer-Integrated Manufacturing*, 29(1):14–25, February 2013.
- [jovane2002] Jovane F. and others . Design issues for reconfigurable PKMs. In 3rd Chemnitzer Parallelkinematik Seminar, pages 69–82, Chemnitz, April, 23-25, 2002.

- [ju2022] Ju Y. and others. Constraint characteristics and type synthesis of two families of 1T2R parallel mechanism. *Robotica*, 40(9):3033–3056, January 2022.
- [jui2003] Jui C.K.K. and Sun Q. Path trackability and verification for parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 4336–4341, Taipei, September, 14-19, 2003.
- [jui2005] Jui C.K.K. and Sun Q. Path tracking of parallel manipulators in the presence of force singularity. ASME J. of Dynamic Systems, Measurement and Control, 127(4):550–563, December 2005.
- [jun99] Jun S.H., Zheng L.Q., and Gao L.C. Direct positional analysis for a kind of 5-5 platform in-parallel robotic mechanism. *Mechanism and Machine Theory*, 34(2):285–301, February 1999.
- [jung-hk2006] Jung H.K., Crane III C.D., and Roberts R.G. Stiffness mapping of planar compliant parallel mechanisms in a serial arrangement. In *ARK*, pages 85–94, Ljubljana, June, 26-29, 2006.
- [jung-hk2008] Jung H.K., Crane III C.D., and Roberts R.G. Stiffness mapping of compliant parallel mechanisms in a serial arrangement. *Mechanism and Machine Theory*, 43(3):271–284, March 2008.
- [jung-j2016] Jung J. and others . Analysis of cable tension of high speed parallel cable robot: high speed position tracking of winch. In 16th International Conference on Control, Automation and Systems (ICCAS), Gyongju, October, 16-19, 2016.
- [jung-j2018] Jung J. and others . A cable-driven parallel robot remotely controlled by a human-driven parallel cable robot. In ISR, 2018.
- [jung93] Jung G.H. and Lee K.I. Real-time estimation of the Stewart platform forward kinematics solution. In *SICE*, pages 1239–1244, Kanazawa, August, 4-6, 1993.
- [kallio98] Kallio P. and others . Position control of a 3 dof piezohydraulic parallel micromanipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Victoria, October 1998.
- [kaloorazi2014] Kaloorazi M.F., Masouleh M.T., and Caro S. Collision-free workspace of a 3-RPR planar parallel mechanism via interval analysis. In ARK, Ljulbjana, June 29- July 3, 2014.
- [kaloorazi2015] Kaloorazi M.F., Masouleh M.T., and Caro S. Determination of the maximal singularity-free workspace of 3-dof parallel mechanisms with a constructive geometric approach. *Mechanism and Machine Theory*, 84, 2015.
- [kaloorazi2016] Kaloorazi M.H.E., Masouleh M.T., and Caro S. Determining the maximal singularity-free circle or sphere of parallel mechanisms using interval analysis. *Robotica*, 34(1):135–149, January 2016.
- [kaloorazi2017] Kaloorazi M.H.E., Masouleh M.T., and Caro S. Collision-free workspace of parallel mechanisms based on an interval analysis approach. *Robotica*, 35:1747–1760, 2017.
- [kaloorazi2018] Kaloorazi M.F., Masouleh M.T., and Caro S. Collision-free workspace of parallel mechanisms based on an interval analysis approach. *Robotica*, 35(8), 2018.
- [kamra2002] Kamra R., Kohli D., and Dhingra A.K. Forward displacement analysis of a six-dof parallel manipulator actuated by 3R3P and 4R2P chains. *Mechanism and Machine Theory*, 37(6):619–637, June 2002.
- [kanaan2007] Kanaan D., Wenger P., and Chablat D. Kinematics analysis of the parallel module of the VERNE machine. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [kanaan2007-1] Kanaan D., Wenger P., and Chablat D. Workspace and kinematic analysis of the VERNE machine. In AIM, Zurich, September 2007.
- [kanaan 2008] Kanaan D., Wenger P., and Chablat D. Singularity analysis of limited-dof parallel manipulators using Grassmann-Cayley algebra. In ARK, pages 59–68, Batz/mer, June, 23-26, 2008.
- [kanaan2009] Kanaan D., Wenger P., and Chablat D. Kinematic analysis of a serial-parallel machine-tool: the VERNE machine. *Mechanism and Machine Theory*, 44(2):487–498, February 2009.

- [kanaan2009-1] Kanaan D. and others . Singularity analysis of lower mobility parallel manipulators using Grass-mann-Cayley Algebra. *IEEE Trans. on Robotics*, 25(5):995–1004, 2009.
- [kang-b-2001] Kang B., Chu J., and Mills J.K. Design of high speed planar parallel manipulator and multiple simultaneous specification control. In *IEEE Int. Conf. on Robotics and Automation*, pages 2723–2728, Seoul, May, 23-25, 2001.
- [kang-b-2002] Kang B. and Mills J.K. Dynamic modeling of structurally flexible planar parallel manipulator. *Robotica*, 20(3):329–339, May 2002.
- [kang-b-2002-1] Kang B., Yeung B., and Mills J.K. Two-time scale controller design for a high speed planar parallel manipulator with structural flexibility. *Robotica*, 20(5):519–528, September 2002.
- [kang-b-2008] Kang B. and Mills J.K. Parallel manipulators, New Developments, chapter Dynamic modeling and vibration control of a planar parallel manipulator with structurally flexible linkages, pages 405–426. ITECH, April 2008. **Keywords:** planar robot, dynamics, vibration, control, piezo-electric.
- [kang-bh-2004] Kang B.H. and others . Analysis and design of parallel mechanisms with flexure joints. In *IEEE Int. Conf. on Robotics and Automation*, pages 4097–4102, New Orleans, April, 28-30, 2004.
- [kang-h-2018] Kang H.Y. and others . Flotation simulation in a cable-driven virtual environment a study with parasailing. In *Conference on Human Factors in Computing Systems*, Montréal, April, 21-26, 2018.
- [kang-jy98] Kang J-Y., Kim D.H., and Lee K-I. Robust estimator for forward kinematics solution of a Stewart platform. J. of Robotic Systems, 15(1):29–42, 1998.
- [kang-r-2012] Kang R. and others . Learning the forward kinematics behavior of a hybrid robot employing artifical neural networks. *Robotica*, 30(5):847–855, September 2012.
- [kang-sr2018] Kang S-R. and others . Controllable magnetorheological fluid based actuators for 6-degree-of-freedom haptic master applicable to robot-assisted surgery. Sensors and Actuators, A(279):649–662, 2018.
- [kang90] Kang H.J. and Freeman R.A. An interactive software package (MAP) for the dynamic modeling and simulation of parallel robotic systems including redundancy. In *ASME Int. Computer in Engineering Conf.*, pages 117–123, Boston, September, 5-9, 1990.
- [kansal2022] Kansal S. and Mukherjee S. Vision-based kinematic analysis of the Delta robot for object catching. *Robotica*, 40:2010–2030, 2022.
- [kapur2007] Kapur P., Ranganath R., and Nataraju B.S. Analysis of Stewart platform with flexural joints at singular configurations. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [karboub2004] Karboub M. and others . Neural-net tuned PID control of a parallel type mechanism with force-feedback for virtual reality applications. Robotica, 22(3):319–327, 2004.
- [karboub2012] Karboub M. and others . Design and control of a cable controlled haptic motion simulator. *Robotica*, 30(5):709–719, Septembre June 2012.
- [kardan2015] Kardan I. and Akbarzadeh A. An improved hybrid method for forward kinematics analysis of parallel robots. *Advanced Robotics*, 29(6):401–411, 2015.
- [karger96] Karger A. and Husty M. On self-motions of a class of parallel manipulators. In ARK, pages 339–348, Portoroz-Bernadin, June, 22-26, 1996.
- [karger98] Karger A. Architecture singular parallel manipulators. In ARK, pages 445–454, Strobl, June 29- July 4, 1998.
- [karger98-1] Karger A. and Husty M. Classification of all self-motion of the original Stewart-Gough platform. Computer-aided design, 30(3):205–215, 1998.
- [karger98-2] Karger A. Classification of 5R closed kinematic chains with self mobility. *Mechanism and Machine Theory*, 33(1-2):213–222, January 1998.

- [karger2001] Karger A. Singularities and self-motions of equiform platforms. *Mechanism and Machine Theory*, 36(8):801–815, August 2001.
- [karger2002] Karger A. Singularities and self-motions of a special type of platforms. In ARK, pages 155–164, Caldes de Malavalla, June 29- July 2, 2002.
- [karger2003] Karger A. Architecture singular planar parallel manipulators. *Mechanism and Machine Theory*, 38(11):1149–1164, November 2003.
- [karger2006] Karger A. Stewart-Gough platforms with simple singularity surface. In ARK, pages 247–254, Ljubljana, June, 26-29, 2006.
- [karger2008] Karger A. Architecturally singular non-planar parallel manipulators. *Mechanism and Machine Theory*, 43(3):335–346, March 2008.
- [karger2008-1] Karger A. Parallel manipulators with simple geometrical structure. In 2nd European Conf. on Mechanism Science (Eucomes), Cassino, September, 17-20, 2008.
- [karger2010] Karger A. Self-motions of 6-3 Stewart-Gough type parallel manipulators. In ARK, pages 359–366, Piran, June 28- July 1, 2010.
- [karimi-a-2016] Karimi A., Masouleh M.T., and Cardou P. Avoiding the singularities of 3-RPR parallel mechanisms via dimensional synthesis and self-reconfigurability. *Mechanism and Machine Theory*, 101:168–180, 2016.
- [karimi-a2014] Karimi A., Masoulet M.T., and Cardou P. The dimensional synthesis of  $3 R\underline{P}R$  parallel mechanisms for a described singularity-free constant-orientation workspace. In ARK, Ljulbjana, June 29- July 3, 2014.
- [karimi2014] Karimi D. and Nategh M.J. Kinematic non linearity analysis in hexapod machine-tools: symmetry and regional accuracy of workspace. *Mechanism and Machine Theory*, 71:115–125, 2014.
- [karman2020] Karman M.K. and others . Computation of the safe working zones of planar and spatial parallel manipulators. *Robotica*, 38:861–885, 2020.
- [karouia2000] Karouia M. and Hervè J.M. A three-dof tripod for generating spherical motion. In ARK, pages 395–402, Piran, June, 25-29, 2000.
- [karouia2002] Karouia M. and Hervè J.M. An orientational 3-dof parallel mechanisms. In 3rd Chemnitzer Parallelkinematik Seminar, pages 139–150, Chemnitz, April, 23-25, 2002.
- [karouia2002-1] Karouia M. and Hervè J.M. A family of novel orientational 3-dof parallel robots. In 14th RoManSy, pages 359–368, Udine, July, 1-4, 2002.
- [karouia2003] Karouia M. and Hervè J.M. Enumération de mécanismes parallèles sphériques isostatiques. In 16eme Congrès Français de Mécanique, Nice, September, 1-5, 2003.
- [karouia2005] Karouia M. and Hervè J.M. Asymmetrical 3-dof spherical parallel mechanisms. European Journal of Mechanics A/Solids, 24(1):47–57, February 2005.
- [karouia2006] Karouia M. and Hervè J.M. Non-overconstrained 3-dof spherical parallel manipulators of type 3-RCC, 3-CRR, 3-CRC. *Robotica*, 24(1):85–94, January 2006.
- [kassner90] Kassner D.J. Kinematics analysis of a planar three-degree-of-freedom platform-type robot manipulator. Master's thesis, Purdue University, Purdue, December 1990. **Keywords:** planar robot,kinematics,singularity,workspace,maximal workspace.
- [katliar2017] Katliar M., Fischer J., Frison G, Diehl M., Teufel H., and Bülthoff H.H. Nonlinear model predictive control of a cable-robot-based motion simulator. In 20th IFAC World Congress, 2017.
- [kawamura95] Kawamura S. and others . Development of an ultrahigh speed robot FALCON using wire drive system. In *IEEE Int. Conf. on Robotics and Automation*, pages 215–220, Nagoya, May, 25-27, 1995.
- [kawamura 2000] Kawamura S. and others . High-speed manipulation by using parallel wire-driven robots. Robotica, 18(1):13-21, January 2000.

- [kazerounian2002] Kazerounian K. Is design of new drugs a challenge for kinematics? In ARK, pages 135–144, Caldes de Malavalla, June 29- July 2, 2002.
- [kelaiaia2012] Kelaiaia R., Company O., and Zaatri A. Multiobjective optimization of parallel kinematic mechanisms by the genetic algorithms. *Robotica*, 30(5):783–797, 2012.
- [kelaiaia2012-1] Kelaiaia R., Zaatri A., and Company O. Multiobjective optimization of 6-dof UPS parallel manipulators. *Advanced Robotics*, 26:1885–1913, 2012.
- [kelaiaia2012-2] Kelaiaia R., Company O., and Zaatri A. Multiobjective optimization of a linear Delta parallel robot. Mechanism and Machine Theory, 50:159–178, 2012.
- [kelaiaia2012-phd] Kelaiaia R. Contribution à la conception optimale de machine-outils parallèles. Ph.D. Thesis, Université de Skikda, Skikda, April 2012. **Keywords:** optimal design,machine-tool,structural synthesis.
- [kelaiaia2016] Kelaiaia R. and others . Some investigations into the optimal dimensional synthesis of parallel robots. The International Journal of Advanced Manufacturing Technology, 83:1525–1538, 2016.
- [kelemen96] Kelemen A. and others . DSP-based control of a parallel-robot drive with permanent-magnet synchronous servomotors. *Electromotion*, 3:181–186, 1996.
- [keler98] Keler M.L. Dual expansion of an optimal spherical platform device. In ARK, pages 79–86, Strobl, June 29–July 4, 1998.
- [kermanian2019] Kermanian A. and others . Dynamic analysis of flexible parallel robots via enhanced co-rotational and rigid finite element formulations. *Mechanism and Machine Theory*, 139:144–173, 2019.
- [kerr88] Kerr D.R. Analysis, properties, and design of a Stewart-platform transducer. In ASME Design Technology Conf., pages 139–145, New-York, 1988.
- [kerr89] Kerr D.R. Analysis, properties, and design of a Stewart-platform transducer. J. of Mechanisms, Transmissions and Automation in Design, 111(1):25–28, March 1989.
- [kerr92] Kerr D.R., Griffis M., Sanger D.J., and Duffy J. Redundant grasps, redundant manipulators and their dual relationships. *J. of Robotic Systems*, 9(7):973–1000, 1992.
- [keshtkar2017] Keshtkar S. and others . Adaptive sliding-mode controller based on the "super-twist" state observer for control of the Stewart platform. *Nonlinear Systems*, 78(7):1218–1233, 2017.
- [kevac2017] Kevac L., Filipovic M., and Racik A. The trajectory generation algorithm for the cable-suspended parallel robot- the CPR trajectory solver. *Robotics and Autonomous Systems*, 94:25–33, 2017.
- [khakpour2014] Khakpour H., Birglen L., and S-A. Tahan. Synthesis of differentially driven planar cable parallel manipulators. *IEEE Trans. on Robotics*, 30(3), June 2014.
- [khalid2018] Khalid A. and Mekid S. Intelligent spherical joints based tri-actuated spatial parallel manipulator for precision applications. *Robotics and Computer-Integrated Manufacturing*, 54:173–184, 2018.
- [khalil99] Khalil W. and Besnard S. Self calibration of Stewart-Gough parallel robot without extra sensors. *IEEE Trans. on Robotics and Automation*, 15(6):1116–1121, December 1999.
- [khalil2001] Khalil W. and Besnard S. Identificable parameters for the geometric calibration of parallel robots. *Archive of Control Sciences*, 11(3-4):263–277, 2001.
- [khalil2002] Khalil W. and Guegan S. A novel solution for the dynamic modeling of Gough-Stewart manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 817–822, Washington, May, 11-15, 2002.
- [khalil2004] Khalil W. and Ibrahim O. General solution for the dynamic modeling of parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 3665–3670, New Orleans, April, 28-30, 2004.
- [khalil2004-1] Khalil W. and Guegan S. Inverse and direct dynamic modeling of Gough-Stewart robots. *IEEE Trans. on Robotics*, 20(4):755–761, August 2004.
- [khalil2007] Khalil W. and Ibrahim O. General solution for the dynamic modeling of parallel robots. *J. of Intelligent and Robotic Systems*, 49(1):19–37, May 2007.

- [khalilpour 2012] Khalilpour S.A. and others . Feasible kinematic sensitivity in cable robots based on interval analysis. In 1st Int. Conf. on cable-driven parallel robots (Cable Con), pages 233–249, Stuttgart, September, 3-4, 2012.
- [khan-2005] Khan W.A. and others . Recursive kinematics and inverse dynamics for a planar 3R parallel manipulator. ASME J. of Dynamic Systems, Measurement and Control, 127(4):529–536, December 2005.
- [khan-2005-1] Khan W.A. and others . Modular and recursive kinematics and dynamics for parallel manipulators. *Multibody System Dynamics*, 14:419–455, 2005.
- [khanzode2022] Kahnzode D. and others . Stacked tensegrity mechanism for medical application. In ARK, Bilbao, June, 26-30, 2022.
- [khatib88] Khatib O. Inertial characteristics and dextrous dynamic coordination of macro/micro manipulator systems. In 7th CISM-IFToMM Symposium on Theory and Practice of Robots and Manipulators, Udine, Italie, September 1988.
- [khatib96] Khatib O. and Bowling A. Optimization of the inertial and acceleration characterics of manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2883–2889, Minneapolis, April, 24-26, 1996.
- [khayour2020] Khayour I. and others . Improving disturbance rejection and dynamics of cable driven parallel robots with on-board propellers. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October, 25-29, 2020.
- [khoshbin2022] Khoshbin E., Youssef K., Meziane R., and Otis M.J.-D. Reconfigurable fully constrained cable-driven parallel mechanism for avoiding collision between cables with human. *Robotica*, pages 1–26, 2022.
- [khosravi2014] Khosravi M. and Taghirad H.D. Robust PID control of fully constrained cable-driven parallel robots. *Mechatronics*, 24:87–97, 2014.
- [khosravi2014-1] Khosravi M. and Taghirad H.D. Dynamic modeling and control of parallel robots with elastic cables: singular perturbation approach. *IEEE Trans. on Robotics*, 30:694–704, 2014.
- [khosravi2014-2] Khosravi M. and Taghirad H.D. Dynamic analysis and control of fully-constrained cable robots with elastic cables: variable stiffness formulation. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), Duisburg, August, 24-27, 2014.
- [khosravi2012] Khosravi M. and Taghirad H. Experimental performance of robust PID controller on a planar cable robot. In 1st Int. Conf. on cable-driven parallel robots (CableCon), pages 337–352, Stuttgart, September, 3-4, 2012.
- [khoukhi2009] Khoukhi A., Baron L., and Balazinski M. Constrained multi-objective trajectory planning of parallel kinematic machines. *Robotics and Computer-Integrated Manufacturing*, 25(4-5):756–769, August 2009.
- [kim-hw-2001] Kim H.W. and others . A transparency-optimized control for a 6-dof parallel-structured haptic device. In *IEEE Int. Conf. on Robotics and Automation*, pages 2331–2336, Seoul, May, 23-25, 2001.
- [kim-js2003] Kim J. and others . Design of a parallel mechanism platform for simulating six degrees-of- freedom general motion including continuous 360-degree spin. *Annals of the CIRP*, 52(1):347–3502, 2003.
- [kim-js2015] Kim J.S., Jeong J.H., and Park J.H. Inverse kinematics and geometric singularity analysis of a 3-SPS/S redundant motion mechanism using conformal geometric algebra. *Mechanism and Machine Theory*, 90:23–36, August 2015.
- [kim-k2003] Kim K., Chung W.K., and Youm Y. Design and analysis of a new 7-dof parallel type haptic device: PATHOS-i1. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October 2003.
- [kim-s97] Kim K. Operational quality analysis of parallel manipulators with actuation redundancy. In *IEEE Int. Conf. on Robotics and Automation*, Albuquerque, April, 21-28, 1997.
- [kim-sm2009] Kim S.M., Kim W., and Yi B-J. Kinematic analysis and optimal design of a 3T1R type parallel mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 2199–2204, Kobe, May, 14-16, 2009.
- [kim-ys2029] Kim Y-S. and others . Design of a six-dof motion tracking system based on a Stewart platform and ball-and-socket joints. *Mechanism and Machine Theory*, 133:84–94, 2019.

- [kim97] Kim D.I., Ching W.K., and Youm Y. Geometrical approach for the workspace of 6-dof parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2986–2991, Albuquerque, April, 21-28, 1997.
- [kimd98] Kim D., W. Chung, and Youm Y. Analytic singularity expression for 6-dof Stewart platform-type parallel manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1015–1020, Victoria, October 1998.
- [kimd99] Kim D. and W. Chung. Analytic singularity equation and analysis of six-dof parallel manipulators using local structurization method. *IEEE Trans. on Robotics and Automation*, 15(4):613–622, August 1999.
- [kimd2000] Kim D., W. Chung, and Youm Y. Analytic jacobian of in-parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2376–2381, San Francisco, April, 24-28, 2000.
- [kimd2003] Kim D. and W.K. Chung. Analytic formulation of reciprocal screws and its application to nonredundant robot manipulators. ASME J. of Mechanical Design, 125(1):158–164, March 2003.
- [kimd2003-1] Kim D. and W.K. Chung. Kinematic condition analysis of three-dof pure translational parallel manipulators. ASME J. of Mechanical Design, 125(2):323–331, June 2003.
- [kimdh2000] Kim D.H, Kang J-Y., and Lee K-I. Robust tracking control design for a 6 dof parallel manipulator. *J. of Robotic Systems*, 17(10):527–547, 2000.
- [kimdh2000-1] Kim D.H, Kang J-Y., and Lee K-I. Robust nonlinear observer for forward kinematics solution of a Stewart platform: an experimental verification. *Robotica*, 18(6):601–610, November 2000.
- [kimhs-2000] Kim H.S. and Choi Y.J. The kinematic error bound analysis of the Stewart platform. *J. of Robotic Systems*, 17(1):63–73, 2000.
- [kimhs-2001] Kim H.S. and Choi Y.J. Forward/inverse force transmission capability analyses of fully parallel manipulators. *IEEE Trans. on Robotics and Automation*, 17(4):526–531, August 2001.
- [kimhs-2002] Kim H.S. and Tsai L-W. Evaluation of a cartesian parallel manipulator. In ARK, pages 21–28, Caldes de Malavalla, June 29- July 2, 2002.
- [kimhs-2002-1] Kim H.S. and Tsai L-W. Design optimization of Cartesian parallel manipulator. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [kimhs-2002-2] Kim H.S. and Tsai L-W. Kinematic synthesis of a spatial 3-RPS parallel manipulator. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [kimhs-2003] Kim H.S. and Tsai L-W. Kinematic synthesis of a spatial 3-RPS parallel manipulator. ASME J. of Mechanical Design, 125(1):92–97, March 2003.
- [kimhs-2003-1] Kim H.S. and Tsai L-W. Design optimization of Cartesian parallel manipulator. ASME J. of Mechanical Design, 125(1):43–51, March 2003.
- [kimhs-2008] Kim H.S. Parallel manipulators, New Developments, chapter Task space approach of robust non linear control for a 6-dof parallel manipulator, pages 427–444. ITECH, April 2008. **Keywords:** dynamics,control.
- [kimj2000] Kim J. and Park F.C. Elasto-kinematic design tools for parallel mechanisms. In ARK, pages 295–304, Piran, June, 25-29, 2000.
- [kimj2000-1] Kim J., Park F.C., and Kim M. Geometric design tools for stiffness and vibration analysis of robotic mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 1942–1947, San Francisco, April, 24-28, 2000.
- [kimj2001] Kim J. and Park F.C. Direct kinematics analysis of 3-RS parallel mechanisms. *Mechanism and Machine Theory*, 36(10):1121–1134, October 2001.
- [kimj2001-1] Kim J. and others . Eclipse-II: a new parallel mechanism enabling continuous 360-degree spinning plus three-axis translational motions. In *IEEE Int. Conf. on Robotics and Automation*, pages 3274–3279, Seoul, May, 23-25, 2001.

- [kimj2001-2] Kim J. and others . Design analysis of a redundantly actuated parallel mechanism for rapid machining. *IEEE Trans. on Robotics and Automation*, 17(4):423–434, August 2001.
- [kimj2002] Kim J. and others . Eclipse II: a new parallel mechanism enabling continuous 360-degree spinning plus three-axis translational motions. *IEEE Trans. on Robotics and Automation*, 18(3):367–373, June 2002.
- [kimni2001] Kim N-I and Lew C-W. Multi-axis vibration control of a slender structure by using Stewart platform manipulator. *Mechanism and Machine Theory*, 36(11-12):1253–1269, November 2001.
- [kimsg2001] Kim S-G. and Ryu J. Optimal design of 6 dof parallel manipulators using three point coordinates. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2178–2182, Maui, Hawaii, October 29-November 3, 2001.
- [kimsg2003] Kim S-G. and Ryu J. New dimensionally homogeneous jacobian matrix formulation by three end-effector points for optimal design of parallel manipulators. *IEEE Trans. on Robotics and Automation*, 19(4):731–736, August 2003.
- [kimts2006] Kim T.S., Park K.W., and Lee M.K. Study on observability of a parallel-types machining centers using a single planar table and digital indicators. *Mechanism and Machine Theory*, 41(10):1147–1156, October 2006.
- [kimwk97] Kim W-K., Lee J-Y., and Yi B.J. Analysis for a planar 3 degree-of-freedom parallel mechanism with actively adjustable stiffness characteristics. In *IEEE Int. Conf. on Robotics and Automation*, pages 2663–2670, Albuquerque, April, 21-28, 1997.
- [kimwk2000] Kim W-K., Yi B.J., and Cho W. RCC characteristics of planar/spherical three degree-of-freedom parallel mechanism with joint compliance. ASME J. of Mechanical Design, 122(1):10–16, March 2000.
- [kimwk2001] Kim W-K., Byun Y.K., and Cho W. Closed-form forward-position solution for a 6-Dof 3-PPSP parallel mechanism and its implementation. *Int. J. of Robotics Research*, 20(1):85–99, January 2001.
- [kimwk2004] Kim W.K. and others . Singularity-free load distribution for a 6-dof parallel haptic device. In *IEEE Int. Conf. on Robotics and Automation*, pages 298–304, New Orleans, April, 28-30, 2004.
- [king73] King R.F. A flight simulator for advanced aircraft-servo: design to realization. In *Summer Computation Simulation Conf.*, pages 248–253, Montréal, July, 13-19, 1973.
- [kingsley99] Kingsley J.S., Martin R.N., and Gasho V.L. A hexapode 12m antenna design concept for the MMA. Research Report 263, MMA, May, 7, 1999.
- [kino2002] Kino H. and Kawamura S. Development of a serial link structure/parallel wire system for a force display. In *IEEE Int. Conf. on Robotics and Automation*, pages 829–834, Washington, May, 11-15, 2002.
- [kino2007] Kino H. and others . Robust PID control using adaptive compensation for completely restrained parallel -wire driven parallel robots: translational systems using the minimum number of wires under zero-gravity condition. *IEEE Trans. on Robotics*, 23(4):803–811, August 2007.
- [kino2018] Kino H. and others . 3-dof planar parallel-wire driven robot with an active balancer and its model-based adaptive control. *Advanced Robotics*, 32(14):766–777, 2018.
- [kirchgessner 2016] Kirchgessner N. and others . The ETH field phenotyping platform FIP: a cable-suspended multi-sensor system. Functional Plant Biology, 44:154–168, 2016.
- [kirchhoff2010] Kirchhof M.R. and Büttgenbach S. MEMS fluxgate magnetometer for parallel robot application. *Microsyst Techno*, 16:787–790, 2010.
- [klein2010] Klein J. and others . Optimization of a parallel shoulder mechanism to achieve a high-force, low-mass, robotic-arm exoskeleton.  $IEEE\ Trans.\ on\ Robotics,\ 26(4):710-715,\ August\ 2010.$
- [kleinfinger86] Kleinfinger J.F. Modélisation dynamique de robots à chaînes cinématiques simple arborescente ou fermée en vue de leur commande. Ph.D. Thesis, Université de Nantes, Nantes, May, 16, 1986. **Keywords:** dynamics.

- [klimchik2011-phd] Klimchik A. Enhanced stiffness modelling of serial and parallel manipulators for robotic-based processing of high performance materials. Ph.D. Thesis, Ecole Centrale, Nantes, October, 27, 2011. **Keywords:** stiffness,machine-tool.
- [klimchik2012] Klimchik A. and others . Compensation of compliance errors in parallel manipulators composed of non-perfect kinematic chains. In ARK, pages 51–58, Innsbruck, June, 25-28, 2012.
- [klimchik2012-1] Klimchik A. and others . Stiffness matrix of manipulators with passive joints: computational aspects. *IEEE Trans. on Robotics*, 28(4):955–961, August 2012.
- [klimchik2012-2] Klimchik A., Pashkevich A., and Chablat D. Stiffness modeling of non-perfect parallel manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Vilamoura, October, 7-12, 2012.
- [klimchik2015] Klimchik A. and others . Static stability of manipulator configuration: influence of the external loading.  $European\ Journal\ of\ Mechanics\ A/Solids,\ 51:193-203,\ 2015.$
- [klinkhamer 2003] Klinkhamer F. An adjustment for five degrees of freedom as an alternative for a hexapod mechanism. In SPIE Optomechanics 2003, San-Diego, August, 3-8, 2003.
- [knapczyk92] Knapczyk J. and Dzierzek S. Kinematic analysis of 6S-5S type Stewart platform mechanism by using vector method. In *ARK*, pages 123–128, Ferrare, September, 7-9, 1992.
- [knapczyk96] Knapczyk J. and Tora G. An inverse force analysis of the spherical 3-dof parallel manipulator with three linear actuators considered as spring system. In 11th RoManSy, pages 53–60, Udine, July, 1-4, 1996.
- [knapczyk98] Knapczyk J. and Dzierzek S. Elastokinematic analysis of the 6-5 in-parallel mechanism with translational springs supporting the platform. In 12th RoManSy, pages 88–94, Paris, July, 6-9, 1998.
- [knapczyk2007] Knapczyk J. and Maniowski M. Estimation of line and torsional stiffness parameters for legs of 6dof parallel mechanism. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [baiko2015] Ko S. and others . Cable-driven parallel robot for cleaning of ship hull, 2015. Patent KR20150114136A. **Keywords:** patent,wire robot,marine.
- [kobler2014] Kobler J-P. and others . Design optimization of a bone-articulated, redundant and reconfigurable parallel kinematic device for skull surgery. In *IEEE Int. Conf. on Robotics and Automation*, Hong-Kong, 7 June 31-June , 2014.
- [kochan96] Kochan A. Parallel robot perfect propellors. Industrial Robot, 23(4):27–30, 1996.
- [kock98] Kock S. and Schumacher W. A parallel x-y manipulator with actuation redundancy for high speed and active stiffness applications. In *IEEE Int. Conf. on Robotics and Automation*, pages 2295–2300, Louvain, May, 18-20, 1998.
- [kock98-1] Kock S. Regelungsstrategien für parallel roboter mit redundanten antrieben. In New machine concepts for handling and manufacturing devices on the basis of parallel structures, pages 155–164, Braunschweig, November, 10-11, 1998.
- [kock2000] Kock S. and Schumacher W. Control of a fast parallel robot with a redundant chain and gear-boxes:experimental results. In *IEEE Int. Conf. on Robotics and Automation*, pages 1924–1929, San Francisco, April, 24-28, 2000.
- [kock2000-1] Kock S. and Schumacher W. A mixed elastic and rigid-body dynamic model of an actuation redundant parallel robot with high-reduction gears. In *IEEE Int. Conf. on Robotics and Automation*, pages 1918–1923, San Francisco, April, 24-28, 2000.
- [koessler2017] Koessler A. and others . Certified detection of parallel robot assembly mode under type 2 singularity crossing trajectories. In *IEEE Int. Conf. on Robotics and Automation*, 2017.
- [koessler2020] Koessler A. and others . Dynamics-based algorithm for reliable assembly mode tracking in parallel robot. *IEEE Trans. on Robotics*, 36(3), June 2020.

- [koevermans75] Koevermans W.P. and others . Design and performance of the four d.o.f. motion system of the NLR research flight simulator. In AGARD Conf. Proc. No 198, Flight Simulation, pages 17–1/17–11, La Haye, October, 20-23, 1975.
- [kohli88] Kohli D., Lee S-H, Tsai K-Y, and Sandor G.N. Manipulator configurations based on Rotary-Linear (R-L) actuators and their direct and inverse kinematics. *J. of Mechanisms, Transmissions and Automation in Design*, 110(4):397–404, December 1988.
- [kokkinis90] Kokkinis T. and Millies P. A dynamically redundant parallel manipulator. In *ISRAM*, pages 527–532, Burnaby, July, 18-20, 1990.
- [kokkinis91] Kokkinis T. and Millies P. A parallel robot-arm regional structure with actuational redundancy. *Mechanism and Machine Theory*, 26(6):629–641, 1991.
- [kokkinis92] Kokkinis T. and Millies P. Kinetostatic performance of a dynamically redundant parallel robot. *Int. J. of Robotics and Automation*, 7(1):30–37, 1992.
- [kolbus 2006] Kolbus ., M, Stachera K., and Schumacher W. Estimation of the payload mass of a flexible parallel robot. In 5th Chemnitzer Parallelkinematik Seminar, pages 429–442, Chemnitz, April, 25-26, 2006.
- [koliskor86] Koliskor A. Sh. The l-coordinate approach to the industrial robot design. In VIFAC/IFIP/IMACS/IFORS Symposium, pages 108–115, Suzdal, URSS, April, 22-25, 1986.
- [khong-l-2018] Kong L. and others . Kinematic calibration and investigation of the influence of universal joint errors on accuracy improvement for a 3-dof parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 49:388–397, 2018.
- [kong94] Kong X-W. and Yang T-L. Generation and forward displacement analyses of two new classes of analytic 6 SPS parallel robot. In ASME Design Automation Conf., pages 293–300, Minneapolis, September, 11-14, 1994.
- [kong2001] Kong X. and Gosselin C.M. Generation of architecturally singular 6-SPS parallel manipulators with linearly related planar platforms. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 67–75. EJCK, May, 20-22, 2001. **Keywords:** singularity, singular robot, singular motion.
- [kong2001-1] Kong X. and Gosselin C.M. Uncertainty singularity analysis of parallel manipulators based on the instability analysis of structures. *Int. J. of Robotics Research*, 20(11):847–856, November 2001.
- [kong2001-2] Kong X. and Gosselin C.M. Forward displacement analysis of third-class analytic 3-RPR planar parallel manipulators. *Mechanism and Machine Theory*, 36(9):1009–1018, September 2001.
- [kong2002] Kong X. and Gosselin C.M. A class of 3-dof translational parallel manipulators with linear input-output equations. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, pages 25–32, Québec, October, 3-4, 2002.
- [kong2002-1] Kong X. and Gosselin C.M. Generation and forward displacement analysis of RPR-PR-RPR analytic planar parallel manipulators. ASME J. of Mechanical Design, 124(2):294–300, June 2002.
- [kong2002-2] Kong X. and Gosselin C.M. Kinematics and singularity analysis of a novel type of 3-<u>CRR</u> 3-dof translational parallel manipulator. *Int. J. of Robotics Research*, 21(9):791–798, September 2002.
- [kong2002-3] Kong X. and Gosselin C.M. Type synthesis of linear translational parallel manipulators. In ARK, pages 453–462, Caldes de Malavalla, June 29- July 2, 2002.
- [kong2002-4] Kong X. and Gosselin C.M. Type synthesis of 3-dof spherical parallel manipulators based on screw theory. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [kong2004] Kong X. and Gosselin C.M. Type synthesis of three-degree-of-freedom spherical parallel manipulators. *Int. J. of Robotics Research*, 23(3):237–245, March 2004.
- [kong2004-1] Kong X. and Gosselin C.M. Type synthesis of 3-dof spherical parallel manipulators based on screw theory. ASME J. of Mechanical Design, 126(1):101–108, January 2004.
- [kong2004-2] Kong X. and Gosselin C.M. Type synthesis of 3 d.of. translational parallel manipulators based on screw theory. ASME J. of Mechanical Design, 126(1):83–92, January 2004.

- [kong2004-3] Kong X. and Gosselin C.M. Type synthesis of 3T1R 4-dof parallel manipulators based on screw theory. *IEEE Trans. on Robotics and Automation*, 20(2):181–190, April 2004.
- [kong2005] Kong X. and Gosselin C.M. Type synthesis of 4-dof SP-equivalent parallel manipulators: a virtual-chain approach. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [kong2005-1] Kong X. and Gosselin C.M. Type synthesis of 5-dof parallel manipulators based on screw theory. *J. of Robotic Systems*, 22(10):535–547, 2005.
- [kong2006] Kong X. and Gosselin C.M. Type synthesis of three-dof UP-equivalent parallel manipulators. In ARK, pages 123–132, Ljubljana, June, 26-29, 2006.
- [kong 2006-1] Kong X. and Gosselin C.M. Type synthesis of 4-dof SP-equivalent parallel manipulators: a virtual-chain approach. *Mechanism and Machine Theory*, 41(11):1306–1319, November 2006.
- [kong2007] Kong X. and Gosselin C.M. *Type synthesis of parallel mechanisms*. Springer Tracts in Advanced Robotics, Heidelberg, 2007. **Keywords:** structural synthesis.
- [kong 2007-1] Kong X., Gosselin C.M., and Richard P.L. Type synthesis of parallel mechanisms with multiple operation modes. ASME J. of Mechanical Design, 129(7):595–601, June 2007.
- [kong2007-2] Kong X. and Gosselin C.M. Type synthesis of 3-dof linear translational parallel manipulators. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [kong2008] Kong X. Forward kinematics and singularity analysis of a  $3-\underline{R}PP$  planar parallel manipulator. In ARK, pages 29–38, Batz/mer, June, 23-26, 2008.
- [kong2008-1] Kong X. and Gosselin C.M. Type synthesis of 6-dof wrist-partitioned parallel manipulators. ASME J. of Mechanical Design, 130(6):062302–1/062302–8, June 2008.
- [kong2009] Kong X. Forward displacement analysis of a  $3 \underline{R}PR$  planar parallel manipulator revisited. In *Computational Kinematics*, pages 69–76, Duisburg, May, 6-8, 2009.
- [kong2013] Kong X. Type synthesis of 3-dof parallel manipulators with both a planar operation mode and a spatial translational operation mode. *J. of Mechanisms and Robotics*, 5(4), November 2013.
- [kong2014] Kong X. and Li D. Condition for sub-6th order screw systems composed of three planar pencil of lines. In ARK, Ljulbjana, June 29- July 3, 2014.
- [kong2015] Kong X. Kinematic analysis of a 6R single-loop overconstrained spatial mechanism for circular translation. Mechanism and Machine Theory, 96:323–333, February 2016.
- [kong2016] Kong X. and Jin Y. Type synthesis of 3-DOF multi-mode translational/spherical parallel mechanisms with lockable joints. *Mechanism and Machine Theory*, 96:323–333, February 2016.
- [kong2016-1] Kong X. Reconfiguration analysis of a 4-DOF 3-RER parallel manipulator with equilateral triangular base and moving platform. *Mechanism and Machine Theory*, 98:180–189, April 2016.
- [konishi2006] Konishi S. and others . Pneumatic micro hand and miniaturized parallel link robot for micro manipulation robot system. In *IEEE Int. Conf. on Robotics and Automation*, pages 1036–1041, Orlando, May, 16-18, 2006.
- [konya2012] Konya B. and others . The kinematics of a new reconfigurable parallel robot with six degrees of freedom. In 4th European Conf. on Mechanism Science (Eucomes), pages 43–51, Santander, September, 19-21, 2012.
- [kool-2000] Kool P. Serial/parallel robots with reciprocal leg structures. In Workshop European Advanced Robotic Systems Development, Salford, April, 12-14, 2000.
- [kool-2000-1] Kool P. Analysis of robot singularities with exterior algebra. In Workshop European Advanced Robotic Systems Development, Salford, April, 12-14, 2000.
- [korayem2007] Korayem M.H., Bamdad M., and Saadat M. Workspace analysis of cable-suspended robots with elastic cable. In *IEEE International Conference on Robotics and Biomimetics*, 2007. ROBIO 2007, pages 1942–1947, 2007.

- [korayem2009] Korayem M.H. and Bamdad M. Dynamic load-carrying capacity of cable-suspended parallel manipulators. Int. J. of Advanced Manufacturing Technology, 44(7-8):829–840, October 2009.
- [korayem2010] Korayem M.H., Tourajizadeh H., and Bamdad M. Dynamic load carrying capacity of flexible cable suspended robot: robust feedback linearization control approach. *J. of Intelligent and Robotic Systems*, 60(3-4):341–363, September 2010.
- [korayem2010-1] Korayem M.H. and Bamdad M. Stiffness modeling and stability analysis of cable-suspended manipulators with elastic cable for maximum load determination. *Kuwait J. Sci. Eng.*, 37(1b):181–201, 2010.
- [korayem2011] Korayem M.H. and Tourajizadeh H. Maximum DLCC of spatial cable robot for a predefined trajectory within the workspace using closed loop optimal control approach. *J. of Intelligent and Robotic Systems*, 63:75–99, 2011.
- [korayem2012] Korayem M.H. and others . Analytical design of optimal trajectory with dynamic load-carrying capacity for cable-suspended manipulator. *The International Journal of Advanced Manufacturing Technology*, 60:317–327, 2012.
- [korayem2013] Korayem M.H. and others . Experimental results for the flexible joint cable-suspended manimulator ICaSbot. *Robotica*, 31(6):887–904, September 2013.
- [korayem2013-1] Korayem M.H. and others . Design and manufacturing the torque gauge of ICaSbot and implementing its data transfer protocol. Int J Advanced Design and Manufacturing Technology, 6(2), June 2013.
- [korayem2014] Korayem M.H. and others. A novel method for recording the position and orientation of the end effector of a spatial cable-suspended robot and using for closed-loop control. The International Journal of Advanced Manufacturing Technology, 72:739–755, 2014.
- [korayem2014-1] Korayem M.H. and others . Optimal motion planning of non-linear dynamic systems in the presence of obstacles and moving boundaries using SDRE: application on cable-suspended robot. *International Journal of Advanced Robotic Systems*, 2014.
- [korayem2015] Korayem M.H. and others . Optimal regulation of a cable robot in presence of obstacle using optimal adaptive feedback linearization approach. Robotica, 33(4):933-952, May 2015.
- [korayem2015-1] Korayem M.H., Taherifar M., and Tourajizadeh H. Compensating the flexibility uncertainties of a cable suspended robot using smc approach. *Robotica*, 33(3):578–598, 2015.
- [korayem2018] Korayem M.H., Yousefzadeh M., and Kian S. Precise end-effector pose estimation in spatial cable-driven parallel robots with elastic cables using data fusion methods. *Measurement*, 130:177–190, 2018.
- [korayem2020] Korayem M.H., Yousefzadeh M., and ourajizadeh H. Optimal control of a wheeled mobile cable-driven parallel robot ICaSbot with viscoelastic cables. *Robotica*, 38:1513–1537, 2020.
- [korkmaz 2014] Korkmaz O. and Ider S.K. Hybrid force and motion control of flexible joint parallel manipulators using inverse dynamics approach. *Advanced Robotics*, 28:1221–1230, 2014.
- [koseki2000] Koseki Y. and others . Kinematic analysis of translational 3-dof micro-parallel mechanism using matrix method. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Takamatsu, Japan, October 30-November 5, 2000.
- [kosinska2002] Kosinska A., Galicki M., and Kedzior K. Determination of parameters of 3-dof spatial orientation manipulators for a specific workspace. *Robotica*, 20(2):179–183, March 2002.
- [kosinska2003] Kosinska A., Galicki M., and Kedzior K. Designing and optimization of parameters of Delta-4 parallel manipulator for a given workspace. J. of Robotic Systems, 20(9):539–548, 2003.
- [kosinska2003-1] Kosinska A., Galicki M., and Kedzior K. Design of parameters of parallel manipulators for a specified workspace. *Robotica*, 21(5):575–579, December 2003.
- [kossowski2002] Kossowski C. and L. Notash. CAT4 (cable actuated truss—4 degrees of freedom): A novel 4 dof cable actuated parallel manipulator. *J. of Robotic Systems*, 19(2):605–615, December 2002.

- [kosuge93] Kosuge K. and others . Input/output force analysis of parallel link manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 714–719, Atlanta, May, 2-6, 1993.
- [kosuge93-1] Kosuge K. and others . Computation of parallel link manipulator dynamics. In *Int. Conf. on Indus. Electronics, Control and Instrumentation (IECON)*, pages 1672–1677, Hawai, November, 15-19, 1993.
- [kosuge96] Kosuge K. and others . Force control of parallel link manipulator with hydraulic actuators. In *IEEE Int. Conf. on Robotics and Automation*, pages 305–310, Minneapolis, April, 24-26, 1996.
- [kotlarski2008] Kotlarski J., Abellatif H., and Heimann B. Improving the pose accuracy of a planar 3<u>R</u>RR parallel manipulator using kinematic redundancy and optimized switching patterns. In *IEEE Int. Conf. on Robotics and Automation*, pages 3863–3868, Pasadena, May, 19-23, 2008.
- [kotlarski2009] Kotlarski J. and others. New interval-based approach to determine the guaranteed singularity-free workspace of parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 1256–1261, Kobe, May, 14-16, 2009.
- [kotlarski2010] Kotlarski J. and others . Optimization strategies for additional actuators of kinematically redundant parallel kinematic machines. In *IEEE Int. Conf. on Robotics and Automation*, pages 656–661, Anchorage, May, 3-8, 2010.
- [kotlarski2011] Kotlarski J., Heimann B., and Ormaier T. Experimental validation of the influence of kinematic redundancy on the pose accuracy of parallel kinematic machines. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [kovecses 2003] Kovecses J., Piedbœ ub J-C., and Lange C. Dynamic modeling and simulation of constrained robotic systems. *IEEE/ASME Trans. on Mechatronics*, 8(2):165–177, June 2003.
- [kozak2001] Kozak K., Ebert-Uphoff I., and Singhose W. Analysis of varying natural frequencies and damping ratio of a sample parallel manipulator throughout its workspace using linearized equation of motion. In *ASME Design Engineering Technical Conference*, Pittsburgh, September, 9-12, 2001.
- [kozak2004] Kozak K. and others . Locally linearized dynamic analysis of parallel manipulators and application of input shaping to reduce vibrations. ASME J. of Mechanical Design, 126(1):156–168, January 2004.
- [kozak2006] Kozak K. and others . Static analysis of cable-driven manipulators with non-negligible cable mass. *IEEE Trans. on Robotics*, 22(3):425–433, June 2006.
- [kozuka2012] Kozuka H. and others . A bio-inspired compliant parallel mechanism for high precision robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 3122–3127, Saint Paul, May, 14-18, 2012.
- [kraus2011] Kraus W. and others . System identification and cable force control for a cable-driven parallel robot with industrial servo drives. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [kraus2012] Kraus W. and Pott A. Scenario-based dimensionning of the actuator of parallel cable-driven robots. In 4th European Conf. on Mechanism Science (Eucomes), pages 131–139, Santander, September, 19-21, 2012.
- [kraus2012-1] Kraus W., Miermeister P., and Pott A. Investigation of the influence of elastic cables on the force distribution of a parallel cable-driven robot. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [kraus2013] Kraus W. and others . Load identification and compensation for a cable-driven parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 2470–2475, Karlsruhe, May, 6-10, 2013.
- [kraus 2014] Kraus W. and others . System identification and cable force control for a cable-driven parallel robot with industrial servo drives. In *IEEE Int. Conf. on Robotics and Automation*, pages 5921–5926, Hong-Kong, May 31- June 7, 2014.
- [kraus2014-1] Kraus W., Miermeister P., and Pott A. Hybrid position/force control of a cable-driven parallel robot with experimental evaluation. In 5th European Conf. on Mechanism Science (Eucomes), pages 553–561, Guimares, September, 16-19, 2014.

- [kraus2015] Kraus W., Kessler M., and Pott A. Pulley friction compensation for winch-integrated cable force measurement and verification on a cable-driven parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 1627–1632, Seattle, May, 26-30, 2015.
- [kraus2015-1] Kraus W. Force control of cable-driven parallel robots. Ph.D. Thesis, Université Stuttgart, Stuttgart, 2015. **Keywords:** control.
- [kraus2016] Kraus W., Spiller A., and Pott A. Energy efficiency of cable-driven parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, Stockholm, May, 16-20, 2016.
- [krefft2006] Krefft M., Last P., and Hesselbach J. New concepts to adapt the PKM performance to application requirements. In 5th Chemnitzer Parallelkinematik Seminar, pages 547–564, Chemnitz, April, 25-26, 2006.
- [krefft2006-1] Krefft M. and Hesselbach J. The dynamic optimization of PKM. In ARK, pages 339–348, Ljubljana, June, 26-29, 2006.
- [kreidler2000] Kreidler V. Development and software methods for parallel kinematic machine accuracy. In 2nd Chemnitzer Parallelkinematik Seminar, pages 241–256, Chemnitz, April, 12-13, 2000.
- [krishnamurthy2008] Krishnamurthy P. and Khorrami F. TriM: an ultra-accurate high-speed six degree-of-freedom manipulator using planar stepper motors. J. of Intelligent and Robotic Systems, 51(2):137–157, February 2008.
- [krishnaprasad94] Krishnaprasad P.S. and Tsakiris D.P. Nonholonomic variable geometry truss assemblies. I: motion control. In 4th IFAC Symp. on Robot Control, Syroco, Capri, September, 19-21, 1994.
- [krut-2003-phd] Krut S. Contribution à l'étude des robots parallèles légers, 3T-1R et 3T-2R, à forts débattements angulaires. Ph.D. Thesis, Université Montpellier II, Montpellier, November, 13, 2003. **Keywords:** 4 dof robot, 5 dof robot.
- [krut2002] Krut S. and others . Twice: a tilting angle amplification system for parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 4108–4113, Washington, May, 11-15, 2002.
- [krut2003] Krut S. and others . I4: a new parallel mechanism for Scara motions. In *IEEE Int. Conf. on Robotics and Automation*, pages 1875–1880, Taipei, September, 14-19, 2003.
- [krut2003-1] Krut S. and others . Eureka: A new 5-degree-of-freedom redundant parallel mechanism with high tilting capabilities. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October 2003.
- [krut2004] Krut S. and others . A high-speed parallel robot for Scara motion. In *IEEE Int. Conf. on Robotics and Automation*, pages 4109–4115, New Orleans, April, 28-30, 2004.
- [krut2004-1] Krut S., Company O., and Pierrot F. Velocity performance indices for parallel mechanisms with actuation redundancy. *Robotica*, 22(2):129–139, March 2004.
- [krut2004-2] Krut S., Company O., and Pierrot F. Force performance indexes for parallel mechanisms with actuation redundancy, especially for parallel wire-driven manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3936–3941, Sendai, September 28- October 2, 2004.
- [krut2006] Krut S., Pierrot F., and Company O. On PKM with articulated traveling plate and large tilting angles. In ARK, pages 445–454, Ljubljana, June, 26-29, 2006.
- [krut2008] Krut S. and others . A parallel cable-driven crane for Scara-motions. In ASME Design Engineering Technical Conference, New-York, August, 3-6, 2008.
- [ku99] Ku D.M. Direct displacement analysis of a Stewart platform mechanism. *Mechanism and Machine Theory*, 34(3):453–465, April 1999.
- [kubler2005] Kübler L., Henninger C., and Eberhard P. Multi-criteria optimization of a hexapod machine. *Multibody System Dynamics*, 14:225–250, 2005.
- [kucuk2013] Kucuk S. Energy minimization for 3-RRR fully planar parallel manipulator using particle swarm optimization. *Mechanism and Machine Theory*, 62:129–149, April 2013.

- [kucuk2017] Kucuk S. Optimal trajectory generation algorithm for serial and parallel manipulators. *Robotics and Computer-Integrated Manufacturing*, 48:219–232, December 2017.
- [kuhfuss2002] Kuhfuss B. and Schenck C. Optimized hybrid machine structures, a new development approach. In 3rd Chemnitzer Parallelkinematik Seminar, pages 213–225, Chemnitz, April, 23-25, 2002.
- [kuhfuss2006] Kuhfuss B., Schenck C., and Allers S. Static calibration of a Tripod by neural network error identification. In 5th Chemnitzer Parallelkinematik Seminar, pages 603–616, Chemnitz, April, 25-26, 2006.
- [kuhlbusch99] Kuhlbusch W. and others . TriPlanar-A new process-machine-type developed by means of the mechatronic design. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 514–519, Atlanta, September, 19-23, 1999.
- [kukula2009] Kukula P. and Valasek M. Kinematical solution by structure approximation. In *Computational Kinematics*, Duisburg, May, 6-8, 2009.
- [kumar-p-2015] Kumar P R., Chalanga A., and Bandyopadhyay B. Smooth integral sliding mode controller for the position control of Stewart platform. *ISA Transactions*, 58:543–551, September 2015.
- [kumar-s2018] Kumar S. and others . Kinematic analysis of a novel parallel 2SPRR+1U ankle mechanism in humanoid robot. In ARK, Bologna, July, 1-5, 2018.
- [kumar-s2019] Kumar S. and others. Design and kinematic analysis of the novel almost spherical parallel mechanism active ankle. J. of Intelligent and Robotic Systems, 95:303–325, 2019.
- [kumar-s2019-1] Kumar S. and others . Model simplification for dynamic control of series-parallel hybrid robots a representative study on the effects of neglected dynamics. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Macau, November, 4-8, 2019.
- [kumar-sg-2009] Kumar S.G., Nagarajan T., and Srinivasa Y.G. Characterization of reconfigurable Stewart platform for contour generation. *Robotics and Computer-Integrated Manufacturing*, 25(4-5):721-731, August 2009.
- [kumar90] Kumar V. Characterization of workspaces of parallel manipulators. In ASME Proc. of the 21th Biennial Mechanisms Conf., pages 321–329, Chicago, September, 16-19, 1990.
- [kumar92] Kumar V. Characterization of workspaces of parallel manipulators. ASME J. of Mechanical Design, 114(3):368–375, September 1992.
- [kumar92-1] Kumar V. Instantaneous kinematics of parallel-chain robotic mechanisms. ASME J. of Mechanical Design, 114(3):349–358, September 1992.
- [kurniawan2016] Kurniawan R. and others . Combined use of modified Hough transformation, random sample consensus and linear least square to extract the normal parameterization of a straight line: an application for cable driven parallel robots. In 3rd Int. Conf. on System-integrated Intelligence, pages 382–388, 2016.
- [kurtz90] Kurtz R.L. Kinematic and optimization of a parallel robotic wrist mechanism with redundancy. Research Report TR-CIM-90-2, Université McGill, Montréal, January 1990.
- [kurtz91] Kurtz R.L. and Hayward V. Dexterity measure for tendon actuated parallel mechanisms. In *ICAR*, pages 1141–1146, Pise, June, 19-22, 1991.
- [kurtz92] Kurtz R.L. and Hayward V. Multiple-goal kinematic optimization of a parallel spherical mechanism with actuator redundancy. *IEEE Trans. on Robotics and Automation*, 8(5):644–651, October 1992.
- [kwon-o-2004] Kwon O. and others . Serially-linked parallel leg design for biped robots. In 2nd Int. Conf. on Autonomous Robots and Agents, Palmerston North, December, 13-15, 2004.
- [kwon98] Kwon D-S. and others . Microsurgical telerobot system. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 945–950, Victoria, October 1998.
- [kyatkin99] Kyatkin A.B. and Chirikjian G.S. Synthesis of binary manipulators using the Fourier transform on the Euclidean group. ASME J. of Mechanical Design, 121(1):9–14, March 1999.

- [lacaze97] Lacaze A., Tasoluk C., and Meystel A. Solving the forward kinematics problem for the Stewart platform by focusing attention and searching. In *Int. Conf. on Intelligent Systems and Semiotics*, pages 477–483, Gaithersburg, September, 22-25, 1997.
- [lacombe 2022] Lacombe J. and Gosselin C. Singularity analysis of a kinematically redundant (6+2)-dof parallel mechanism for general configurations. *Mechanism and Machine Theory*, 176, 2022.
- [lafmejani2018] Lafmejani A.S., Masouleh M.T., and Kalhor A. Trajectory tracking control of a pneumatically actuated 6-dof Gough–Stewart parallel robot using backstepping-sliding mode controller and geometry-based quasi forward kinematic method. *Robotics and Computer-Integrated Manufacturing*, 54:96–114, 2018.
- [lafourcade-2004-phd] Lafourcade P. Contribution à l'étude de manipulateurs parallèles à câbles. Ph.D. Thesis, École Nationale Supérieure de l'Aéronautique et de l'Espace, Toulouse, December, 9, 2004. **Keywords:** wire robot, workspace, applications.
- [lafourcade 2002] Lafourcade P., Llibre M., and Reboulet C. Design of a parallel wire-driven manipulator for wind tunnels. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, Québec, October, 3-4, 2002.
- [lafourcade 2003] Lafourcade P. and Verhoeven R. Une nouvelle architecture, fortement redondante, pour une manipulateur à câbles au volume de travail étendu. In 16eme Congrès Français de Mécanique, Nice, September, 1-5, 2003.
- [lahouar 2007] Lahouar S. and others . Collision free path-planning for cable driven parallel robots. In 2nd Int. Congress, Design and Modelling of mechanical systems, Monastir, March, 19-21, 2007.
- [lahouar 2008] Lahouar S. and others . Singularity free path planning for parallel robots. In ARK, Batz/mer, June, 23-26, 2008.
- [lahouar 2009] Lahouar S. and others. Collision free path-planning for cable driven parallel robots. *Robotics and Autonomous Systems*, 57(11):1083–1093, November 2009.
- [lai2011] Lai L. and others . Design of a decoupled 2-dof translational parallel micro-positioning stage. In *IEEE Int. Conf. on Robotics and Automation*, pages 5070–5075, Shangai, May, 9-13, 2011.
- [lai208] Lai Y-L., Liao C-C., and Ghao Z-G. Inverse kinematics for a novel hybrid parallel–serial five-axis machine tool. *Robotics and Computer-Integrated Manufacturing*, 50:63–79, 2018.
- [laliberte99] Laliberté T., Gosselin C.M., and Côté G. Rapid prototyping of mechanisms. In 10th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 959–964, Oulu, June, 20-24, 1999.
- [laliberte2024] Laliberté T., Abdallah M., and Gosselin C.M. A backdrivable 6-dof parallel robot for sensorless dynamically interactive tasks. *Robotics and Computer-Integrated Manufacturing*, 86, April 2024.
- [lallemand97] Lallemand J-P., Goudali A., and Zeghloul S. The 6-dof 2-Delta parallel robot. *Robotica*, 15(4):407–416, July August , 1997.
- [lalo2012] Lalo W., Vruckmann T., and Schramm D. Optimal control for a wire-based storage retrieval machine. In 4th European Conf. on Mechanism Science (Eucomes), pages 631–639, Santander, September, 19-21, 2012.
- [lamaury2012] Lamaury J. and others . Design and control of a redundant suspended cable-driven parallel robot. In ARK, pages 237–244, Innsbruck, June, 25-28, 2012.
- [lamaury2012-1] Lamaury J. and Gouttefarde M. A tension distribtion method with improved computational efficiency. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [lamaury2013] Lamaury J. and others . Dual-space adaptive control of redundantly actuated cable-driven parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 4879–4886, Tokyo, November, 3-7, 2013.
- [lamaury 2013-1] Lamaury J. and Gouttefarde M. Control of a large redundantly actuated cable-suspended parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, Karlsruhe, May, 6-10, 2013.

- [lamaury 2013-phd] Lamaury J. Contribution à la commande des robots parallèles à câbles à redondance d'actionnement. Ph.D. Thesis, Université de Montpellier, Montpellier, October, 8, 2013. Keywords: wire robot, redundant robot, control.
- [lambert-c2006] Lambert C. and Nahon M. Study of a multitethered aerostat system: experimental observations and model validation. *Journal of Aircraft*, 43(4), 2006.
- [lambert-p2012] Lambert P. and Herder J.L. Mobility analysis of non series-parallel mechanisms. In 4th European Conf. on Mechanism Science (Eucomes), pages 63–71, Santander, September, 19-21, 2012.
- [lambert-p2016] Lambert P. and Herder J.L. Parallel robots with configurable platforms: Fundamental aspects of a new class of robotic architectures. *Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science*, 230(3):463–472, February 2016.
- [lambert-p2019] Lambert P. and Herder J.L. A 7-dof redundantly actuated parallel haptic device combining 6-dof manipulation and 1-dof grasping. *Mechanism and Machine Theory*, 134:349–364, 2019.
- [lambert-p2020] Lambert P., Da Cruz L., and Bergels C. Design, modelling, and implementation of a 7-dof cable-driven haptic device with a configurable cable platform. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October, 25-29, 2020.
- [lambert87] Lambert M. Polyarticulated retractile mechanism, March, 24, 1987. United States Patent n° 4,651,589, Société Becart S.A. **Keywords:** mechanical architecture,3 dof robot, patent.
- [lamine2014] Lamine H., Bennour S., Merlet J-P., and Romdhane L. Workspace evaluation for a cable based gait trainer robot. In *Troisième Congrès Tunisien de Mécanique*, Sousse, March, 24-26, 2014.
- [lamine2016] Lamine H., Bennour S., and Romdhane L. Design of cable-driven parallel manipulators for a specific workspace using interval analysis. *Advanced Robotics*, 30:585–594, 2016.
- [lamine2019] Lamine H., Romdhane L., and Bennour S. Parametric dynamic analysis of walking within a cable-based gait trainer. *Robotica*, 37:1225–1239, 2019.
- [lamine2020] Lamine H. and others . Design-to-workspace synthesis of a cable robot used in legs training machine. *Robotica*, 38:1703–1714, 2020.
- [lampariello 2006] Lampariello R. and others . Reactionless control for two manipulators mounted on a cable-suspended platform. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Beijing, October, 9-15, 2006.
- [lande81] Lande M.A. and David R.J.P. Articulation for manipulator arm, November, 17, 1981. United States Patent n° 4,300,362, Association des Ouvriers en Instruments de Précision, Paris. **Keywords:** mechanical architecture,3 dof robot,patent.
- [landsberger85] Landsberger S.E. and Sheridan T.B. A new design for parallel link manipulator. In *Proc. Systems*, *Man and Cybernetics Conf.*, pages 812–814, Tucson, 1985.
- [landsberger92] Landsberger S.E. and Shanmugasundram A.P. Workspace of parallel link crane. In *IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems*, pages 479–486, Kobe, September, 16-20, 1992.
- [landsberger 92-1] Landsberger S.E. and Sheridan T.B. A minimal, minimal linkage: the tension-compression parallel link manipulator. In *IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems*, pages 493–500, Kobe, September, 16-20, 1992.
- [lang2001] Lang J., Mick S., and Röschel O. The rigidity rate of positions of Stewart-Gough platforms. *Journal for Geometry and Graphics*, 5(2):121–132, 2001.
- [laribi2007] Laribi M.A., Romdhane L., and Zeghloul S. Analysis and dimensional synthesis of the DELTA robot for a prescribed workspace. *Mechanism and Machine Theory*, 42(7):859–870, July 2007.
- [laribi2007-1] Laribi M.A., Romdhane L., and Zeghloul S. Synthesis of RAF parallel robot for prescribed workspace. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.

- [laribi2008] Laribi M.A., Romdhane L., and Zeghloul S. Parallel manipulators, Towards new applications, chapter Advanced synthesis of the DELTA parallel robot for a specified workspace, pages 207–224. ITECH, April 2008. **Keywords:** 3 dof robot,workspace,design,optimal design.
- [laribi2017] Laribi M.A., Mlika A., Romdhane L., and Zeghloul S. Robust optimization of the RAF parallel robot for a prescribed workspace. In *Computational Kinematics*, Poitiers, 2017.
- [laroche2012] Laroche E.and others. A preliminary study for  $H_{\infty}$  control of parallel cable-driven manipulators. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [larochelle95] Larochelle P.M. Design of 3-dof spherical robotic mechanisms. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1826–1830, Milan, August 30- September 2, 1995.
- [larsonneur92] Larsonneur R., Arai T., and Jaya Y.M. A six-degree-of-freedom micro-manipulator using a piezoelectrically driven parallel-link mechanism. In 10th Robotics Society Japan Annual Conf., pages 863–864, Kanazawa, November 1992.
- [laryushkin2012] Laryushkin P. and Glazunov V. A new 3-dof translational parallel manipulator: Kinematics, dynamics and workspace analysis. In *RoManSy*, Paris, June, 12-15, 2012.
- [laryushkin2019] Laryushkin P., Glazunov V., and Erastova K. On the maximization of joint velocities and generalized reactions in the workspace and singularity analysis of parallel mechanisms. *Robotica*, 37:675–690, 2019.
- [lasker2013] Lasker L. and Or Y. Path planning of planar parallel manipulator with joint clearance. In 4th Israeli Conf. onRobotics, Tel-Aviv, November, 19-20, 2013.
- [laski2015] Laski P.A., Takosoglu J.E., and Blasiak S. Design of a 3-dof tripod electro-pneumatic parallel manipulator. Robotics and Autonomous Systems, 72:59–70, October 2015.
- [last2006] Last P. and Hesselbach J. A new calibration strategy for a class of parallel mechanism. In ARK, pages 331–338, Ljubljana, June, 26-29, 2006.
- [last2007] Last P. and others . A general approach to solve the singular kinematic problem. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3943–3949, San Diego, September, 22-26, 2007.
- [last2007-1] Last P. and others . Singularity based calibration of 3-dof fully parallel planar manipulators. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [lau2011] Lau D., Oetomo D., and Halgamuge S.K. Wrench-closure workspace generation for cable driven parallel manipulators using a hybrid analytical-numerical approach. ASME J. of Mechanical Design, 133(7):071004–1/9, July 2011.
- [lau2012] Lau D. and others . On the task specific evaluation and optimisation of cable-driven manipulators. In *Advances in reconfigurable mechanisms and robots I*, pages 707–716. Springer, 2012. **Keywords:** wire robot, optimal design.
- [lau2013] Lau D., Oetomo D., and Halgamuge K. Generalized modeling of multilink cable-driven manipulators with arbitrary routing using the cable-routing matrix. *IEEE Trans. on Robotics*, 29(5):1102–1113, October 2013.
- [lau2014] Lau D. and others. Cable function analysis for the musculoskeletal static workspace of a human shoulder. In 2nd Int. Conf. on cable-driven parallel robots (Cable Con), Duisburg, August, 24-27, 2014.
- [lau2015] Lau D. and others . Musculoskeletal static workspace analysis of the human shoulder as a cable-driven robot. *IEEE/ASME Trans. on Mechatronics*, 210(2), April 2015.
- [lau2016] Lau D., Eden J., Tan Y., and Oetomo D. CASPR: A comprehensive cable-robot analysis and simulation platform for the research of cable-driven parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3004–3011, Daejeon, October, 9-14, 2016.
- [lau2017] Lau D. Initial length and pose calibration for cable-driven parallel robots with relative lengths feedback. In 3rd Int. Conf. on cable-driven parallel robots (Cable Con), Québec, 2017.
- [lauffer96] Lauffer J.P. and others . Milling machine for the 21st century, goals, approach, characterization and modeling. *Proc. of the SPIE*, 2721:326–340, 1996.

- [lauzier2009] Lauzier N., Grenier M., and Gosselin C. 2 dof cartesian force limiting device for safe physical human-robot interaction. In *IEEE Int. Conf. on Robotics and Automation*, pages 253–258, Kobe, May, 14-16, 2009.
- [lauzier2010] Lauzier N. and Gosselin C. 3-DOF cartesian force limiting device based on the Delta architecture for safe physical human-robot interaction. In *IEEE Int. Conf. on Robotics and Automation*, pages 3420–3425, Anchorage, May, 3-8, 2010.
- [lazard91] Lazard D. Stewart platform, October, 17, 1991. Communication personelle. **Keywords:** forward kinematics.
- [lazard92] Lazard D. Stewart platform and Gröbner basis. In ARK, pages 136–142, Ferrare, September, 7-9, 1992.
- [lazard93] Lazard D. Generalized Stewart Platform: How to compute with rigid motions? In *IMACS Symp. on Symbolic Computation*, pages 85–88, Lille, June, 14-17, 1993.
- [lazard93-1] Lazard D. On the representation of rigid-body motions and its application to generalized platform manipulators. In J. Angeles P. Kovacs, G. Hommel, editor, *Computational Kinematics*, pages 175–182. Kluwer, 1993. **Keywords:** forward kinematics.
- [lazard94] Lazard D. and Merlet J-P. The (true) Stewart platform has 12 configurations. In *IEEE Int. Conf. on Robotics and Automation*, pages 2160–2165, San Diego, May, 8-13, 1994.
- [le2017] Le M.N., Inuzuka H., and Sakai M. Graphical simulator for teaching robot with parallel wire type teaching device. In 3rd International Conference on Control, Automation and Robotics, 2017.
- [lealnaranjo2019] Leal-Naranjo J-A. and others. Comparison of metaheuristic optimization algorithms for dimensional synthesis of a spherical parallel manipulator. *Mechanism and Machine Theory*, 140:586–600, 2019.
- [lebesgue67] Lebesgue H. Octaèdre articulé de Bricard. L'enseignement mathématique, (13):150–160, 1967.
- [leblond98] Leblond M. and Gosselin C.M. Static balancing of spatial and planar parallel manipulators with prismatic actuators. In ASME Design Engineering Technical Conferences, Atlanta, September, 13-16, 1998.
- [lebret93] Lebret G., Liu K., and Lewis F. Dynamic analysis and control of a Stewart platform manipulator. *J. of Robotic Systems*, 10(5):629–655, July 1993.
- [lee-cc-2006] Lee C-C. and Hervè J.M. Translational parallel manipulators with doubly planar limbs. *Mechanism and Machine Theory*, 41(4):433–455, April 2006.
- [lee-cc-2007] Lee C-C. and Hervè J.M. Cartesian parallel manipulators with pseudoplanar limbs. ASME J. of Mechanical Design, 129(12):1256–1264, December 2007.
- [lee-cc-2009] Lee C-C. and Hervè J.M. On some applications of primitive Schönflies-motion generators. *Mechanism and Machine Theory*, 44(12):2153–2163, December 2009.
- [lee-cc-2009-1] Lee C-C. and Hervè J.M. Uncoupled actuation of overconstrained 3T-1R hybrid parallel manipulators. *Robotica*, 27(1):103–117, January 2009.
- [lee-cc-2009-2] Lee C-C. and Hervè J.M. Type synthesis of primitive Schönflies-motion generators. *Mechanism and Machine Theory*, 44(10):1980–1997, October 2009.
- [lee-cc-2009-3] Lee C-C. and Hervè J.M. Uncoupled 6-dof tripods via group theory. In *Computational Kinematics*, Duisburg, May, 6-8, 2009.
- [lee-cc-2010] Lee C-C. and Hervè J.M. Mechanical generators of 2-dof translation along a ruled surface. In ARK, pages 73–80, Piran, June 28- July 1, 2010.
- [lee-cc-2011] Lee C-C. and Hervè J.M. Isoconstrained parallel generators of Schoenflies motion. *J. of Mechanisms and Robotics*, 3(2), March 2011.
- [lee-cc-2012] Lee C-C. and Hervè J.M. Parallel mechanis, generating 3-dof finite translation and (2 or 1)-dof infinitesimal rotation. *Mechanism and Machine Theory*, 51:185–194, 2012.
- [lee-ds-96] Lee D.S. and Chirikjian G.S. A combinatorial approach to trajectory planning for binary manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2749–2754, Minneapolis, April, 24-26, 1996.

- [lee-ds-96-1] Lee D.S. and Chirikjian G.S. An efficient method for computing the forward kinematics of binary manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1012–1017, Minneapolis, April, 24-26, 1996.
- [lee-e-99] Lee E. and Mavroidis C. Rigid body displacement analysis using the method of loci and its application on the direct kinematics of hybrid serial-parallel mechanisms. In 10th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 513–522, Oulu, June, 20-24, 1999.
- [lee-hy-93] Lee H-Y. and Roth B. A closed-form solution of the forward displacement analysis of a class of in-parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 720–724, Atlanta, May, 2-6, 1993.
- [lee-j-96] Lee J. and Duffy J. An investigation of a quality index for the stability of in-parallel platform devices. In 11th RoManSy, pages 27–35, Udine, July, 1-4, 1996.
- [lee-j-99] Lee J., Duffy J., and Keler M. The optimum quality index for the stability of in-parallel planar platform devices. ASME J. of Mechanical Design, 121(1):15–20, March 1999.
- [lee-j98] Lee J., Duffy J., and Hunt K.H. A practical quality index based on the octahedral manipulator. *Int. J. of Robotics Research*, 17(10), 1998.
- [lee-jd-93] Lee J.D. and Geng Z. A dynamic model of a flexible Stewart platform. Computers & Structures, 48(3):367–374, August, 3, 1993.
- [lee-jd-93-1] Lee J.D. and Geng Z. Modeling and control of a flexible Stewart platform. In *IFAC 12th Triennial World Congress*, pages 441–444, Sydney, July, 18-23, 1993.
- [lee-jh-2004] Lee J-H. and Hong K-S. Kinematic optimal design of a Paramill: a multi-SP device. *J. of Robotic Systems*, 21(6):345–359, 2004.
- [lee-mk-95] Lee M.K. Design of a high stiffness machining robot arm using double parallel mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 234–240, Nagoya, May, 25-27, 1995.
- [lee-mk-98] Lee M.K. and Park K.W. Direct kinematics of a double parallel robot arm for real time velocity control. KSME Int. Journal, 12(4):525–535, 1998.
- [lee-mk-99] Lee M.K. and Park K.W. Kinematics and dynamics analysis of a double parallel manipulator for enlarging workspace and avoiding singularities. *IEEE Trans. on Robotics and Automation*, 15(6):1024–1034, December 1999.
- [lee-mk-2000] Lee M.K. and Park K.W. Workspace and singularity analysis of a double parallel manipulator. *IEEE/ASME Trans. on Mechatronics*, 5(4):367–375, December 2000.
- [lee-pc2016] Lee P-C. and Lee J-J. On the kinematics of a new parallel mechanism with Schonflies motion. *Robotica*, 34(9):2056–2070, September 2016.
- [lee-s-93] Lee S. and Kim S. Kinematic analysis of generalized parallel manipulator systems. In 32nd Conf. on Decision and Control, pages 1097–1102, San Antonio, December, 15-17, 1993.
- [lee-s-94] Lee S. and Kim S. Kinematic feature analysis of parallel manipulator systems. In *IEEE Int. Conf. on Robotics and Automation*, pages 77–82, San Diego, May, 8-13, 1994.
- [lee-s-2011] Lee S. and others . Experimental verification of antagonistic stiffness planning for a planar parallel mechanism with 2-dof force redundancy. *Robotica*, 29(4):547–554, July 2011.
- [lee-sh2001] Lee S-H. and others . Analysis on impact propagation of docking platform for spacecrafts. In *IEEE Int. Conf. on Robotics and Automation*, pages 413–420, Seoul, May, 23-25, 2001.
- [lee-sh2001-1] Lee S.H., Yi B-J., and Kim S.H. Modeling and analysis on the internal impact of a Stewart platform used for spacecraft docking. *Advanced Robotics*, 15(7):763–777, 2001.
- [lee-sh2002] Lee S-H. and others . Workspace and force-moment transmission of a variable arm type parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3666–3671, Washington, May, 11-15, 2002.

- [lee-sh2006] Lee S-H. and others. Analysis of two 3-dof parallel mechanisms with constrained stewart platform structure. In *IEEE Int. Conf. on Robotics and Automation*, pages 4227–4233, Orlando, May, 16-18, 2006.
- [lee-tc-2007] Lee T-C. and Perng M.H. Analysis of simplified position and 5-dof total orientation workspaces of a hexapod mechanism. *Mechanism and Machine Theory*, 42(12):1577–1600, December 2007.
- [lee-ty2001] Lee T-Y and Shim J-K. Elimination-based solution method for the forward kinematics of the general Stewart-Gough platform. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 259–267. EJCK, May, 20-22, 2001. **Keywords:** forward kinematics.
- [lee-ty2001-1] Lee T-Y and Shim J-K. Forward kinematics of the general 6-6 Stewart platform using algebraic elimination. *Mechanism and Machine Theory*, 36(9):1073–1085, September 2001.
- [lee-ty2001-2] Lee T-Y and Shim J-K. Algebraic elimination-based real-time forward kinematics of the 6-6 Stewart platform with planar base and platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 1301–1306, Seoul, May, 23-25, 2001.
- [lee-ty2003] Lee T-Y and Shim J-K. Improved dyalitic elimination algorithm for the forward kinematics of the general Stewart-Gough platform. *Mechanism and Machine Theory*, 38(6):563–577, June 2003.
- [lee-ws98] Lee W-S., Kim J-H., and J-H Cho. A driving simulator as a virtual reality tool. In *IEEE Int. Conf. on Robotics and Automation*, pages 71–76, Louvain, May, 18-20, 1998.
- [lee88] Lee K-M. and Shah D.K. Kinematic analysis of a three-degrees-of-freedom in-parallel actuated manipulator. *Int. J. of Robotics and Automation*, 4(3):354–360, June 1988.
- [lee88-1] Lee K-M. and Shah D.K. Dynamic analysis of a three-degrees-of-freedom in-parallel actuated manipulator. *Int. J. of Robotics and Automation*, 4(3):361–368, June 1988.
- [lee91] Lee K-M. and Arjunan S. A three-degrees-of freedom micromotion in-parallel actuated manipulator. *IEEE Trans. on Robotics and Automation*, 7(5):634–641, October 1991.
- [lee-d2012] Lee D., Kim J., and Seo T. Optimal design of 6-dof Eclipse mechanism based on task-oriented workspace. *Robotica*, 30(7):1041–1048, December 2012.
- [lee-dg2016] Lee D.G., Oh S., and Son H.I. Maintenance robot for 5-MW offshore wind turbines and its control. *IEEE/ASME Trans. on Mechatronics*, 21(5), October 2016.
- [legnani2010] Legnani G. and others . The point of isotropy and other properties of serial and parallel manipulators.  $Mechanism\ and\ Machine\ Theory,\ 45(10):11407-1423,\ October\ 2010.$
- [legnani2012] Legnani G. and others . A new isotropic and decoupled 6-dof parallel manipulators. *Mechanism and Machine Theory*, 58:64–81, December 2012.
- [legnani2014] Legnani G. and M. Tiboni. Optimal design and application of a low-cost wire-sensor system for the kinematic calibration of industrial manipulators. *Mechanism and Machine Theory*, 73:25–48, March 2014.
- [leguay96] Leguay-Durand S. and Reboulet C. New design of a redundant spherical manipulator. In 6th ISRAM, pages 365–370, Montpellier, May, 28-30, 1996.
- [leguay97] Leguay-Durand S. and Reboulet C. Optimal design of a redundant spherical parallel manipulator. Robotica, 15(4):399-405, July August , 1997.
- [leguay98-phd] Leguay S. Conception et optimisation de mécanismes parallèles à mobilités restreintes. Ph.D. Thesis, ENSAE, Toulouse, June, 23, 1998. **Keywords:** design,optimal design,mechanical architecture,3 dof robot,wrist,mobility.
- [lei-y2022] Lei Y., Suhahara Y., and Takeda Y. Design and inverse kinematics of a novel tendon-driven continuum manipulator capable of twisting motion. In *ARK*, Bilbao, June, 26-30, 2022.
- [lei2013] Lei M.C. and Oetomo D. Modelling of cable wrapping phenomenon towards improved cable-driven mechanisms. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, Wollogong, July, 9-12, 2012.

- [lei2020] Lei M.C. Dynamics of cable driven parallel manipulator allowing cable wrapping over rigid link. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, Boston (virtual), July, 6-9, 2020.
- [lemay2004] Lemay J. and Notash L. Configuration engine for architecture planning of modular parallel robot. *Mechanism and Machine Theory*, 39(1):101–117, January 2004.
- [lenarcic2000] Lenarčič J., Stanišić M.M., and Parenti-Castelli V. A 4-dof parallel mechanism simulating the movement of the human sternum-clavicle-scapula complex. In ARK, pages 325–332, Piran, June, 25-29, 2000.
- [lenarcic2000-1] Lenarčič J., Stanišić M.M., and Parenti-Castelli V. Kinematic design of a humanoid robotic shoulder complex. In *IEEE Int. Conf. on Robotics and Automation*, pages 4123–4128, San Francisco, April, 24-28, 2000.
- [lenarcic2002] Lenarčič J., Stanišić M.M., and Schearer E. Humanoid humeral pointing kinematics. In *ARK*, pages 79–88, Caldes de Malavalla, June 29- July 2, 2002.
- [lenarcic2003] Lenarčič J. and Stanišić M.M. A humanoid shoulder complex and the humeral pointing kinematics. *IEEE Trans. on Robotics and Automation*, 19(3):499–506, June 2003.
- [lenders2011] Lenders C., Gauthier M., and Lambert P. Parallel microrobot actuated by capillary effects. In *IEEE Int. Conf. on Robotics and Automation*, pages 470–475, Shangai, May, 9-13, 2011.
- [lenders2012] Lenders C. and others . Three-dof microrobot platform based on capillary actuation. *IEEE Trans. on Robotics*, 28(5):1153–1161, October 2012.
- [leonardis2017] Leonardis D. and others . A 3-RSR haptic wearable device for rendering fingertip contact forces. *IEEE Trans. on Haptics*, 10(3):305–316, 2017.
- [lerbet87] Lerbet J. Mécanique des systèmes de solides rigides comportant des boucles fermées. Ph.D. Thesis, Paris VI, Paris, June, 19, 1987. **Keywords:** mobility.
- [leroy2003] Leroy N. and others . Dynamic modeling of a parallel robot. Application to a surgical simulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 4330–4335, Taipei, September, 14-19, 2003.
- [lescano2015] Lescano S., Rakotondrabe M., and Andreff N. Precision prediction using interval exponential mapping of a parallel kinematic smart; composite microstructure. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, September 28- October 2, 2015.
- [lesellier2018] Lesellier M. and others . An active stabilizer for cable-driven parallel robot vibration damping. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Vilamoura, October, 7-12, 2012.
- [lessanibahri2017] Lessanibahri S. and others . Twist feasibility analysis of cable-driven parallel robots. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [lessanibahri2018] Lessanibahri S., Cardou P., and Caro S. Parasitic inclinations in cable-driven parallel robot using cable loops. In 28th CIRP Design Conf., Nantes, 2018.
- [lessanibahri2019] Lessanibahri S., Cardou P., and Caro S. A cable-driven parallel robot with an embedded tilt-roll wrist. In ASME Design Engineering Technical Conference, Anaheim, August, 18-21, 2019.
- [lessard2007] Lessard S. and others . Optimum static balancing of the parallel robot for medical 3D-ultrasound imaging. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [lessard2007-1] Lessard S., Bigras P., and Bonev I.A. A new medical parallel robot and its static balancing optimization. ASME Journal of Medical Devices, 1, December 2017.
- [levey2007] Le Vey G. Dynamics and control of actuated parallel structures as a constrained optimization problem through Gauss's principle 'and Appell's equations. In *IEEE Int. Conf. on Robotics and Automation*, pages 1480–1485, Roma, April, 10-14, 2007.
- [lewkowicz2019] Lewkowicz R. and Kowaleczko G. Kinematic issues of a spatial disorientation simulator. *Mechanism and Machine Theory*, 138, 2019.

- [li-b2011] Li B. and others . Conceptual design and analysis of the 2T1R mechanism for a cooking robot. *Robotics and Autonomous Systems*, 59(1):74–83, January 2011.
- [li-b2013] Li B., Zhang Q., and Huang Z. Position singularity analysis of a spherical class of the Stewart parallel mechanism with two dissimilar semi-symmetrical haxagons. *Robotica*, 31(1):123–136, January 2013.
- [li-b2015] Li B. and others . Design and analysis of parallel robots for a flexible fixturing system with performance atlases. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, September 28-October 2, 2015.
- [li-b2016] Li B., Li Y., and Zhao X. Kinematics analysis of a novel over-constrained three degree-of-freedom spatial parallel manipulator. *Mechanism and Machine Theory*, 104:222–233, 2016.
- [li-c-2013] Li C. and others . Cartesian stiffness evaluation of a novel 2 dof parallel wrist under redundant and antagonistic actuation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 959–964, Tokyo, November, 3-7, 2013.
- [li-c-2019] Li C. and others . A robotic system with multichannel flexible parallel manipulators for single port access surgery. *IEEE Trans. on Industrial Informatics*, 15(3):1678–1687, 2019.
- [li-chun94] Li-Chun T., Jun Kuo W., and Jun Kuo M. Dynamic load-carrying capacity and inverse dynamics of multiple cooperating robotic manipulators. *IEEE Trans. on Robotics and Automation*, 10(1):71–74, February 1994.
- [li-h-2006] Li H. and others . Analytic form of the six-dimensional singularity locus of the general Gough-Stewart platform. ASME J. of Mechanical Design, 128(1):279–287, January 2006.
- [li-h-2006-1] Li H., Gosselin C.M., and Richard M.J. Determination of maximal singularity-free zones in the workspace of planar three-degree-of-freedom parallel mechanisms. *Mechanism and Machine Theory*, 41(10):1157–1167, October 2006.
- [li-h-2006-2] Li H., Gosselin C.M., Richard M.J., and Mayer St-Onge B. Analytic form of the six-dimensional singularity locus of the general Gough-Stewart platform. ASME J. of Mechanical Design, 128(1):279–287, 2006.
- [li-h-2015] Li H. and others . Design and control of 3-dof spherical parallel mechanism robot eyes inspired by the binocular vestibule-ocular reflex. J. of Intelligent and Robotic Systems, 78(3-4):425–441, June 2015.
- [li-h-2015-1] Li H. and Hao G. A constraint and position identification (CPI) approach for the synthesis of decoupled spatial translational compliant parallel manipulator. *Mechanism and Machine Theory*, 90:59–83, 2015.
- [li-h-2016] Li H. and Pan Z. The five-hundred-meter aperture spherical radio telescope project. AGU Radio Science, pages 1060–1064, 2016.
- [li-h-2017] Li H. and others . Preliminary running and performance test of the huge cable robot of FAST telescope. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [li-h2011] Li H., Zhang Y., and Dai J.S. Design optimization of parallel manipulators with required pose resolution. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [li-h2012] Li H. and others . Optimal force distribution based on a slack rope model in the incompletely constrained cable-driven parallel mechanism of FAST telescope. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [li-h2014] Li H. On the static stiffness of incompletely restrained cable-driven robot. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 17–28, Duisburg, August, 24-27, 2014.
- [li-j-2001] Li J. and others. Inverse kinematics and dynamics of the 3-RRS parallel platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 2506–2511, Seoul, May, 23-25, 2001.
- [li-j-2018] Li J. and others . Position solution and kinematic interference analysis of a novel parallel hip-assistive mechanism. *Mechanism and Machine Theory*, 120:265–287, 2018.
- [li-j-2020] Li J. and others . Velocity and force transfer performance analysis of a parallel hip assistive mechanism. Robotica, 38:747-759, 2020.

- [li-j-2020-1] Li J. and others . Dimensional synthesis of a 5-dof hybrid robot. *Mechanism and Machine Theory*, 150, 2020.
- [li-j-2022] Li J. and others . Conceptual design and error analysis of a cable-driven parallel robot. *Robotica*, 40(7):2152–2167, July 2022.
- [li-l2020] Li L. and others . Type synthesis of a class of novel 3-dof single-loop parallel leg mechanisms for walking robots. *Mechanism and Machine Theory*, 145, 2020.
- [li-l2020-1] Li L., Fang Y., and Wang L. Design of a family of multi-dof drive systems for fewer limb parallel mechanisms. *Mechanism and Machine Theory*, 148, 2020.
- [li-l2021] Li L. and others . Type synthesis of single-loop 3T1R-parallel mechanisms with a multi-dof drive system. Mechanism and Machine Theory, 163, 2021.
- [li-m-2006] Li M. and others . Forward position analysis of the 3-dof module of the TriVariant: a 5-dof reconfigurable hybrid robot. ASME J. of Mechanical Design, 128(1):319–322, January 2006.
- [li-p2018] Li P. and others . Relative posture-based kinematic calibration of a 6-RSS parallel robot by optical coordinate measurement machine. *International Journal of Advanced Robotic Systems*, 2018.
- [li-q-2003] Li Q. and Huang Z. Type synthesis of 4-dof parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 755–760, Taipei, September, 14-19, 2003.
- [li-q-2003-1] Li Q. and Huang Z. Mobility analysis of a 3-5R parallel mechanism family. In *IEEE Int. Conf. on Robotics and Automation*, pages 1887–1892, Taipei, September, 14-19, 2003.
- [li-q-2003-2] Li Q. and Huang Z. Mobility analysis of lower-mobility parallel manipulators based on screw theory. In *IEEE Int. Conf. on Robotics and Automation*, pages 1179–1184, Taipei, September, 14-19, 2003.
- [li-q-2003-3] Li Q. and Huang Z. Type synthesis of 5-dof parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1203–1208, Taipei, September, 14-19, 2003.
- [li-q-2004] Li Q. and Wu F.X. Control performance improvement of a parallel robot via the design for control approach. *Mechatronics*, 14(8):947–964, October 2004.
- [li-q-2006] Li Q. Experimental validation on the integrated design and control of a parallel robot. *Robotica*, 24(2):173–181, March 2006.
- [li-q-2009] Li Q. and Hervè J.M. Parallel mechanisms with bifurcation of Schoenflies motion. *IEEE Trans. on Robotics*, 25(1):158–164, February 2009.
- [li-q-2009-1] Li Q. and Hervè J.M. Structural shakiness of non overconstrained translational parallel mechanisms with identical limbs. *IEEE Trans. on Robotics*, 25(1):25–36, February 2009.
- [li-q-2010] Li Q. and Hervè J.M. 1T2R parallel mechanisms without parasitic motion. *IEEE Trans. on Robotics*, 26(3):401–410, June 2010.
- [li-q-2011] Li Q. and others . Parasitic motion of 3-PRS parallel mechanism with different limb arrangements. *Robotics and Computer-Integrated Manufacturing*, 27(2):389–396, April 2011.
- [li-q-2014] Li Q. and Hervè J.M. Type synthesis of 3-dof RPR-equivalent parallel mechanisms. *IEEE Trans. on Robotics*, 30(6):1333–1343, December 2014.
- [li-qc-2003] Li Q-C. and Huang Z. A family of symmetrical lower mobility parallel mechanisms with spherical and parallel subchains. *J. of Robotic Systems*, 20(6):297–305, 2003.
- [li-qc-2004] Li Q-C., Huang Z., and Hervé J-M. Type synthesis of 3R2T 5-dof parallel mechanisms using Lie group of displacements. *IEEE Trans. on Robotics and Automation*, 20(2):173–180, April 2004.
- [li-qc-2004-1] Li Q-C. and Huang Z. Mobility analysis of a novel 3-5R parallel mechanism family. ASME J. of Mechanical Design, 126(1):79–82, January 2004.
- [li-s-2002] Li S., Huang Z., and Zuo Q. Kinematics of a special 3-dof 3-UPU parallel manipulator. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.

- [li-s2007] Li S. and Gosselin C. Stiffness analysis of 3-RRR planar parallel mechanisms based on CCT. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [li-s2009] Li S. and others. Design of a new fMRI compatible haptic interface. In Third Joint Eurohaptics Conference and Symposium on Haptic Interfaces for Virtual Environment and Teleoperator Systems, Slat Lake City, March, 18-20, 2009.
- [li-s2019] Li S. and Zanotto D. Tracking control of fully-constrained cable-driven parallel robots using adaptive dynamic programming. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Macau, 2019.
- [li-t-2002] Li T. and Payandeh S. Design of spherical parallel mechanisms for application to laparoscopic surgery. *Robotica*, 20(2):133–138, March 2002.
- [li-t-2012] Li T. and Ceccarelli M. A characterization of human locomotion by CATRASYS (cassino tracking system). In 4th European Conf. on Mechanism Science (Eucomes), pages 469–485, Santander, September, 19-21, 2012.
- [li-t2005] Li T., Li Q., and Payendeh S. Nn-based solution of forward kinematics of 3dof parallel spherical manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Edmonton, August, 2-6, 2005.
- [li-w-2005] Li W., Gao F., and Zhang J. R-cube, a decoupled parallel manipulator only with revolute joints. *Mechanism and Machine Theory*, 40(4):467–473, April 2005.
- [li-w-2005-1] Li W., Gao F., and Zhang J. A three-dof translational manipulator with decoupled geometry. *Robotica*, 23(6):805–808, November 2005.
- [li-w-2007] Li W., Liu X., and Liu K. Tracking control of a planar parallel robot via adaptive backstepping. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [li-w-2008] Li W. Parallel manipulators, New Developments, chapter Type design of decoupled manipulators with lowe mobility, pages 483–498. ITECH, April 2008. **Keywords:** 3 dof robot, structural synthesis, decoupled robot.
- [li-w-2018] Li W. and Angeles J. A novel three-loop parallel robot with full mobility: Kinematics, singularity, workspace, and dexterity analysis. J. of Mechanisms and Robotics, 9(5), 2018.
- [li-w2018-1] Li W. and Angeles J. The design for isotropy of a class of six-dof parallel-kinematics machines. *Mechanism and Machine Theory*, 126, 2018.
- [li-w2018-2] Li W. and others . Design of 6-dof parallel ankle rehabilitation robot. In *Int. Conf. on Cyborg and Bionic Systems*, Shenzhen, October, 25-27, 2018.
- [li-w2018-3] Li W. and Angeles J. Full-mobility  $3-\underline{C}CC$  parallel-kinematics machines: forward kinematics, singularity, workspace and dexterity analyses. *Mechanism and Machine Theory*, 126:312–328, August 2018.
- [li-y-2003] Li Y., Huang Z., and Chen L. Singular loci analysis of 3/6-Stewart manipulator by singularity-equivalent mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 1881–1886, Taipei, September, 14-19, 2003.
- [li-y-2004] Li Y. and Xu Q. Optimal kinematic design for a general 3-PRS spatial parallel manipulator based on dexterity and workspace. In 11th International Conference on Machine Design and Production, Antalya, October, 13-15, 2004.
- [li-y-2005] Li Y. and Xu Q. Kinematics and inverse dynamics for a general 3-PRS spatial parallel mechanism. *Robotica*, 23(2):219–229, March 2005.
- [li-y-2005-1] Li Y. and Xu Q. Kinematics and dexterity analysis for a novel 3-dof translational parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 2955–2960, Barcelona, April, 19-22, 2005.
- [li-y-2005-2] Li Y. and Xu Q. Dynamic analysis of a modified DELTA parallel robot for cardiopulmonary resuscitation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Edmonton, August, 2-6, 2005.
- [li-y-2006] Li Y. and others . Novel design and modeling of a mobile parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 1135–1140, Orlando, May, 16-18, 2006.

- [li-y-2006-1] Li Y. and Xu Q. Kinematic analysis and design of a new 3-dof translational parallel manipulator. ASME J. of Mechanical Design, 128(4):729–737, July 2006.
- [li-y-2006-2] Li Y. and Xu Q. GA-based multi-objective optimal design of a planar 3-dof cable-driven parallel manipulator. In *IEEE Int. Conf. on Robotics and Biomimetics*, pages 1360–1365, Kunming, December, 17-20, 2006.
- [li-y-2006-3] Li Y. and Xu Q. A new approach to the architecture optimization of a general 3-PUU translational parallel manipulator. *J. of Intelligent and Robotic Systems*, 46:59–72, 2006.
- [li-y-2007] Li Y. and Xu Q. Kinematic analysis of a 3-PRS parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 23(4):395–408, August 2007.
- [li-y-2007-1] Li Y. and Xu Q. Design and development of a medical parallel robot for cardiopulmonary resuscitation. *IEEE/ASME Trans. on Mechatronics*, 12(3):265–273, June 2007.
- [li-y-2008] Li Y. and Xu Q. Optimum design and development of an XY flexure micromanipulator for micro scale positioning. In *IEEE Int. Conf. on Robotics and Automation*, pages 3112–3117, Pasadena, May, 19-23, 2008.
- [li-y-2008-1] Li Y. and Xu Q. Design of a new decoupled XY flexure parallel kinematic manipulator with actuator isolation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 470–475, Nice, France, September, 22-26, 2008.
- [li-y-2008-2] Li Y. and Xu Q. Stiffness analysis for a 3-PUU parallel kinematic machine. *Mechanism and Machine Theory*, 43(2):186–200, February 2008.
- [li-y-2008-3] Li Y. and Xu Q. Parallel manipulators, New Developments, chapter Design, analysis and applications of a class of new 3-dof translational parllel manipulator, pages 457–482. ITECH, April 2008. **Keywords:** 3 dof robot.
- [li-y-2009] Li Y. and Xu Q. Dynamic modeling and robust control of a 3-PRC translational parallel kinematic machine. Robotics and Computer-Integrated Manufacturing, 25(3):630–640, June 2009.
- [li-y-2010] Li Y. and others . Dynamique performance comparison and counterweight optimization of two 3-dof parallel manipulators for a new hybrid machine-tool. *Mechanism and Machine Theory*, 45(11):1668–1680, November 2010.
- [li-y-2016] Li Y. and others. Design, analysis and simulation of a novel 3-dof translational micromanipulator based on the PRB model. *Mechanism and Machine Theory*, pages 235–258, 2016.
- [li-y-b-2001] Li Y. and Bone G.M. Are parallel manipulators more energy efficient? In *IEEE Int. Symp. on Computational Intelligence in Robotics and Automation*, Banff, August 29- September 1, 2001.
- [li-y2018] Li Y., Huang T., and Chetwynd D.K. An approach for smooth trajectory planning of high-speed pick-and-place parallel robots using quintic B-splines. *Mechanism and Machine Theory*, 126:479–490, 2018.
- [li-y2019] Li Y., Yao Y-A., and He Y. Design and analysis of a multi-mode mobile robot based on a parallel mechanism with branch variation. *Mechanism and Machine Theory*, 130:276–300, 2019.
- [li-y2020] Li Y. and others . Optimization of dynamic load distribution of a serial-parallel hybrid humanoid arm. *Mechanism and Machine Theory*, 149, 2020.
- [li-yg-2010] Li Y.G. and others . Design of a 3-dof PKM module for large structural component machining. *Mechanism and Machine Theory*, 45(6):941–954, June 2010.
- [li-yh2014] Li Y.H. and others . Integrated design of a 4-DOF high-speed pick-and-place parallel robot. Annals of the CIRP, 63(1):185–188, 2014.
- [li-yw-2002] Li Y-W., Wang J-S., and Wang L-P. Stiffness analysis of a Stewart platform-based parallel kinematic machine. In *IEEE Int. Conf. on Robotics and Automation*, pages 3672–3677, Washington, May, 11-15, 2002.
- [li-yw-2003] Li Y-W. and others . Inverse dynamics and simulation of a 3-dof spatial parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 4092–4097, Taipei, September, 14-19, 2003.

- [li97] Li D. and Salcudean T. Modeling, simulation and control of hydraulic Stewart platform. In *IEEE Int. Conf.* on Robotics and Automation, pages 3360–3366, Albuquerque, April, 21-28, 1997.
- [lian-b-2016] Lian B. and others . Passive and active gravity compensation of horizontally- mounted 3-RPS parallel kinematic machine. *Mechanism and Machine Theory*, 104:190–201, 2016.
- [lian-b-2017] Lian B., Sun T., and Song Y. Parameter sensitivity analysis of a 5-dof parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 46:1–14, 2017.
- [lian-b-2019] Lian B., Wang L., and Wang X.V. Elastodynamic modeling and parameter sensitivity analysis of a parallel manipulator with articulated traveling plate. The International Journal of Advanced Manufacturing Technology, 102:1583-1599, 2016.
- [lian-d2017] Lian D. and others . Rigid-flexible coupling dynamic modeling and investigation of a redundantly actuated parallel manipulator with multiple actuation modes. *Journal of Sound and Vibration*, 403:129–151, 2017.
- [liang-x2018] Liang X. and Takeda Y. Iterative method for the inverse kinematics of a 2-limb parallel mechanism with 3-dof using a 6-limb mechanism with 6-dof. In *ARK*, pages 108–115, Bologna, July, 1-5, 2018.
- [liang-x2019] Liang X. and Takeda Y. Transmission index of a class of parallel manipulators with 3-RS(SR) primary structures based on pressure angle and equivalent mechanism with 2-SS chains replacing RS chain. *Mechanism and Machine Theory*, 139:359–378, 2019.
- [liang2011] Liang Q. and others. Six dof micro manipulator based on compliant parallel mechanism with integrated force sensor. *Robotics and Computer-Integrated Manufacturing*, 27(1):124–134, February 2011.
- [liao-h-2007] Liao H. and others . Surgical manipulator with linkage mechanism for anterior cruciate ligament reconstruction. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1266–1271, San Diego, September, 22-26, 2007.
- [liao-s2020] Liao S. and others . Parameter identification and nonparametric calibration of the Tri-Pyramid robot. *IEEE/ASME Trans. on Mechatronics*, 25(5), October 2020.
- [liao-z2018] Liao Z. and others . Screw theory based mathematical modeling and kinematic analysis of a novel ankle rehabilitation robot with a constrained 3-PSP mechanism topology. *The International Journal of Advanced Manufacturing Technology*, pages 351–360, 2018.
- [liao2001] Liao Q. and McCarthy J. M. On the seven position synthesis of a 5-SS platform linkage. ASME J. of Mechanical Design, 123(1):74–79, March 2001.
- [liao93] Liao Q., SAeneviratne L.D., and Earles S.W.E. Forward kinematic analysis for the general 4-6 Stewart platform. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Yokohoma, July, 26-30, 1993.
- [liem2007] Liem K., Kecskeméthy A., and Merlet J-P. Hexaspine: A parallel platform for physical cervical spine simulation design and interval-based verification. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [lim2009] Lim W.B. and others. A generic tension-closure analysis method for fully-constrained cable-driven parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2187–2192, Kobe, May, 14-16, 2009.
- [lim2011] Lim W.B. and others. A generic force closure algorithm for cable-driven parallel manipulators. *Mechanism and Machine Theory*, 46(9):1265–1275, September 2011.
- [lin-cl2008] Lin C-L. and others . Singularity characterization and path planning of a new 3 links 6-dofs parallel manipulator. *European Journal of Control*, 3:201–212, 2008.
- [lin-h2003] Lin H. and McInroy J.E. Adaptive sinusoidal disturbance cancellation for precise pointing of Stewart platforms. *IEEE Trans. on Control Systems Technology*, 11(2):267–272, March 2003.
- [lin-j2009] Lin J. and Chen C-W. Computer-aided-symbolic dynamic modeling for Stewart-platform manipulator. *Robotica*, 27(3):331–341, May 2009.
- [lin-j2018] Lin J., Wu C.Y., and Chang J. Design and implementation of a multi-degrees-of-freedom cable-driven parallel robot with gripper. *International Journal of Advanced Robotic Systems*, 2020.

- [lin-lc-2000] Lin L-C. and Tsay M-U. Modeling and control of micropositioning systems using Stewart platforms. *J. of Robotic Systems*, 17(1):17–52, 2000.
- [lin90] Lin W., Duffy J., and Griffis M. Forward displacement analysis of the 4-4 Stewart platform. In ASME Proc. of the the 21th Biennial Mechanisms Conf., pages 263–269, Chicago, September, 16-19, 1990.
- [lin92] Lin W., Crane III C.D., and Duffy J. Closed-form forward displacement analysis of the 4-5 in-parallel platforms. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 521–527, Scottsdale, September, 13-16, 1992.
- [lin92-1] Lin W., Duffy J., and Griffis M. Forward displacement analysis of the 4-4 Stewart platform. ASME J. of Mechanical Design, 114(3):444–450, September 1992.
- [lin94] Lin W., Crane III C.D., and Duffy J. Closed-form forward displacement analysis of the 4-5 in-parallel platforms. ASME J. of Mechanical Design, 116(1):47–53, March 1994.
- [linda2011] Linda O. and Manic M. Uncertainty-robust design of interval type-2 fuzzy logic controller for Delta parallel robot. *IEEE Trans. on Industrial Informatics*, 7(4), November 2011.
- [lindem95] Lindem T.J. and Charles P.A.S. Octahedral machine with a hexapodal triangular servostrut section, March, 28, 1995. United States Patent n° 5,401,128, Ingersoll Milling Machine Company. **Keywords:** applications,machine-tool,patent.
- [ling-m2018] Ling M. and others . Kinetostatic modeling of complex compliant mechanisms with serial-parallel substructures: A semi-analytical matrix displacement method. *Mechanism and Machine Theory*, 126:169–184, 2018.
- [ling94] Ling S-H. and Huang M.Z. Kinestatic analysis of general parallel manipulators. In ASME Mechanisms Design Conf., Minneapolis, September, 14-16, 1994.
- [ling98] Ling S.H. Motion/force simulator with six or three degrees of freedom, May, 19, 1998. United States Patent n° 5,752,834. **Keywords:** mechanical architecture,6 dof robot,3 dof robot,patent.
- [lins-vieira2018] Lins Vieira H. and da Silva M.M. Estimating the probability of failure of a 3<u>R</u>RR manipulator using a metamodel. In 7tht European Conf. on Mechanism Science (Eucomes), Aachen, September, 4-6, 2018.
- [lins-vieira2019] Lins Vieira H. and others . Reliable motion planning for parallel manipulators. *Mechanism and Machine Theory*, 140, 2019.
- [lintott96] Lintott A.B. and Dunlop G.R. Calibration of a parallel topology robot. In 6th ISRAM, pages 429–434, Montpellier, May, 28-30, 1996.
- [lintott97] Lintott A.B. and Dunlop G.R. Parallel topology robot calibration. *Robotica*, 15(4):395–398, July August , 1997.
- [lintott98] Lintott A.B. and Dunlop G.R. Geometric modelling of general parallel mechanisms for calibration purposes. In ARK, pages 175–184, Strobl, June 29- July 4, 1998.
- [liping2016] Liping W. and others . A novel 3-PUU parallel mechanism and its kinematic issues. *Robotics and Computer-Integrated Manufacturing*, 42:86–102, 2016.
- [liping2016-1] Liping W., Huayang X., and Liwen G. Kinematics and inverse dynamics analysis for a novel 3-PUU parallel mechanism. *Robotica*, 35:2018–2035, 2016.
- [liping 2017] Liping W., Huayang X., and Liwen G. Kinematic and inverse dynamic analysis for a novel 3-PUU parallel manipulator. *Robotica*, 35(10):2018–2035, October 2017.
- [lippi2018] Lippi M. and Marino A. Cooperative object transportation by multiple ground and aerial vehicles: modeling and planning. In *IEEE Int. Conf. on Robotics and Automation*, Brisbane, May, 21-25, 2018.
- [liu-ax-95] Liu A-X. and Yang T-L. Configuration analysis of a class of parallel structures using improved continuation. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 155–158, Milan, August 30- September 2, 1995.

- [liu-ch-2004] Liu C-H. and Cheng S. Direct singular position of 3RPS parallel manipulator. ASME J. of Mechanical Design, 126(6):1006–1016, November 2004.
- [liu-f2020] Liu F. and others. Design and analysis of a cable-driven rigid–flexible coupling parallel mechanism with variable stiffness. *Mechanism and Machine Theory*, 153, 2020.
- [liu-g-2003] Liu G., Lou Y., and Li Z. Singularities of parallel manipulators: a geometric treatment. *IEEE Trans. on Robotics and Automation*, 19(4):579–594, August 2003.
- [liu-g2006] Liu G., Trinkle J.C., and Shvalb N. Motion planning for a class of planar closed-chain manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 133–138, Orlando, May, 16-18, 2006.
- [liu-g2014] Liu G. and others . Singularity analysis and detection of 6-UCU parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 30, 2014.
- [liu-g2018] Liu G. and others. GA
  SQP optimization for the dimensional synthesis of a delta mechanism based haptic device design. Robotics and
  Computer-Integrated Manufacturing, 51:72-84, 2018.
- [liu-gf-2001] Liu G.F. and others . Analysis and control of redundant parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 3748–3754, Seoul, May, 23-25, 2001.
- [liu-gf-2002] Liu G.F., Wu X.Z., and Li Z.X. Inertial equivalence principle and adaptive control of redundant parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 835–840, Washington, May, 11-15, 2002.
- [liu-gf-2003] Liu G.F. and others . Kinematic synthesis of parallel manipulators; a Lie theoretic approach. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2096–2100, Las Vegas, October 2003.
- [liu-h-2007] Liu H. and others . Kinematic design of a 5-dof hybrid robot with large workspace/limb-stroke ratio. ASME J. of Mechanical Design, 129(5):530–537, May 2007.
- [liu-h-2011] Liu H., Huang T., and Chetwynd D.G. A method to formulate a dimensionnally homogeneous jacobian of parallel robots. *IEEE Trans. on Robotics*, 27(1):150–156, February 2011.
- [liu-h-2014] Liu H. and others . A generalized approach for computing the transmission index of parallel mechanisms. Mechanism and Machine Theory, 74:245–256, April 2014.
- [liu-h-2017] Liu H. and others . Force/motion transmissibility analyses of redundantly actuated and overconstrained parallel manipulators. *Mechanism and Machine Theory*, 109:126–138, 2017.
- [liu-h-2017-1] Liu H. and others . Stiffness modeling of parallel mechanisms at limb and joint/link levels.  $IEEE\ Trans.$  on  $Robotics,\ 33(3):734-741,\ 2017.$
- [liu-ht-2007] Liu H.T. and others . Optimal design of the TriVariant robot to achieve a nearly axial symmetry of kinematic performance. *Mechanism and Machine Theory*, 42(12):1643–1652, December 2007.
- [liu-j2021] Liu J. and others . Investigation of a novel 2R1T parallel mechanism and construction of its variants. *Robotica*, 39:1834–1848, 2021.
- [liu-j2024] Liu J. and others . Design and kinematical performance analysis of a novel reconfigurable parallel mechanism with three remote center-of-motion modes. *Mechanism and Machine Theory*, 191, 2024.
- [liu-k-2017] Liu K. and others . Robust control of 3-DOF parallel robot driven by PMAs based on nominal stiffness model.  $Advanced\ Robotics,\ 31(10):531-543,\ 2017.$
- [liu-k-2019] Liu K., Kong X., and Yu J. Operation mode analysis of lower-mobility parallel mechanisms based on dual quaternions. *Mechanism and Machine Theory*, 142, 2019.
- [liu-mj-2000] Liu M-J., Li C-X., and C-N. Li. Dynamics analysis of the Gough-Stewart platform manipulator. *IEEE Trans. on Robotics and Automation*, 16(1):94–98, February 2000.
- [liu-p-2016] Liu P. and Ma H. On the stability for a cable driven parallel robot while considering the cable sag effect. In 13th Int. Conf. on Ubiquitous robotics and ambiant intelligence (URAI), August, 19-22, 2016.

- [liu-q2014] Liu Q. and others . Fuzzy sliding mode control of a multi-dof parallel robot in rehabilitation environment. International Journal of Humanoid Robotics, 11(1), 2014.
- [liu-q2019] Liu Q. and others . An iterative tuning approach for feedforward control of parallel manipulators by considering joint couplings. *Mechanism and Machine Theory*, 140:159–169, 2019.
- [liu-q2019-1] Liu Q. and Huang T. Inverse kinematics of a 5-axis hybrid robot with non-singular tool path generation. Robotics and Computer-Integrated Manufacturing, 56:140–148, 2019.
- [liu-s-2017] Liu S., Qiu Z-C., and Zhang X-M. Singularity and path-planning with the working mode conversion of a 3-DOF 3-RRR planar parallel manipulator. *Mechanism and Machine Theory*, 107:166–182, 2017.
- [liu-sa-2002] Liu S.A. and Tzo H.L. A novel six components force sensor with good measurement isotropy and sensitivities. Sensors and Actuators A, 100:223–230, 2002.
- [liu-t2007] Liu T., Inoue Y., and Shibata K. Wearable force sensor with parallel structure for measurement of ground reaction force. *Measurement*, 40:644–653, 2007.
- [liu-t2017] Liu T. and others . Design of a thrust-vectoring tailcone based on 3-RRRR parallel manipulator for small-size autonomous underwater vehicles. In OCEANS 2017, Anchorage, 2017.
- [liu-x2021] Liu X. and others . Coordination dynamics and model-based neural network synchronous controls for redundantly full-actuated parallel manipulator. *Mechanism and Machine Theory*, 160, 2021.
- [liu-x2022] Liu X. and others . Performance evaluation of a special 6-PUS type parallel manipulator. Robotica, 40:505-519, 2022.
- [liu-xj2006-1] Liu X-J., Wang J., and Pritschow G. On the optimal kinematic design of the PRRRP 2-dof parallel mechanism. *Mechanism and Machine Theory*, 41(9):1111–1130, September 2006.
- [liu-xj2006-2] Liu X-J. Optimal kinematic design of a three translational dofs parallel manipulator. ASME J. of Mechanical Design, 128(1):239–250, January 2006.
- [liu-xj2006-3] Liu X-J., Wang J., and Zheng H.J. Optimum design of the 5R symmetrical parallel manipulator with surrounded and good-condition workspace. *Robotics and Autonomous Systems*, 54(3):221–233, March 2006.
- [liu-xj2006-4] Liu X-J., Wang J., and Kim J. Determination of the link lengths for a spatial 3-dof parallel manipulator. ASME~J.~of~Mechanical~Design,~128(2):365-373,~March~2006.
- [liu-xj2007] Liu X-J., Guan L., and Wang J. Kinematics and closed optimal design of a kind of PRRRP parallel manipulator. ASME J. of Mechanical Design, 129(5):558–563, May 2007.
- [liu-xj2009] Liu X-J. and others . A new family of spatial 3-dof parallel manipulators with two translational and one rotational dofs. *Robotica*, 27(2):241–247, March 2009.
- [liu-xj2015] Liu X-J., Li J., and Zhou Y. Kinematic optimal design of a 2-degreee-of-freedom 3-parallelogram planar parallel manipulator. *Mechanism and Machine Theory*, 91:168–196, 2015.
- [liu-xj2018] Liu X-J. and others. A novel acceleration capacity index based on motion/force transmissibility for high-speed parallel robots. *Mechanism and Machine Theory*, 126:156–170, 2018.
- [liu-xj2000] Liu X-J., Wang J-S., and Gao F. On the optimum design of planar 3-dof planar parallel manipulators with respect to the workspace. In *IEEE Int. Conf. on Robotics and Automation*, pages 4123–4128, San Francisco, April, 24-28, 2000.
- [liu-xj2000-1] Liu X-J., Wang J., and Gao F. Performance at lases of the workspace for planar 3-dof parallel manipulators. *Robotica*, 18(5):563–568, September 2000.
- [liu-xj2001] Liu X-J., Wang J., Gao F., and Wang L-P. On the analysis of a new spatial three-degree-of-freedom parallel manipulator. *IEEE Trans. on Robotics and Automation*, 17(6):959–968, December 2001.
- [liu-xj2001-1] Liu X-J., Wang J., Gao F., and Wang L-P. On the design of 6-dof parallel micro-motion manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Maui, Hawaii, October 29- November 3, 2001.

- [liu-xj2002] Liu X-J. and others. Mechanism design of a simplified 6-dof 6-RUS parallel manipulator. *Robotica*, 20(1):81–91, January 2002.
- [liu-xj2002-1] Liu X-J. and Kim J. A new three-degree-of-freedom parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 1155–1160, Washington, May, 11-15, 2002.
- [liu-xj2003] Liu X-J., Jeong J.I., and Kim J. A three translational dofs parallel cube-manipulator. *Robotica*, 21(6):645–652, December 2003.
- [liu-xj2003-1] Liu X-J. and Wang J. Some new parallel mechanisms containing the planar four-bar parallelogram. *Int. J. of Robotics Research*, 22(9):717–732, September 2003.
- [liu-xj2003-2] Liu X-J., Wang J., and Zheng H. Workspace at lases for the computer aided design of the Delta robot. Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science, 217(8):861–869, August 2003.
- [liu-xj2003-3] Liu X-J., Kim J., and Oh K-K. Singularity analysis of the HALF parallel manipulator with revolute actuators. In *IEEE Int. Conf. on Robotics and Automation*, pages 767–772, Taipei, September, 14-19, 2003.
- [liu-xj2004] Liu X-J. and others . A new approach to the design of a DELTA robot with a desired workspace. J. of Intelligent and Robotic Systems, 39(2):209–225, June 2004.
- [liu-xj2005] Liu X-J. and others . HANA: a novel spatial parallel manipulator with one rotational and two translational degree of freedom. *Robotica*, 23(2):257–270, March 2005.
- [liu-xj2005-1] Liu X-J., Wang J., and Pritschow G. A new family of spatial 3-dof fully parallel manipulators with high rotational capability. *Mechanism and Machine Theory*, 40(4):475–494, April 2005.
- [liu-xj2006] Liu X-J., Wang J., and Wang L-P. Optimal kinematic design of the 2-dof translational parallel mechanism in a 5-axis gantry machine-tool. In 5th Chemnitzer Parallelkinematik Seminar, pages 267–288, Chemnitz, April, 25-26, 2006.
- [liu-y-2006] Liu Y. and others . Time-optimal trajectory generation of a fast-motion planar parallel manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Beijing, October, 9-15, 2006.
- [liu-y-2012] Liu Y. and Staicu S. Inverse dynamics of a 3-PRC parallel kinematic machine. *Nonlinear Dynamics*, 67:1031–1041, 2012.
- [liu-y2016] Liu Y. and others . Determination of the maximal singularity-free zone of 4-RRR redundant parallel manipulator and its application on investigating length ratio of links. *Robotica*, 34(9):2039–2055, September 2016.
- [liu-y2020] Liu Y., Dai Z., and Lu Y. Precise stiffness and elastic deformations of serial–parallel manipulators by considering inertial wrench of moving links. *Robotica*, 38:2204–2220, 2020.
- [liu-y2020-1] Liu Y. and others . Type synthesis of multi-mode mobile parallel mechanisms based on refined virtual chain approach. *Mechanism and Machine Theory*, 152, 2020.
- [liu-z-2016] Liu Z. and others . Dimensional optimization of the Stewart platform based on inertial decoupling characteristics. *Robotica*, 34(5):1151–1167, May 2016.
- [liu91] Liu K., Fitzgerald M.K., and Lewis F. Some issues about modeling of the Stewart platform. In 2nd Int. Symp. on Implicit and Robust systems, Warsaw, 1991.
- [liu91-1] Liu K. and al . Modeling and control of a Stewart platform manipulator. In ASME Symp. on Control of Systems with inexact dynamic models, pages 83–89, Atlanta, 1991.
- [liu92] Liu K., Lebret G., Lowe J.A., and Lewis F.L. Control of a Stewart platform based robotic milling cell. In ASME Winter Annual Meeting, Symp. on Manufacturing and Control issues in a robotics assembly Workcell, Angheim, February, 8-13, 1992.
- [liu93] Liu K., Fitzgerald M.K., and Lewis F. Kinematic analysis of a Stewart platform manipulator. *IEEE Trans.* on Industrial Electronics, 40(2):282–293, April 1993.

- [liu93-1] Liu K. and others . Stewart-Platform-based inlet duct painting system. In *IEEE Int. Conf. on Robotics and Automation*, pages 106–113, Atlanta, May, 2-6, 1993.
- [liu93-2] Liu K., Lewis F., Lebret G., and Taylor D. The singularities and dynamics of a Stewart platform manipulator. J. of Intelligent and Robotic Systems, 8(3):287–308, 1993.
- [liu94] Liu K., Fitzgerald M.K., and Lewis F. Solution of nonlinear kinematics of a parallel-link constrained Stewart platform manipulator. *Circuits, Systems, and Signal Processing*, 13(2-3):167–183, 1994.
- [loloei2009] Loloei A.Z., Aref M.M., and Taghirad H.D. Wrench feasible workspace analysis of cable-driven parallel manipulators using LMI approach. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, Singapore, June, 4-17, 2009.
- [loloei2011] Loloei A.Z. and Taghirad H.D. Controlable workspace of general cable-driven redundant parallel manipulator based on fundamental wrench. In *CCToMM Symposium on Mechanisms, Machine and Mechatronics*, Montréal, June, 2-3, 2011.
- [loncaric91] Loncaric J. and De Comarmond F. Modular dextrous hand, October, 1, 1991. United States Patent n° 5,052,736 Univ. of Maryland. **Keywords:** applications, patent.
- [long2014] Long P., Khalil W., and Martinet P. Dynamic modeling of parallel robots with flexible platforms. *Mechanism and Machine Theory*, 81:21–35, 2014.
- [lopes2007] Lopes A.M. and Almeida F.G. Acceleration-based force-impedance control of a six-dof parallel manipulator. *Industrial Robot*, 35(4):386–393, 2007.
- [lopes 2008] Lopes A.M. and Almeda F. Parallel manipulators, Towards new applications, chapter Dynamic model of a 6-dof parallel manipulator using the generalized momentum, pages 69–86. ITECH, April 2008. **Keywords:** dynamics.
- [lopes2010] Lopes A.M. Complete dynamic of a moving base 6-dof parallel manipulator. *Robotica*, 28(5):781–793, September 2010.
- [lorenz2016] Lorenz M. and others . Power manipulability analysis of redundantly actuated parallel kinematic manipulators with different types of actuators. In *IEEE Int. Conf. on Robotics and Automation*, Stockholm, May, 16-20, 2016.
- [lorenzo2001] Lorenzo J. and others . Hydraulic excavator dynamic model for a real time training simulator. In *Driving* simulation Conf (DSC), pages 201–211, Sophia-Antipolis, September, 5-7, 2001.
- [losch95] Lösch S. Inverse force analysis of the general planar parallel manipulator. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1831–1835, Milan, August 30- September 2, 1995.
- [losch95-1] Lösch S. Parallel redundant manipulator based on open and closed normal Assur chains. In J-P. Merlet B. Ravani, editor, *Computational Kinematics*, pages 251–260. Kluwer, 1995. **Keywords:** redundant robot.
- [lou2003] Lou Y.J., Liu G.F., and Li Z.X. Optimal design of parallel manipulators via LMI approach. In *IEEE Int. Conf. on Robotics and Automation*, pages 1869–1874, Taipei, September, 14-19, 2003.
- [lou2003-1] Lou Y.J., Liu G.F., and Li Z.X. An LMI based optimal design of parallel manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2115–2120, Las Vegas, October 2003.
- [lou2004] Lou Y. and others . A general approach for optimal kinematic design of parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 3659–3664, New Orleans, April, 28-30, 2004.
- [lou2005] Lou Y. and others . Optimal design of a parallel machine based on multiple criteria. In *IEEE Int. Conf. on Robotics and Automation*, pages 3230–3235, Barcelona, April, 19-22, 2005.
- [lou2006] Lou Y. and others . Task space based contouring control of parallel machining systems. In *IEEE Int. Conf.* on *Intelligent Robots and Systems (IROS)*, Beijing, October, 9-15, 2006.
- [lou2007] Lou Y. and others . Development of a novel 3-dof purely translational parallel mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 169–174, Roma, April, 10-14, 2007.

- [lou2014] Lou Y. and others. Optimization algorithms for kinematically optimal design of parallel manipulators. *IEEE Trans. on Automation Science and Engineering*, 11(2):574–584, April 2014.
- [lu-b2018] Lu B., Fang Y., and Sun N. Nonlinear control for underactuated multi-rope cranes: Modeling, theoretical design and hardware experiments. *Control Eng. Practice*, 76:123–132, 2018.
- [lu-l2019] Lu L. and others . Development of a emg-based torque estimation control strategy for a soft elbow exoskeleton. *Advanced Robotics*, 111:88–98, 2019.
- [lu2004] Lu Y. Using CAD functionalities for the kinematic analysis of spatial parallel manipulators with 3-,4-,5-,6-linearly driven limbs. *Mechanism and Machine Theory*, 39(1):41–60, January 2004.
- [lu2005] Lu Y. and Leinonen T. Solution and simulation of position-orientation for multi-spatial 3-RPS parallel mechanisms in series connection. *Multibody System Dynamics*, 14:47–60, 2005.
- [lu2006] Lu Y. Using CAD variation geometry for solving velocity and acceleration of parallel manipulators with 3-,4-,5-linearly driven limbs. ASME J. of Mechanical Design, 128(4):738–746, July 2006.
- [lu2006-1] Lu Y. and Hu B. Solving driving forces of 2(3-SPR) serial-parallel manipulator by CAD variation geometry approach. ASME J. of Mechanical Design, 128(6):1349–1351, November 2006.
- [lu2006-2] Lu Y. Using CAD variation geometry and analytic approach for solving kinematics of a novel 3-SPU/3-SPU parallel manipulator. ASME J. of Mechanical Design, 128(3):574–580, May 2006.
- [lu2007] Lu Y. and Hu B. Unified solving jacobian/hessian manipulators with n SPS active legs and a passive constrained leg. ASME J. of Mechanical Design, 129(1):1161–1169, November 2007.
- [lu2007-1] Lu Y. and Hu B. A unified approach to solving driving forces in spatial parallel manipulators with less than 6 DOFs. ASME J. of Mechanical Design, 129(1):1153–1160, November 2007.
- [lu2007-2] Lu Y. and Hu B. Analysing kinematics and solving active/constrained forces of a 3SPU+UPR parallel manipulator. *Mechanism and Machine Theory*, 42(10):1298–1313, October 2007.
- [lu2007-3] Lu Y., Hu B., and Shi Y. Kinematic analysis and statics of a 2SPS+UPR parallel manipulator. *Multibody System Dynamics*, 18(4):619–636, September 2007.
- [lu2007-4] Lu Y., Hu B., and Liu P-L. Kinematics and dynamics analyses of a parallel manipulator with three active legs and one passive leg by a virtual serial mechanism. *Multibody System Dynamics*, 17:229–241, 2007.
- [lu2008] Lu Y. and Hu B. Determining singularity of parallel maniputors with n linear active legs by using CAD variation geometry. *Int. J. of Robotics and Automation*, 23(3):160–167, 2008.
- [lu2008-2] Lu Y. and Hu B. Analysis of stiffness and elastic deformation for some 3-5-dof PKMs with  $S\underline{P}R$  or RPS-type legs.  $ASME\ J.$  of  $Mechanical\ Design,\ 130(10):102307-1/8$ , October 2008.
- [lu2008-1] Lu Y. and others . Synthesis and analysis of kinematics/statics of a novel  $2\underline{P}S + S\underline{P}R + SP$  parallel manipulator. ASME J. of Mechanical Design, 130(9):092302-1/8, September 2008.
- [lu2008-3] Lu Y., Shi Y., and Hu B. Kinematic analysis of two novel 3 UPU I and 3 UPU II PKMs. Robotics and Autonomous Systems, 56(4):296–305, April 2008.
- [lu2009] Lu Y. and others . Kinematics/statics of a 4-dof over-constrained parallel manipulator with 3 legs. *Mechanism and Machine Theory*, 44(8):1497–1506, August 2009.
- [lu2009-1] Lu Y. and others . Kinematics and statics analysis of a novel 4-dof 2SPS+2SPR parallel manipulator and solving its workspace. *Robotica*, 27(5):771–778, September 2009.
- [lu2009-2] Lu Y., Hu B., and Sun T. Analyses of velocity, acceleration, statics and workspace of a 2(3-SPR) serial-parallel manipulator. *Robotica*, 27(4):529–538, July 2009.
- [lu2009-3] Lu Y. and Hu B. Analyzing kinematics and solving active/constrained forces of a 4-dof 3SPS+SP parallel manipulator. *Robotica*, 27(1):29–36, January 2009.
- [lu2009-4] Lu Y. and others . Kinematics/statics of a 4-dof over-constrained parallel manipulator with 3 legs. *Mechanism and Machine Theory*, 44(8):1497–1506, August 2009.

- [lu2009-5] Lu Y., Hu B., and Yu J. Analysis of kinematics/statics and workspace of a 2(SP + SPR + SPU) serial–parallel manipulator. *Multibody System Dynamics*, 21:361–374, 2009.
- [lu2010] Lu Y., Li S-Y., and Shi Y. Determining singularities of some 3-dof parallel manipulators with linear active legs by 3x3 translational/3x3 rotational jacobian matrices. *Int. J. of Robotics and Automation*, 25(4):335–343, 2010.
- [lu2010-1] Lu J., Y.and Xu and Yu J. Using CAD geometric variation approach machining complex workpiece by a 3-SPR parallel machine-tool. *Robotics and Computer-Integrated Manufacturing*, 26(2):130136, April 2010.
- [lu2010-2] Lu B., Y.and Hu and Yu J. Unification and simplification of dynamics of limited-dof parallel manipulators with linear active legs. *Int. J. of Robotics and Automation*, 25(2):81–88, 2010.
- [lu2010-3] Lu Y., Y.and Shi and Yu J. Determination of singularities of some 4-dof parallel manipulators by translational/rotational jacobian matrices. *Robotica*, 28(6):811–889, October 2010.
- [lu2012] Lu Y.and others. Computational derivation of valid kinematic limbs of spatial 3-dof parallel mechanisms without redundant constraints. *Robotica*, 30(4):559–569, July 2012.
- [lu2013] Lu Y.and others. Static and stiffness analysis of a novel six-component force/torque sensor with 3-RPPS compliant parallel structure. *Mechanism and Machine Theory*, 62:90–111, April 2013.
- [lu2013-1] Lu Y.and others. Kinematics/statics and workspace analysis of a 3-leg 5-dof parallel manipulator with a UPU-type composite active constrained leg. *Robotica*, 31(2):183–191, March 2013.
- [lu2014] Lu Y. Kinetostatic analysis of a novel 6-dof 3UPS parallel manipulator with multi-fingers. *Mechanism and Machine Theory*, 78:36–50, August 2014.
- [lu2014-1] Lu Y. and others . Kinematics and statics analysis of a novel 5-dof parallel manipulator with two composite rotational/linear active legs. Robotics and Computer-Integrated Manufacturing, 30(1):25-33, February 2014.
- [lu2014-2] Lu Y. and Li X.P. Dynamics analysis for a novel 6-dof parallel manipulator i with three planar limbs. *Advanced Robotics*, 28(16):1121–1132, 2014.
- [lu2016] Lu Y. and Dai Z. Dynamic model of redundant hybrid manipulator connected in series by three or more different parallel manipulators with linear active legs. *Mechanism and Machine Theory*, 103:222–235, 2016.
- [lu2016-1] Lu Y. and Ye N. Dynamics analysis of a novel 5-DoF 3SPU+2SPRR type parallel manipulator. *Advanced Robotics*, 30(9):595–607, 2016.
- [lu2017] Lu Z., Y.and Dai and Ye N. Stiffness analysis of parallel manipulatos with linear limb by considering inertial wrench of moving link and constrained wrench. *Robotics and Computer-Integrated Manufacturing*, 46:58–67, 2017.
- [lu2017-1] Lu N., Y.and Ye. Type synthesis of parallel mechanism by using sub-mechanisms and digital topological graphs. *Mechanism and Machine Theory*, 109:39–50, 2017.
- [lu2017-2] Lu Z., Y.and Dai and Ye N. Stiffness analysis of parallel manipulators with linear limbs by considering inertial wrench of moving links and constrained wrench. *Robotics and Computer-Integrated Manufacturing*, 46:58–67, 2017.
- [lu2017-3] Lu N., Y.and Ye. Type synthesis of parallel mechanisms by utilizing sub- mechanisms and digital topological graphs. *Mechanism and Machine Theory*, 109:39–50, 2017.
- [lu2017-4] Lu N., Y.and Ye and Ding L. Type synthesis of spatial 3-DoF parallel mechanisms with planar sub-chains using revised digital topological graphs and arrays. *Robotica*, 35:370–383, 2017.
- [lu2018] Lu Y.and others. Dynamics analysis of a novel 5-dof parallel manipulator with couple-constrained wrench. Robotica, 36:1421-1435, 2018.
- [lubrano2010] Lubrano E. and Clavel R. Thermal calibration of a 3 dof ultra high-precision robot operating in industrial environment. In *IEEE Int. Conf. on Robotics and Automation*, pages 3692–3697, Anchorage, May, 3-8, 2010.

- [lubrano2011] Lubrano E., Bouri M., and Clavel R. Ultra-high-precision industrial robots calibration. In *IEEE Int. Conf. on Robotics and Automation*, pages 228–233, Shangai, May, 9-13, 2011.
- [luces 2017] Luces M., J.K Mills., and Benhabib B. A review of redundant parallel kinematic mechanisms. *J. of Intelligent and Robotic Systems*, 86:175–188, 2017.
- [luckel2001] Lückel J. and others . Iterative model-based design of the parallel robot, TriPlanar. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 135–140, Como, July, 8-12, 2001.
- [luh96] Luh C.M., Adkins F.A., Haugh E.J., and Qiu C.C. Working capability analysis of Stewart platforms. *ASME J. of Mechanical Design*, 118(2):221–227, June 1996.
- [lumsden95] Lumsden C.J. CELLSIM: Virtual cells for research and molecular therapy design. J. of Medecine and Virtual Reality, 1(1):6–10, 1995.
- [luttmer2020] Luttmer N.G. and others. Treadmill based three tether parallel robot for evaluating auditory warnings while running. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [lv2017] Lv W., Tao L., and Ji Z. Design and control of cable-driven parallel robot with 6-dof active wave compensation. In 3rd International Conference on Control, Automation and Robotics, 2017.
- [lyder2009] Lyder A., Petersen H.K., and Stoy K. Representation and shape estimation of Odin, a parallel under-actuated modular robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, St Louis, October, 11-15, 2009.
- [lytle2008] Lytle A., Proctor F., and Saidi K. *Parallel manipulators, Towards new applications*, chapter Control of cable robots for construction applications, pages 1–20. ITECH, April 2008. **Keywords:** wire robot, applications, hardware, control.
- [ma-n2018] Ma N. and others . Design and stiffness analysis of a class of 2-DoF tendon driven parallel kinematics mechanism. *Mechanism and Machine Theory*, 129:202–217, 2018.
- [ma-y-2018] Ma Y. and others . Static and dynamic performance evaluation of a 3-DOF spindle head using CAD–CAE integration methodology. *Robotics and Computer-Integrated Manufacturing*, 41:1–12, 2018.
- [ma89] Ma O. and Angeles J. Direct kinematics and dynamics of a planar three-dof parallel manipulator. In ASME Design and Automation Conf., volume 3, pages 313–320, Montréal, September, 17-20, 1989.
- [ma91] Ma O. and Angeles J. Architecture singularities of platform manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 1542–1547, Sacramento, April, 11-14, 1991.
- [ma91-1] Ma O. and Angeles J. Optimum architecture design of platform manipulator. In *ICAR*, pages 1131–1135, Pise, June, 19-22, 1991.
- [mac79] McCallion H. and Pham D.T. The analysis of a six degrees of freedom work station for mechanized assembly. In 5th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 611–616, Montréal, July 1979.
- [machida92] Machida K. and others. New robotic mechanism using a parallel moving platform. In IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems, pages 425–430, Kobe, September, 16-20, 1992.
- [machida94] Machida K. Space-borne smart end effector. Advanced Robotics, 8(6):605, December 1994.
- [macho2007] Macho E. and others . Singularity free change of assembly mode in parallel manipulators. Application to the  $3-R\underline{P}R$  planar platform. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [macho2008] Macho E. and others . Transitions between multiple solutions of the direct kinematic problem. In ARK, Batz/mer, June, 23-26, 2008.
- [macho2009] Macho E. and others . Obtaining configuration space and singularity maps for parallel manipulators. *Mechanism and Machine Theory*, 44(11):2110–2125, November 2009.

- [macho2011] Macho E. and others . Software tool to compute, analyze and vizualise workspace of parallel kinematics robots. *Advanced Robotics*, 25(6-7):675–698, 2011.
- [macho2013] Macho E. and others . Enhancing operational workspace in parallel manipulator by connecting working modes. *Robotica*, 31(4):539–548, July 2013.
- [macho2019] Macho E. and others . Designing a translational parallel manipulator based on the 3ss kinematic joint. J. of Mechanisms and Robotics, 11(5), October 2019.
- [madsen2012] Madsen A.L. and Kristensen S.G. Design of Stewart platform for wave compensation. Master's thesis, Aalborg University, Aalborg, 2012. **Keywords:** applications,marine.
- [maeda92] Maeda K. and others. An analysis of passive impedance of 6-dof direct-drive wrist joint. In IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems, pages 433–438, Kobe, September, 16-20, 1992.
- [maeda93] Maeda K. and others . Time delay control of a 6 d.o.f. direct drive wrist joint using pneumatic actuators. In *ICAR 93*, pages 159–164, Tokyo, November, 1-2, 1993.
- [maeda99] Maeda K. and others . On design of a redundant wire-driven parallel robot WARP manipulator. In *IEEE Int. Conf. on Robotics and Automation*, Detroit, May, 10-15, 1999.
- [maier98] Maier T. and Woernle C. Inverse kinematics for an underconstrained cable suspension manipulator. In ARK, pages 97–104, Strobl, June 29- July 4, 1998.
- [majou2002] Majou F., Wenger P., and Chablat D. Design of 2-dof parallel mechanisms for machining applications. In ARK, pages 319–328, Caldes de Malavalla, June 29- July 2, 2002.
- [majou2004-phd] Majou F. Analyse cinétostatique des machines parallèles à translations. Ph.D. Thesis, Ecole Centrale, Nantes, September, 24, 2004. **Keywords:** 3 dof robot, performance analysis, stiffness, optimal design.
- [maloletov2019] Malosio A.V. and others. Error analysis in solving the inverse problem of the cable-driven parallel underactuated robot kinematics and methods for their elimination. In 9th IFAC Conf. on Manufacturing Modelling, Management and Control, Berlin, August, 28-30, 2019.
- [malosio2013] Malosio M. and others . A 3T2R parallel and partially decoupled kinematic architecture. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 444–449, Tokyo, November, 3-7, 2013.
- [manubens2013] Manubens M. and others . Motion planning for 6-D manipulation with aerial towed-cable systems. In *Robotics: Science and Systems*, Berlin, June 2013.
- [mao2011] Mao Y. and Agrawal S.K. A cable driven upper arm exoskeleton for upper extremity rehabilitation. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [mao2012] Mao Y. and Agrawal S.K. Design of a cable-driven arm exoskeleton (CAREX) for neural rehabilitation. *IEEE Trans. on Robotics*, 28(4):922–931, August 2012.
- [mao2015] Mao Y. and others . Human movement training with a cable driven ARm EXsokeleton (CAREX). *IEEE Trans. on Neural Systems and Rehabilitation Engineering*, 23(1):84–92, 2015.
- [marchalcrespo2013] Marchal-Crespo L. and others . The effect of haptic guidance and visual feedback on learning a complex tennis task. *Experimental Brain Research*, 3:277–291, 2013.
- [marchegiani76] Marchegiani D. Motion simulator, July, 6, 1976. United States Patent n° 3,967,387. **Keywords:** mechanical architecture,6 dof robot, patent.
- [marco89] Marco D, Torfason L., and Tesar D. Computer simulation and design of a three d.o.f. shoulder module. In NASA Conference on Space Telerobotics, volume 5, pages 273–282, Pasadena, January, 31, 1989.
- [marconi85] Marconi . The Gadfly manipulator. Research Report 732, Marconi Research Centre, 1985.
- [marconi86] Marconi . Development of the Tetrabot robotic manipulator. Research report, Marconi Research Centre, 1986.

- [marlow2014] Marlow K. and others. Workspace analysis of two similar 3-dof axis-symmetric parallel manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Chicago, September, 14-18, 2014.
- [marquet2001] Marquet F. and others . Archi: a new redundant parallel mechanism -modeling, control and first results. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Maui, Hawaii, October 29- November 3, 2001.
- [marquet2002] Marquet F. and others . Enhancing parallel robots accuracy with redundant sensors. In *IEEE Int. Conf. on Robotics and Automation*, pages 4114–4119, Washington, May, 11-15, 2002.
- [marquet2002-1] Marquet F. and others . Control of a 3-dof over-actuated parallel mechanism. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [martin-a2017] Martin A., Caro S., and Cardou P. Geometric determination of the cable cylinder interference regions in the workspace of a cable driven parallel robot. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [martin-a2018] Martin A., Caro S., and Cardou P. Design of a cable-driven parallel robot with grasping device. In 28th CIRP Design Conf., Nantes, 2018.
- [martin-th2013] Martin ., Th and others . Silicon linkage with novel compliant mechanism for piezoelectric actuation of an intraocular implant. Sensors and Actuators A, 188:335–341, 2012.
- [martin2006] Martin Y.S. and others . VERNE, a new 5-axes hybrid architecture machining center. In 5th Chemnitzer Parallelkinematik Seminar, pages 657–676, Chemnitz, April, 25-26, 2006.
- [martinez95] Martinez J.M.R. and Duffy J. A simple method for the velocity and acceleration analysis of in-parallel platforms. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 842–846, Milan, August 30- September 2, 1995.
- [martinez2000] Martinez J.M.R. and Duffy J. Forward and inverse acceleration analysis of in-parallel manipulators. ASME J. of Mechanical Design, 122(3):299–303, September 2000.
- [martinez2003] Martinez J.M.R. and Ravani B. On mobility analysis of linkages using group theory. ASME J. of Mechanical Design, 125(1):70–80, March 2003.
- [martini2015] Martini A. and others . Static balancing of a parallel kinematics machine with Linear Delta architecture: theory, design and numerical investigation. *Mechanism and Machine Theory*, 90:128–141, 2015.
- [masone2016] Masone C., Bülthoff H.H., and Stegagno P. Cooperative transportation of a payload using quadrotors: a reconfigurable cable-driven parallel robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Daejeon, October, 9-14, 2016.
- [masory92] Masory O. and Wang J. Workspace evaluation of Stewart platforms. In 22nd Biennial Mechanisms Conf., pages 337–346, Scottsdale, September, 13-16, 1992.
- [masory93] Masory O., Wang J., and Zhuang H. On the accuracy of a Stewart platform-part II: Kinematic calibration and compensation. In *IEEE Int. Conf. on Robotics and Automation*, pages 725–731, Atlanta, May, 2-6, 1993.
- [masory93-1] Masory O. and others . Design and construction of a Space Emulator. In *American Control Conf.*, pages 1825–1829, San Francisco, June, 2-4, 1993.
- [masory95] Masory O. and Wang J. Workspace evaluation of Stewart platforms. *Advanced Robotics*, 9(4):443–461, 1995.
- [masory95-1] Masory O. and Jihua Y. Measurement of pose repetability of Stewart platforms. *J. of Robotic Systems*, 12(12):821–832, 1995.
- [masory97] Masory O., Wang J., and Zhuang H. Kinematic modeling and calibration of a Stewart platform. *Advanced Robotics*, 11(5):519–539, 1997.
- [mass2006] Maass J. and others . Control strategies for enlarging a spatial parallel robot's workspace by change of configuration. In 5th Chemnitzer Parallelkinematik Seminar, pages 515–530, Chemnitz, April, 25-26, 2006.

- [masuda2000] Masuda T., Fujiwara M., and Arai T. Specific kinematic changes in a linear-actuated parallel mechanism according to differences in actuator arrangement. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Takamatsu, Japan, October 30- November 5, 2000.
- [masuda2002] Masuda T. and others. Mechanism configuration evaluation of a linear-actuated parallel mechanism using manipulability. In *IEEE Int. Conf. on Robotics and Automation*, pages 489–495, Washington, May, 11-15, 2002.
- [mata2008] Mata V. and others. *Parallel manipulators, Towards new applications*, chapter Dynamic parameter identification for parallel manipulators, pages 21–44. ITECH, April 2008. **Keywords:** calibration, dynamics, state of the art.
- [mathey95] Mathey C. Les simulateurs d'entrainement. Revue technique Thomson-CSF, 25(2):683-705, June 1995.
- [matich2015] Matich S. and others . A new single-port robotic system based on a parallel kinematic structure. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, September 28- October 2, 2015.
- [matich2016] Matich S. and others . 3-d force measurement using single axis force sensors in a new single port parallel kinematics surgical manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Daejeon, October, 9-14, 2016.
- [matone99] Matone R. and Roth B. In-parallel manipulators: a framework on how to model actuation scheme and a study of their effects on singular postures. ASME J. of Mechanical Design, 121(1):2–8, March 1999.
- [mattiazzo2007] Mattiazzo G. and others . A pneumatically actuated motion simulator. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [maurin-2004] Maurin B. and others . A parallel robotic system with force sensors for percutaneous procedures under CT guidance. In *MICCAI*, pages 176–183, St Malo, September, 26-29, 2004.
- [maurin2006] Maurin B. and others . A robotized positioning platform guided by computed tomography : Practical issues and evaluation. In *IEEE Int. Conf. on Robotics and Automation*, pages 251–256, Orlando, May, 16-18, 2006.
- [maurine96] Maurine P. and Dombre E. A calibration procedure for the parallel robot Delta 4. In *IEEE Int. Conf.* on Robotics and Automation, pages 975–980, Minneapolis, April, 24-26, 1996.
- [maurine96-1] Maurine P. and Dombre E. A registration and calibration procedure for a parallel robot. In 6th ISRAM, pages 447–452, Montpellier, May, 28-30, 1996.
- [maurine99] Maurine P., Abe K., and Uchiyama M. Toward more accurate parallel robots. In 15th World Congress of Int. Measurement Confederation, Osaka, June 1999.
- [mavroidis98] Mavroidis C. Completely specified displacements of a rigid body and their application in the direct kinematics of in-parallel mechanisms. In *ASME Design Engineering Technical Conference*, Atlanta, September, 13-16, 1998.
- [mavroidis99] Mavroidis C. Completely specified displacements of a rigid body and their application in the direct kinematics of in-parallel mechanisms. ASME J. of Mechanical Design, 121(4):485–491, December 1999.
- [mavroidis2001] Mavroidis C. and others. Fabrication of non-assembly mechanisms and robotic systems using rapid prototyping. ASME J. of Mechanical Design, 123(4):516–524, December 2001.
- [mayer96] Mayer St-Onge B. and Gosselin C. Singularity analysis and representation of spatial six-dof parallel manipulators. In ARK, pages 389–398, Portoroz-Bernadin, June, 22-26, 1996.
- [mayer2000] Mayer St-Onge B. and Gosselin C.M. Singularity analysis and representation of the general Gough-Stewart platform. *Int. J. of Robotics Research*, 19(3):271–288, March 2000.
- [mayhew2005] Mayhew D. and others. Development of the MACARM- a novel cable-robot for upper-link neurore-habilitation. In *Int. Conf. on Rehabilitation Robotics*, pages 299–302, Chicago, June 28- July 1, 2005.

- [maza99] Maza M., Fontaine J-G., and Baselga S. Motion transmission in VR systems: the spherical platform concept. In ISMCR Topical Workshop on VR and Advanced Human-robot Systems, pages 299–305, Budapest, 1999.
- [mazare2017] Mazare M., Taghizadeh M., and Najafi M.R. Contouring control of a 3-[P2(US)] parallel manipulator. Advanced Robotics, 31(9):496–508, 2017.
- [mazare2019] Mazare M., Taghizadeh M., and Najafi M.R. Inverse dynamics of a 3-P[2(US)] translational parallel robot. *Robotica*, 37:708–728, 2019.
- [mazare2019-1] Mazare M. and Taghizadeh M. Geometric optimization of a Delta type parallel robot using harmony search algorithm. *Robotica*, 37:1494–1512, 2019.
- [mbarek2005] Mbarek T., Nefzi M., and Corves B. Kinematic analysis and workspace determination of a parallel manipulator with five degree of freedom. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [mbarek2007] Mbarek T., Nefzi M., and Corves B. Kinematics and kinetics of a high-dynamic sewing plant for FRC materials based on parallel manipulator. In 2nd Int. Congress, Design and Modelling of mechanical systems, Monastir, March, 19-21, 2007.
- [mbarek2007-1] Mbarek T., Lonij G., and Corves B. Singularity analysis of a fully parallel manipulator with five-degrees-of-freedom based on Grassmann line geometry. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [mcaree96] McAree P.R. and Daniel R.W. A fast, robust solution to the Stewart platform forward kinematics. *J. of Robotic Systems*, 13(7):407–427, July 1996.
- [mcaree99] McAree P.R. and Daniel R.W. An explanation of never-special assembly changing motions of the 3-3 parallel manipulators. *Int. J. of Robotics Research*, 18(6):556–574, June 1999.
- [mccann2017] McCann C.M. and Dollar A.M. Design of a Stewart platform-inspired dexterous hand for 6-dof within-hand manipulation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Vancouver, September, 24-28, 2017.
- [mccarthy2000] McCarthy J.M. Mechanism synthesis theory and the design of robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 55–60, San Francisco, April, 24-28, 2000.
- [mccloy90] McCloy D. Some comparisons of serial-driven and parallel driven manipulators. *Robotica*, 8(4):355–362, 1990.
- [mccoll2009] McColl D. and Notash L. Extension of the Antipodal theorem to workspace analysis of planar wire-actuated manipulators. In *Computational Kinematics*, pages 9–16, Duisburg, May, 6-8, 2009.
- [mccoll2011] McColl D. and Notash L. Workspace formulation of planar wire-actuated parallel manipulators. *Robotica*, 29(4):607–617, July 2011.
- [mcinroy2000] McInroy J. E. and Hamann J.C. Design and control of flexure jointed hexapods parallel manipulator. *IEEE Trans. on Robotics and Automation*, 16(4):372–381, August 2000.
- [mcinroy2002] McInroy J. E. Modeling and design of flexure jointed Stewart platforms for control purposes. *IEEE/ASME Trans. on Mechatronics*, 7(1):95–99, March 2002.
- [mcinroy2005] McInroy J. E., Jafari F., and O'Brien J. Tri-symmetric orthogonal Gough-Stewart platforms. In *IEEE Int. Conf. on Robotics and Automation*, pages 948–953, Barcelona, April, 19-22, 2005.
- [mejia2014] Mejia L., Simas H., and Martins D. Force capability polytope of a  $4 \underline{R}RR$  redundant planar parallel manipulator. In ARK, pages 87–94, Ljulbjana, June 29- July 3, 2014.
- [mejia2016] Mejia L., Simas H., and Martins D. Wrench capability in redundant planar parallel manipulators with net degree of constraint equal to four, five or six. *Mechanism and Machine Theory*, 105:58–79, 2016.
- [mejia2022] Mejia L. and others . Best operation regions in a planar cable driven system. In ARK, Bilbao, June, 26-30, 2022.

- [mendes-lopes96] Mendes Lopes A. and Gomes de Almeida F. Manipulability optimization of a parallel structure robotic manipulator. In 2nd Portugese Automatic Control Conf., Porto, September 1996.
- [meng-j2005] Meng J., Liu G.F., and Li Z. A geometric theory for synthesis and analysis of sub-6 dof parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2949–2954, Barcelona, April, 19-22, 2005.
- [meng-j2007] Meng J. and others . Accuracy analysis of general parallel manipulators with joint clearance. In *IEEE Int. Conf. on Robotics and Automation*, pages 889–894, Roma, April, 10-14, 2007.
- [meng-j2007-1] Meng J., Liu G.F., and Li Z. A geometric theory for analysis and synthesis of sub-6 dof parallel manipulators. *IEEE Trans. on Robotics*, 23(4):625–649, August 2007.
- [meng-j2007-2] Meng J., Zhang D., and Li X. Assembly problem of overconstrained and clearance-free parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1183–1188, Roma, April, 10-14, 2007.
- [meng-j2009] Meng J., Zhang D., and Li Z. Accuracy analysis of parallel manipulators with joint clearance. ASME J. of Mechanical Design, 131(1):011013-1/011013-9, January 2009.
- [meng-q2016] Meng Q. and others . Adaptive vector sliding mode fault-tolerant control of the uncertain Stewart platform based on position measurement only. *Robotica*, 34(6):1297–1320, June 2016.
- [meng-q2020] Meng Q. and others. An evaluation approach for motion-force interaction performance of parallel manipulators with closed-loop passive limbs. *Mechanism and Machine Theory*, 149, 2020.
- [meng-q2020-1] Meng Q. and others . Motion–force interaction performance analyses of redundantly actuated and overconstrained parallel robots with closed-loop subchains. ASME J. of Mechanical Design, 142, October 2020.
- [meng-q2022] Meng Q., Liu X-J., and Xie F. Design and development of a Schönflies-motion parallel robot with articulated platforms and closed-loop passive limbs. *Robotics and Computer-Integrated Manufacturing*, 77, October 2022.
- [meng2003] Meng G., Tiemin L., and Wensheng Y. Calibration method and experiment of Stewart platform using a laser tracker. In *Int. Conf on Systems, Man and Cybernetics*, pages 2797–2802, The Hague, October, 10-13, 2003.
- [mengx-2014] Meng X. and others . Type synthesis of parallel robotic mechanisms: framework and brief review. Mechanism and Machine Theory, 78:177–186, 2014.
- [menon2009] Menon C. and others . Geometrical optimization of parallel mechanism based on natural frequency evaluation. application to a spherical mechanism for future space applications. *IEEE Trans. on Robotics*, 25(2):929–940, February 2009.
- [merkle94] Merkle R.C. A new family of six degree of freedom positional devices. 1994, http://nano.xerox.com/nanotech/6dof.html. **Keywords:** mechanical architecture,redundant robot.
- [merlet86-phd] Merlet J-P. Contribution à la commande par retour d'efforts. Application au contrôle des robots parallèles. Ph.D. Thesis, Université Paris VI, Paris, June, 18, 1986. **Keywords:** control, kinematics, force feedback.
- [merlet87] Merlet J-P. Parallel manipulators, Part 1, theory. Research Report 646, INRIA, March 1987.
- [merlet87-1] Merlet J-P. Kinematics, singular configurations and compliance of parallel manipulators. In *ICAR*, pages 125–136, Versailles, October, 13-15, 1987.
- [merlet87-3] Merlet J-P. Robots parallèles. In AFCET RFIA, pages 569–574, Antibes, November, 18-20, 1987.
- [merlet88] Merlet J-P. Parallel manipulators, Part 2, Singular Configurations and Grassmann geometry. Research Report 791, INRIA, February 1988.
- [merlet88-1] Merlet J-P. Force-feedback control of parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1484–1489, Philadelphia, April, 24-29, 1988.

- [merlet89] Merlet J-P. Manipulateurs parallèles, 3eme partie : applications. Research Report 1003, INRIA, March 1989.
- [merlet89-1] Merlet J-P. Manipulateurs parallèles, 4eme partie : mode d'assemblage et cinématique directe sous forme polynomiale. Research Report 1135, INRIA, December 1989.
- [merlet89-2] Merlet J-P. Singular configurations of parallel manipulators and Grassmann geometry. In Boissonnat J-D. and J-P.Laumond, editors, *Geometry and Robotics*, volume LNCS 391, pages 194–212. Springer-Verlag, 1989. **Keywords:** singularity,grassmann geometry.
- [merlet89-3] Merlet J-P. Singular configurations of parallel manipulators and Grassmann geometry. *Int. J. of Robotics Research*, 8(5):45–56, October 1989.
- [merlet90] Merlet J-P. Les Robots parallèles. Hermès, Paris, 1990.
- [merlet90-1] Merlet J-P. Assembly modes and minimal polynomial formulation of the direct kinematics of parallel manipulators. In *CSME Mechanical Engineering Forum 1990*, pages 343–348, Toronto, June, 3-9, 1990.
- [merlet90-2] Merlet J-P. Assembly modes and direct kinematics of parallel manipulators. In *ISRAM*, volume 3, pages 43–48, Burnaby, July, 18-20, 1990. ASME Press Series.
- [merlet90-3] Merlet J-P. Symbolic computation for the determination of the minimal direct kinematics polynomial and the singular configurations of parallel manipulators. In ARK, Linz, September, 10-12, 1990.
- [merlet90-4] Merlet J-P. An algorithm for the forward kinematics of general 6 d.o.f. parallel manipulators. Research Report 1331, INRIA, November 1990.
- [merlet91] Merlet J-P. and Gosselin C. Nouvelle architecture pour un manipulateur parallèle à 6 degrés de liberté. Mechanism and Machine Theory, 26(1):77–90, 1991.
- [merlet91-1] Merlet J-P. An algorithm for the forward kinematics of general parallel manipulators. In *ICAR*, pages 1131–1135, Pise, June, 19-22, 1991.
- [merlet91-2] Merlet J-P. Articulated device, for use in particular in robotics, October, 1, 1991. United States Patent n° 5,053,687. **Keywords:** mechanical architecture,6 dof robot, patent.
- [merlet92] Merlet J-P. Manipulateurs parallèles, 5eme partie : Détermination de l'espace de travail à orientation constante. Research Report 1645, INRIA, March 1992.
- [merlet92-1] Merlet J-P. Direct kinematics and assembly modes of parallel manipulators. *Int. J. of Robotics Research*, 11(2):150–162, April 1992.
- [merlet92-2] Merlet J-P. On the infinitesimal motion of a parallel manipulator in singular configurations. In *IEEE Int. Conf. on Robotics and Automation*, pages 320–325, Nice, May, 12-14, 1992.
- [merlet92-3] Merlet J-P. Geometrical determination of the workspace of a constrained parallel manipulator. In ARK, pages 326–329, Ferrare, September, 7-9, 1992.
- [merlet92-4] Merlet J-P. Parallel manipulators: state of the art and perspective. In *IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems*, pages 403–408, Kobe, September, 16-20, 1992.
- [merlet92-6] Merlet J-P. Parallel manipulators: state of the art and perspective. *Journal of Robotics Society of Japan*, 10(6):57–62, October 1992.
- [merlet92-7] Merlet J-P. Geometry and Kinematic singularities of closed-loop manipulators. J. of Laboratory Robotic and Automation, 4(1):85–96, 1992.
- [merlet93] Merlet J-P. Closed-form resolution of the direct kinematics of parallel manipulators using extra sensors data. In *IEEE Int. Conf. on Robotics and Automation*, pages 200–204, Atlanta, May, 2-7, 1993.
- [merlet93-1] Merlet J-P. Manipulateurs parallèles, 6eme partie : Détermination des espaces de travail en orientation. Research Report 1921, INRIA, May 1993.
- [merlet93-2] Merlet J-P. Manipulateurs parallèles, 7eme partie : Vérification et planification de trajectoire dans l'espace de travail. Research Report 1940, INRIA, June 1993.

- [merlet93-3] Merlet J-P. Algebraic geometry for the study of kinematics of parallel manipulators. In J. Angeles P. Kovacs, G. Hommel, editor, *Computational Kinematics*, pages 183–194. Kluwer, 1993.
- [merlet93-4] Merlet J-P. Orientation workspace of a parallel manipulator with a fixed point. In *ICAR*, pages 141–146, Tokyo, November, 1-2, 1993.
- [merlet93-5] Merlet J-P. Forward kinematics of non-polyhedral parallel manipulators. ASME J. of Mechanical Design, 115(4):938–940, December 1993.
- [merlet93-6] Merlet J-P. Direct kinematics of parallel manipulators. *IEEE Trans. on Robotics and Automation*, 9(6):842–845, December 1993.
- [merlet93-7] Merlet J-P. Parallel manipulators: state of the art and perspective. In Takamori T. and Tsuchiya K., editors, *Robotics, Mechatronics and Manufacturing Systems*. Elsevier, 1993. **Keywords:** state of the art.
- [merlet93-h] Merlet J-P. Les robots parallèles, June, 21, 1993. Habilitation à diriger les recherches, UNSA, Nice.
- [merlet94] Merlet J-P. Some algebraic problems arising in the field of mechanisms theory. In *MEGA*, Santander, April, 5-9, 1994.
- [merlet94-1] Merlet J-P. Trajectory verification in the workspace of parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2166–2171, San Diego, May, 8-13, 1994.
- [merlet94-2] Merlet J-P. and Mouly N. Espaces de travail et planification de trajectoire des robots parallèles plans. Research Report 2291, INRIA, February 1994.
- [merlet94-3] Merlet J-P. Parallel manipulators: state of the art and perspective. Advanced Robotics, 8(6):589–596, December 1994.
- [merlet94-4] Merlet J-P. Trajectory verification in the workspace for parallel manipulators. *Int. J. of Robotics Research*, 13(4):326–333, August 1994.
- [merlet94-5] Merlet J-P. Détermination de l'espace de travail d'un robot parallèle pour une orientation constante. Mechanism and Machine Theory, 29(8):1099–1113, November 1994.
- [merlet95] Merlet J-P. Designing a parallel robot for a specific workspace. Research Report 2527, INRIA, April 1995.
- [merlet95-1] Merlet J-P. Determination of the orientation workspace of parallel manipulators. *J. of Intelligent and Robotic Systems*, 13(1):143–160, September, 4-6, 1995.
- [merlet95-2] Merlet J-P. Designing a parallel robot for a specific workspace. In J-P. Merlet B. Ravani, editor, Computational Kinematics, pages 203–212. Kluwer, 1995.
- [merlet96-1] Merlet J-P. Direct kinematics of planar parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 3744–3749, Minneapolis, April, 24-26, 1996.
- [merlet96-2] Merlet J-P. Workspace-oriented methodology for designing a parallel manipulator. In *IEEE Int. Conf.* on Robotics and Automation, pages 3726–3731, Minneapolis, April, 24-26, 1996.
- [merlet96-3] Merlet J-P. Workspace-oriented methodology for designing a parallel manipulator. In *IDMME*, Nantes, April, 15-17, 1996.
- [merlet96-4] Merlet J-P. Redundant parallel manipulators. J. of Laboratory Robotic and Automation, 8(1):17–24, 1996
- [merlet96-5] Merlet J-P., Gosselin C., and Mouly N. Workspaces of planar parallel manipulators. In 11th RoManSy, pages 37–44, Udine, July, 1-4, 1996.
- [merlet96-6] Merlet J-P. Some algebraic problems arising in the field of mechanisms theory. In *Progress in Mathematics*, volume 143. Birkhäuser Verlag, 1996. **Keywords:** mechanism theory.
- [merlet96-7] Merlet J-P. Designing a parallel manipulator for a specific workspace. In *ISRAM*, pages 441–446, Montpellier, May, 28-30, 1996.
- [merlet97] Merlet J-P. Les Robots parallèles. Hermès, Paris, 1997.

- [merlet97-1] Merlet J-P. Articular velocities of parallel manipulators, Part II: Finding all the robots with fixed extremal articular velocity for performing a fixed cartesian velocity over a whole workspace. In *IEEE Int. Conf. on Robotics and Automation*, pages 3262–3267, Albuquerque, April, 21-28, 1997.
- [merlet97-2] Merlet J-P. First experiments with MIPS 1 (Mini In-Parallel Positionning System). In *ISER*, pages 372–379, Barcelone, June, 15-18, 1997.
- [merlet97-3] Merlet J-P. Democrat: A DEsign Methodology for the Conception of robots with parallel ArchiTecture. *Robotica*, 15(4):367–373, July August , 1997.
- [merlet97-4] Merlet J-P. Robot parallèle: Etat de l'art. In 13<sup>eme</sup> Congrès Français de Mécanique, volume 1, pages 331–334, Poitiers, September, 1-5, 1997.
- [merlet97-5] Merlet J-P. Designing a parallel manipulator for a specific workspace. *Int. J. of Robotics Research*, 16(4):545–556, August 1997.
- [merlet97-6] Merlet J-P. Estimation efficace des caractéristiques de robots paralèlles: Extremums des raideurs et des coordonnées, vitesses, forces articulaires et singularités dans un espace de travail en translation. Research Report 3243, INRIA, September 1997.
- [merlet97-7] Merlet J-P. Democrat: A DEsign Methodology for the Conception of robots with parallel ArchiTecture. In *IROS*, pages 1630–1636, Grenoble, September, 7-11, 1997.
- [merlet97-8] Merlet J-P. Miniature in-parallel positionning system MIPS for minimally invasive surgery. In World Congress on Medical Physics and Biomedical Engineering, Nice, September, 14-19, 1997.
- [merlet97-9] Merlet J-P. Determination of the presence of singularities in a workspace volume of a parallel manipulator. In NATO-ASI, Computational methods in mechanisms, Sts. Konstantin and Elena Resort, June, 16-28, 1997.
- [merlet98] Merlet J-P., Gosselin C., and Mouly N. Workspaces of planar parallel manipulators. *Mechanism and Machine Theory*, 33(1/2):7–20, January 1998.
- [merlet98-1] Merlet J-P. Efficient computation of the extremum of the articular velocities of a parallel manipulator in a translation workspace. In *IEEE Int. Conf. on Robotics and Automation*, pages 1976–1981, Louvain, May, 18-20, 1998.
- [merlet98-2] Merlet J-P. Efficient estimation of the extremal articular forces of a parallel manipulator in a translation workspace. In *IEEE Int. Conf. on Robotics and Automation*, pages 1982–1987, Louvain, May, 18-20, 1998.
- [merlet98-3] Merlet J-P. Determination of the presence of singularities in 6D workspace of a Gough parallel manipulator. In ARK, pages 39–48, Strobl, June 29- July 4, 1998.
- [merlet98-4] Merlet J-P. Determination of 6D workspaces of a Gough-type 6 d.o.f. parallel manipulator. In 12th RoManSy, pages 261–268, Paris, July, 6-9, 1998.
- [merlet98-5] Merlet J-P. Designing a parallel structure for a milling machine. In *Rencontre Franco-Israelienne sur la Robotique*, Besancon, May, 13-14, 1998.
- [merlet98-6] Merlet J-P. The importance of optimal design for parallel structures. In *First European-American Forum* on Parallel Kinematic Machines, Milan, August 31- September 1, 1998.
- [merlet98-7] Merlet J-P. Efficient design of parallel robots. In New machine concepts for handling and manufacturing devices on the basis of parallel structures, pages 1–13, Braunschweig, November, 10-11, 1998.
- [merlet99] Merlet J-P. Finding the extrema of the leg lengths of a Gough-type parallel robot when the platform is moving in a given 6D workspace. In 10th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 86–91, Oulu, June, 20-24, 1999.
- [merlet99-2] Merlet J-P. Determination of 6D workspaces of Gough-type parallel manipulator and comparison between different geometries. *Int. J. of Robotics Research*, 18(9):902–916, October 1999.
- [merlet99-3] Merlet J-P. Forward kinematics of parallel robots. In *IMACS Conf. on Applications of Computer Algebra*, El Escorial, June, 24-27, 1999.

- [merlet99-4] Merlet J-P. Parallel robot: open problems. In 9th Int. Symp. of Robotics Research, Snowbird, October, 9-12, 1999.
- [merlet2000] Merlet J-P., Perng M-W., and Daney D. Optimal trajectory planning of a 5-axis machine tool based on a 6-axis parallel manipulator. In *ARK*, pages 315–322, Piran, June, 25-29, 2000.
- [merlet2000-1] Merlet J-P. and Dahan M. Un micro-robot parallèle pour l'inspection industrielle et l'endoscopie médicale. In *Troisième Journées du Pôle Micro-robotique*, Cachan, June, 27-28, 2000.
- [merlet2000-2] Merlet J-P. A formal-numerical approach to determine the accuracy of a parallel robot in a 6D workspace. In 13th RoManSy, pages 51–58, Zakopane, July, 3-6, 2000.
- [merlet2000-3] Merlet J-P. On the separability of the solutions of the direct kinematics of a special class of planar 3-RPR parallel manipulator. In 26th ASME Biennial Mechanisms and Robotics Conference, Baltimore, September, 10-13, 2000.
- [merlet2000-4] Merlet J-P. An efficient trajectory verifier for motion planning of parallel machine. In *Parallel Kinematic Machines Int. Conf.*, Ann Arbor, September, 14-15, 2000.
- [merlet2000-5] Merlet J-P. Parallel robots. Kluwer, Dordrecht, 2000. Keywords: state of the art.
- [merlet2005-5] Merlet J-P. Parallel robots, 2nd Edition. Springer, Heidelberg, 2005. Keywords: state of the art.
- [merlet2001] Merlet J-P. and Daney D. A formal-numerical approach to determine the presence of singularity within the workspace of a parallel robot. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 167–176. EJCK, Seoul, May, 20-22, 2001. **Keywords:** singularity.
- [merlet2001-1] Merlet J-P. An improved design algorithm based on interval analysis for parallel manipulator with specified workspace. In *IEEE Int. Conf. on Robotics and Automation*, pages 1289–1294, Seoul, May, 23-25, 2001.
- [merlet2001-2] Merlet J-P. Perspectives à court et moyen terme pour la robotique. In *Rencontre internationale de prospective du Sénat*, Paris, June, 27, 2001.
- [merlet2001-3] Merlet J-P. and Dahan M. Le micro-robot parallèle MIPS. In *Quatrième Journées du Pôle Micro-robotique*, Lyon, July, 4-5, 2001.
- [merlet2001-4] Merlet J-P. System-solving and parallel robots. In Workshop on Robot Mechanics, Paris, July, 12-13, 2001.
- [merlet2001-5] Merlet J-P. Micro parallel robot MIPS for medical applications. In *IEEE Int. Conf. on Emerging Technologies and Factory Automation*, Antibes, October, 15-18, 2001.
- [merlet2001-6] Merlet J-P. A generic trajectory verifier for the motion planning of parallel robots. ASME J. of Mechanical Design, 123(4):510–515, December 2001.
- [merlet2002] Merlet J-P. The need for a systematic methodology for the evaluation and optimal design of parallel manipulators. In 3rd Chemnitzer Parallelkinematik Seminar, pages 49–62, Chemnitz, April, 23-25, 2002.
- [merlet2002-1] Merlet J-P. A general methodology for certified evaluation of the performances of parallel robots. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 97–106, Braunschweig, May, 29-30, 2002.
- [merlet2002-2] Merlet J-P. Optimal design for the micro robot MIPS. In *IEEE Int. Conf. on Robotics and Automation*, Washington, May, 11-15, 2002.
- [merlet2002-3] Merlet J-P. Still a long way to go on the road for parallel mechanisms. In ASME 27th Biennial Mechanisms and Robotics Conf., Montréal, September 29- October 2, 2002.
- [merlet2002-4] Merlet J-P. An initiative for the kinematic study of parallel manipulators. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, pages 2–9, Québec, October, 3-4, 2002.
- [merlet2002-5] Merlet J-P. Micro-robot parallèle pour la chirurgie minimalement invasive. In MS4CMS'02, Rocquencourt, November, 12-15, 2002.

- [merlet2003] Merlet J-P. Determination of the optimal geometry of modular parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, Taipei, September, 14-19, 2003.
- [merlet2004] Merlet J-P. Solving the forward kinematics of a Gough-type parallel manipulator with interval analysis. *Int. J. of Robotics Research*, 23(3):221–236, 2004.
- [merlet2004-1] Merlet J-P. Getting exact information from the inverse jacobian matrix of parallel and serial robots. In 11th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1951–1955, Tianjin, April, 1-4, 2004.
- [merlet2004-2] Merlet J-P. Guaranteed in-the-workspace improved trajectory/suface/volume verification for parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, New Orleans, April, 28-30, 2004.
- [merlet2004-3] Merlet J-P. Analysis of the influence of wire interference on the workspace of wire robots. In ARK, pages 211–218, Sestri-Levante, June 28- July 1, 2004.
- [merlet2005] Merlet J-P. and Daney D. Dimensional synthesis of parallel robots with a guaranteed given accuracy over a specific workspace. In *IEEE Int. Conf. on Robotics and Automation*, Barcelona, April, 19-22, 2005.
- [merlet2005-1] Merlet J-P. and Daney D. Kinematics and synthesis of cams-coupled parallel robots. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [merlet2005-2] Merlet J-P. The necessity of optimal design for parallel machines and a possible certified methodology. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 7–20, Braunschweig, May, 10-11, 2005.
- [merlet2005-3] Merlet J-P. Optimal design of robots. In Robotics: Science and Systems, Boston, June, 8-11, 2005.
- [merlet2005-4] Merlet J-P. Jacobian, manipulability, condition number and accuracy of parallel robots. In *ISRR*, San Francisco, October, 12-15, 2005.
- [merlet2006] Merlet J-P. Jacobian, manipulability, condition number, and accuracy of parallel robots. ASME J. of Mechanical Design, 128(1):199–206, January 2006.
- [merlet2006-1] Merlet J-P. Computing the worst case accuracy of a PKM over a workspace or a trajectory. In 5th Chemnitzer Parallelkinematik Seminar, pages 83–96, Chemnitz, April, 25-26, 2006.
- [merlet2006-2] Merlet J-P. and Daney D. Legs interference checking of parallel robots over a given workspace or trajectory. In *IEEE Int. Conf. on Robotics and Automation*, pages 757–762, Orlando, May, 16-18, 2006.
- [merlet2006-3] Merlet J-P. and Donelan P. On the regularity of the inverse jacobian of parallel robot. In ARK, pages 41–48, Ljubljana, June, 26-29, 2006.
- [merlet2007] Merlet J-P. and Daney D. A new design for wire-driven parallel robot. In 2nd Int. Congress, Design and Modelling of mechanical systems, Monastir, March, 19-21, 2007.
- [merlet2007-2] Merlet J-P. A local motion planner for closed-loop robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3088–3093, San Diego, September, 22-26, 2007.
- [merlet2007-1] Merlet J-P. A formal-numerical approach for robust in-workspace singularity detection. *IEEE Trans. on Robotics*, 23(3):393–402, June 2007.
- [merlet2008] Merlet J-P. Kinematics of the wire-driven parallel robot MARIONET using linear actuators. In *IEEE Int. Conf. on Robotics and Automation*, Pasadena, May, 19-23, 2008.
- [merlet2008-2] Merlet J-P. and Gosselin C. *Handbook of Robotics*, chapter Parallel Mechanisms and Robots, pages 269–285. Springer, Heidelberg, 2008. **Keywords:** state of the art.
- [merlet2008-3] Merlet J-P. and Daney D. Appropriate Design of Parallel Manipulators, chapter 1, pages 1–25. Springer, 2008. **Keywords:** state of the art.
- [merlet2008-4] Merlet J-P. Analysis of wire elasticity for wire-driven parallel robots. In 2nd European Conf. on Mechanism Science (Eucomes), pages 471–478, Cassino, September, 17-20, 2008.
- [merlet2009] Merlet J-P. Kinematic analysis of a spatial four-wire driven parallel crane without constraining mechanism. In *Computational Kinematics*, pages 1–8, Duisburg, May, 6-8, 2009.

- [merlet2010] Merlet J-P. and Daney D. A portable, modular parallel wire crane for rescue operations. In *IEEE Int. Conf. on Robotics and Automation*, pages 2834–2839, Anchorage, May, 3-8, 2010.
- [merlet2010-1] Merlet J-P. MARIONET, a family of modular wire-driven parallel robots. In ARK, pages 53–62, Piran, June 28- July 1, 2010.
- [merlet2011] Merlet J-P. and others . Siropa: singularités des robots parallèles. In *Colloque ANR*, Paris, January, 11-12, 2011.
- [merlet2012] Merlet J-P. The kinematics of the redundant N-1 wire driven parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 2313–2318, Saint Paul, May, 14-18, 2012.
- [merlet2012-1] Merlet J-P. On the accuracy of N-1 wire-driven parallel robots. In *RoManSy*, pages 1–10, Paris, June, 12-15, 2012.
- [merlet2012-2] Merlet J-P. Wire-driven parallel robots: open issues. In RoManSy, Paris, June, 12-15, 2012.
- [merlet2012-3] Merlet J-P. Managing the redundancy of N-1 wire-driven parallel robots. In ARK, pages 405–412, Innsbruck, June, 25-28, 2012.
- [merlet2012-4] Merlet J-P. Unsolved issues in kinematics and redundancy of wire-driven parallel robots. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [merlet2012-5] Merlet J-P. Comparison of actuation schemes for wire-driven parallel robots. In 4th European Conf. on Mechanism Science (Eucomes), pages 245–254, Santander, September, 19-21, 2012.
- [merlet2013] Merlet J-P. Kinematic analysis of the 4-3-1 and 3-2-1 wire-driven parallel crane. In *IEEE Int. Conf. on Robotics and Automation*, pages 4620–4625, Karlsruhe, May, 6-10, 2013.
- [merlet2013-1] Merlet J-P. Further analysis of the 2-2 wire-driven parallel crane. In *Computational Kinematics*, Barcelona, May, 12-15, 2013.
- [merlet2013-2] Merlet J-P. Robots à câbles, tour d'horizon et défis. In *Journées Nationales de la Recherche en Robotique*, Annecy, October, 16-18, 2013.
- [merlet2014] Merlet J-P. Checking the cable configuration of cable-driven parallel robots on a trajectory. In *IEEE Int. Conf. on Robotics and Automation*, pages 1586–1591, Hong-Kong, May 31- June 7, 2014.
- [merlet2014-1] Merlet J-P. The influence of discrete-time control on the kinematico-static behavior of cable-driven parallel robot with elastic cables. In ARK, pages 113–121, Ljulbjana, June 29- July 3, 2014.
- [merlet2014-2] Merlet J-P. The forward kinematics of cable-driven parallel robots with sagging cables. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 3–16, Duisburg, August, 24-27, 2014.
- [merlet2014-3] Merlet J-P. On the redundancy of cable-driven parallel robots. In 5th European Conf. on Mechanism Science (Eucomes), pages 31–39, Guimares, September, 16-19, 2014.
- [merlet2015] Merlet J-P. The kinematics of cable-driven parallel robots with sagging cables: preliminary results. In *IEEE Int. Conf. on Robotics and Automation*, pages 1593–1598, Seattle, May, 26-30, 2015.
- [merlet2015-1] Merlet J-P. On the inverse kinematics of cable-driven parallel robots with up to 6 sagging cables. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 4536–4361, Hamburg, Germany, September 28- October 2, 2015.
- [merlet2015-2] Merlet J-P. On the real-time calculation of the forward kinematics of suspended cable-driven parallel robots. In 14th IFToMM World Congress on the Theory of Machines and Mechanisms, Taipei, October, 27-30, 2015.
- [merlet2015-3] Merlet J-P. On the robustness of cable configurations of suspended cable-driven parallel robots. In 14th IFToMM World Congress on the Theory of Machines and Mechanisms, Taipei, October, 27-30, 2015.
- [merlet2016] Merlet J-P. On the workspace of suspended cable-driven parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, Stockholm, May, 16-20, 2016.

- [merlet2016-1] Merlet J-P. Cable-driven parallel robots and their extension to other domains. In *IEEE Int. Conf. on Robotics and Automation*, Stockholm, May, 16-20, 2016.
- [merlet2016-2] Merlet J-P. A new generic approach for the inverse kinematics of cable-driven parallel robot with 6 deformable cables. In *ARK*, Grasse, June, 27-30, 2016.
- [merlet2016-3] Merlet J-P. Preliminaries of a new approach for the direct kinematics of suspended cable-driven parallel robot with deformable cables. In *Eucomes*, Nantes, September, 20-23, 2016.
- [merlet2016-4] Merlet J-P. A generic numerical continuation scheme for solving the direct kinematics of cable-driven parallel robot with deformable cables. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Daejeon, October, 9-14, 2016.
- [merlet2017] Merlet J-P. Direct kinematics of CDPR with extra cable orientation sensors: the 2 and 3 cables case with perfect measurement and sagging cables. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Vancouver, September, 24-28, 2017.
- [merlet2017-1] Merlet J-P. Direct kinematics of CDPR with extra cable orientation sensors: the 2 and 3 cables case with perfect measurement and ideal or elastic cables. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [merlet2017-2] Merlet J-P. Computing cross-sections of the workspace of cable-driven parallel robots with 6 sagging cables. In *Computational Kinematics*, Poitiers, 2017.
- [merlet2017-3] Merlet J-P. Simulation of discrete-time controlled cable-driven parallel robots on a trajectory. *IEEE Trans. on Robotics*, 33(3):675–688, June 2017.
- [merlet2018] Merlet J-P. An experimental investigation of extra measurements for solving the direct kinematics of cable-driven parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, Brisbane, May, 21-25, 2018.
- [merlet2018-1] Merlet J-P. Computing cross-sections of the workspace of a cable-driven parallel robot with 6 sagging cables having limited lengths. In *ARK*, Bologna, July, 1-5, 2018.
- [merlet2018-3] Merlet J-P. Computing cross-sections of the workspace of suspended cable-driven parallel robot with sagging cables having tension limitations. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Madrid, October, 1-5, 2018.
- [merlet2018-4] Merlet J-P. Some properties of the Irvine cable model and their use for the kinematic analysis of cable-driven parallel robots. In 7tht European Conf. on Mechanism Science (Eucomes), Aachen, September, 4-6, 2018.
- [merlet2019] Merlet J-P. Some properties of the Irvine cable model and their use for the kinematic analysis of cable-driven parallel robots. *Mechanism and Machine Theory*, 135:271–280, 2019.
- [merlet2019-1] Merlet J-P. Singularity of cable-driven parallel robot with sagging cables: preliminary investigation. In *IEEE Int. Conf. on Robotics and Automation*, Montréal, May, 20-24, 2019.
- [merlet2019-2] Merlet J-P. Improving cable length measurements for large CDPR using the Vernier principle. In 4th Int. Conf. on cable-driven parallel robots (CableCon), Cracow, June 30- July 4, 2019.
- [merlet2019-3] Merlet J-P. Influence of parameters uncertainties on the positioning of cable-driven parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Macau, November, 4-8, 2019.
- [merlet2020] Merlet J-P. The forward kinematics of the 4-1 cable-driven parallel robot with non elastic sagging cables. In ARK, 2020.
- [merlet2020-1] Merlet J-P., Papegay Y., and Gasc A-V. The Prince's tears, a large cable-driven parallel robot for an artistic exhibition. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [merlet2021] Merlet J-P. Efficient kinematics of a 2-1 and 3-1 CDPR with non-elastic sagging cables. In 5th Int. Conf. on cable-driven parallel robots (CableCon), virtual, July, 7-9, 2021.
- [merlet2021-1] Merlet J-P. Maximal cable tensions of a N-1 cable-driven parallel robot with elastic or ideal cables. In 5th Int. Conf. on cable-driven parallel robots (CableCon), virtual, July, 7-9, 2021.

- [merlet2022] Merlet J-P. and Tissot R. A panorama of methods for dealing with sagging cables in cable-driven parallel robots. In *ARK*, Bilbao, June, 26-30, 2022.
- [merlet2023] Merlet J-P. Advances in the use of neural network for solving the direct kinematics of CDPR with sagging cable. In 6th Int. Conf. on cable-driven parallel robots (Cable Con), Nantes, June, 25-28, 2023.
- [merlet2023-1] Merlet J-P. The new exhibition Blind Machines, a large 3d printing machine. In *IEEE Int. Conf. on Robotics and Automation*, London, May 29- June 2, 2023.
- [merlet2024] Merlet J-P. The inverse kinematics of cable-driven parallel robot with more than 6 sagging cables. part 1: from ideal to sagging cables. In ARK, Ljulbjana, June 30- July 4, 2024.
- [mersi2018] Mersi R. and others . Design and control of a suspended cable-driven parallel robot with four cables. In 6th RSI International Conference on Robotics and Mechatronics (IcRoM), Teheran, October, 23-25, 2018.
- [metillon2022] Métillon M. and others . Stiffness and transparency of a collaborative cable-driven parallel robot. In ARK, Bilbao, June, 26-30, 2022.
- [mianowski90] Mianowski K. and Nazarczuk K. Parallel drive of manipulator arm. In 8th RoManSy, pages 140–147, Cracovie, July, 2-6, 1990.
- [mianowski98] Mianowski K. Dextrous fully parallel manipulator with six degrees of freedom. In 12th RoManSy, pages 253–260, Paris, July, 6-9, 1998.
- [mianowski2007] Mianowski K. Singularity analysis of parallel manipulator POLMAN 3x2 with six degrees of freedom. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [michael2009] Michael N., Fink J., and Kumar V. Cooperative manipulation and transportation with aerial robots. In *Robotics: Science and Systems*, Seattle, June 2009.
- [michelin2014] Michelin M. and others . Simulation and control with XDE and Matlab/Simulink of a cable-driven parallel robot (CoGiRo). In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 71–86, Duisburg, August, 24-27, 2014.
- [mick98] Mick S. and Röschel O. Geometry & architecturally shaky platform. In ARK, pages 455–464, Strobl, June 29- July 4, 1998.
- [miermeister 2010] Miermeister P. and Pott A. Modeling and real-time dynamic simulation of the cable-driven parallel robot IPAnema. In 3rd European Conf. on Mechanism Science (Eucomes), pages 353–360, Cluj-Napoca, September, 14-17, 2010.
- [miermeister 2012] Miermeister P. and Pott A. Auto calibration method for cable-driven parallel robot using force sensors. In ARK, pages 269–276, Innsbruck, June, 25-28, 2012.
- [miermeister 2012-1] Miermeister P., Pott A., and Verl A. Auto-calibration method for overconstrained cable-driven parallel robots. In *ROBOTIK 2012*, 2012.
- [miermeister 2012-2] Miermeister P., Kraus W., and Pott A. Differential kinematics for calibration, system investigation, and force based forward kinematics of cable-driven parallel robots. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [miermeister 2014] Miermeister P. and others. An elastic cable model for cable-driven parallel robots including hysteresis effect. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 17–28, Duisburg, August, 24-27, 2014.
- [miermeister 2016] Miermeister P. and others . The CableRobot simulator large scale motion platform based on cable robot technology. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Daejeon, October, 9-14, 2016.
- [mikelsons 2008] Mikelsons L. and others . A real-time capable force calculation algorithm for redundant tendon-based parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 3869–3874, Pasadena, May, 19-23, 2008.

- [miletovic2017] Miletovic I. and others. Improved Stewart platform state estimation using inertial and actuator position measurements. Control Eng. Practice, 62:102–115, 2017.
- [milica2018] Milica L., Năstase A., , and Andrei G. A new insight into the geometric models and workspace volume of the 6RSS manipulator by disjunction of the translational and orientation subspaces. Mechanism and Machine Theory, 121:804–828, 2018.
- [milica2018-1] Milica L., Năstase A., , and Andrei G. Optimal path planning for a new type of 6RSS parallel robot based on virtual displacements expressed through Hermite polynomials. *Mechanism and Machine Theory*, 126:14–31, 2018.
- [milica2019] Milica L., Năstase A., , and Andrei G. Survey on the kinematics of a 6RSS parallel robot based on manipulability indices. *IOP Conference Series: Materials Science and Engineering*, 564(1), 2019.
- [miller92] Miller K. and Clavel R. The Lagrange-based model of Delta-4 robot dynamics. *Robotersysteme*, 8(1):49–54, 1992.
- [miller93] Miller K. The proposal of a new model of direct drive robot DELTA-4 dynamics. In *ICAR*, pages 411–416, Tokyo, November, 1-2, 1993.
- [miller95] Miller K. Experimental verification of modeling of Delta robot dynamics by direct application of Hamilton's principle. In *IEEE Int. Conf. on Robotics and Automation*, pages 532–537, Nagoya, May, 25-27, 1995.
- [miller95-1] Miller K. Model-based control of DELTA direct drive parallel robot; trajectory tracking experiments. In 26th Int. Symp. on Industrial Robots (ISIR), pages 491–496, Singapour, October, 4-6, 1995.
- [miller95-2] Miller K. On accuracy and computational efficiency of DELTA direct drive robot dynamics model. In *Int. Symp. on Microsystems, Intelligent materials and Robots*, pages 568–571, Sendai, September, 27-29, 1995.
- [miller95-3] Miller K. Modeling of dynamics and model-based control of DELTA direct-drive parallel robot. *J. of Robotics and Mechatronics*, 17(4):344–352, 1995.
- [miller2000] Miller K. Mechanics of the new UWA robot. In 13th RoManSy, pages 67–74, Zakopane, July, 3-6, 2000.
- [miller2001] Miller K. Design and applications of parallel robots. In *ISRR*, pages 161–173, Lorne, November, 9-12, 2001.
- [miller2002] Miller K. Maximization of workspace volume of 3-DOF spatial parallel manipulators. ASME J. of Mechanical Design, 124(2):347–350, June 2002.
- [miller2004] Miller K. Optimal design and modeling of spatial parallel manipulators. *Int. J. of Robotics Research*, 23(2):127–140, February 2004.
- [millies90] Millies P. Kinematics of parallel robot arms. Master's thesis, Université de Californie, Santa Barbara, March 1990. **Keywords:** mechanical architecture.
- [millman91] Millman P.A. and Colgate J.E. Design of a four d.o.f. force reflecting manipulandum with a specified force/torque workspace. In *IEEE Int. Conf. on Robotics and Automation*, pages 1488–1493, Sacramento, April, 11-14, 1991.
- [mimura95] Mimura N. and Y. Funahashi. A new analytical system applying 6 dof parallel link manipulator for evaluating motion sensation. In *IEEE Int. Conf. on Robotics and Automation*, pages 227–233, Nagoya, May, 25-27, 1995.
- [ming94] Ming A., Kajitani M., and Higuchi T. Study on wire parallel mechanism. In 2nd Japan-France Congress on Mechatronics, pages 667–670, Takamatsu, November, 1-3, 1994.
- [ming94-1] Ming A. and Higuchi T. Study on multiple degree of freedom positioning mechanisms using wires, Part 1, Concept, Design and Control. *Int. J. Japan Soc. Prec. Eng.*, 28(2):131–138, June 1994.
- [ming94-2] Ming A. and Higuchi T. Study on multiple degree of freedom positioning mechanisms using wires, Part 2, Development of a planar completely restrained positioning mechanism. *Int. J. Japan Soc. Prec. Eng.*, 28(3):235–242, September 1994.

- [minsky72] Minsky M. Manipulator design vignettes. Research Report 267, MIT AI Lab., 1972.
- [mitova91] Mitova T. and Vatkitchev A. Analysis of a closed space mechanism with three degree of mobility. In XI COBEM, Rio de Janeiro, 1991.
- [mitrouchev2008] Mitrouchev P. Formulation for actuators' number enumeration for main planar structures in robotics. European Journal of Mechanics A/Solids, 27:622–646, 2008.
- [miura84] Miura K. and Furuya H. Variable geometry truss and its application to deployable truss and space crane arms. In 35th Congress of the Int. Astronautical Federation, pages 1–9, Lausanne, October, 7-13, 1984.
- [miyasaka2015] Miyasaka M. and others. Measurement of the cable-pulley coulomb and viscous friction for a cable-driven surgical robotic system. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, September 28- October 2, 2015.
- [miyasaka2016] Miyasaka M. and others . Hysteresis model of longitudinally loaded cable for cable driven robots and identification of the parameters. In *IEEE Int. Conf. on Robotics and Automation*, Stockholm, May, 16-20, 2016.
- [miyoshi2011] Miyoshi T., Suzuki K., and Terashima K. Development of five-degree-of-freedom wire suspension power-assisted system using linear cylinders. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011
- [mkrtychev2019] Mkrtychev O.V. and Kartygin A.V. Computer simulation of kinetics of parallel mechanisms. *IOP Conference Series: Materials Science and Engineering*, 680, 2019.
- [mo2017] Mo J. and others . Dynamic performance analysis of the X4 high-speed pick-and-place parallel robot. Robotics and Computer-Integrated Manufacturing, 46:48–57, 2017.
- [mobedi2018] Mobedi I., E.and Görguülü and Can Dede M.I. Experimental evaluation of actuation and sensing capabilities of a haptic device. In *EUCOMES*, pages 137–144, Aachen, September, 4-6, 2018.
- [modak2024] Modak S. and Krishna R.K. Kinematics and singularity analysis of a novel hybrid industrial manipulator. *Robotica*, 42:579–610, 2024.
- [moghadam2015] Moghadam A.A.A; and others. Development of a novel soft parallel robot equipped with polymeric artificial muscles. *Smart Mater. Struct.*, 24(4), 2015.
- [mohamed83] Mohamed M.G., Sanger J., and Duffy J. Instantaneous kinematics of fully-parallel devices. In 6th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 77–80, New-Delhi, December, 15-20, 1983.
- [mohamed85] Mohamed M.G. and Duffy J. A direct determination of the instantaneous kinematics of fully parallel robot manipulators. *J. of Mechanisms, Transmissions and Automation in Design*, 107(2):226–229, June 1985.
- [mohanta2018"] Mohanta J.K., Singh Y., and Mohan S. Kinematic and dynamic performance investigations of asymmetric (U-shape fixed base) planar parallel manipulators. *Robotica*, 36:1111–1143, 2018.
- [molinari2000] Molinari-Tosatti L. and others . An integrated tool for parallel kinematic machine design. In 2nd Chemnitzer Parallelkinematik Seminar, pages 57–71, Chemnitz, April, 12-13, 2000.
- [molinari2001] Molinari-Tosatti L. and Fassi I. Parallel kinematic machines for an application in shoes manufacturing: from the conceptual design to the fvst experimental campaign. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Maui, Hawaii, October 29- November 3, 2001.
- [molinari2003] Molinari-Tosatti L., Fassi I., and Lagagni G. Klneto-statle optmisatlon of PKMs. *Annals of the CIRP*, 52(1):337–341, 2003.
- [monckton2002] Monckton S.P. and Chrystall K. Design and development of an automated footwear testing system. In *IEEE Int. Conf. on Robotics and Automation*, pages 3684–3689, Washington, May, 11-15, 2002.
- [monsarrat2001] Monsarrat B. and Gosselin C.M. Singularity analysis of a three-leg six-degree-of-freedom parallel platform mechanism based on Grassman line geometry. *Int. J. of Robotics Research*, 20(4):312–328, April 2001.

- [monsarrat2002] Monsarrat B. and Gosselin C.M. Jacobian matrix of general parallel and hybrid mechanisms with rigid and flexible link: a software oriented approach. In *ASME Design Engineering Technical Conference*, Montréal, September 29- October 2, 2002.
- [monsarrat2003] Monsarrat B. and Gosselin C.M. Workspace analysis and optimal design of a 3-leg 6-DOF parallel platform mechanism. *IEEE Trans. on Robotics and Automation*, 19(6):954–966, December 2003.
- [moon2002] Moon Y-M. and Kota S. Design of compliant parallel kinematic machine. In ASME 27th Biennial Mechanisms and Robotics Conf., pages 1–7, Montréal, September 29- October 2, 2002.
- [moosavian2009] Moosavian S.A.A., Pourreza A., and Alipour K. Kinematics and dynamics of a hybrid serial-parallel mobile robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 1358–1363, Kobe, May, 14-16, 2009.
- [moosavian2010] Moosavian S.A.A. and Pourreza A. Heavy object manipulation by a hybrid serial-parallel mobile robot. *Int. J. of Robotics and Automation*, 25(2):109–120, 2010.
- [moosavian2016] Moosavian A. and Xi F. Modular design of parallel robots with static redundancy. *Mechanism and Machine Theory*, 96:26–37, 2016.
- [moosavian2016-1] Moosavian A. and Xi F. Holonomic under-actuation of parallel robots with topological reconfiguration. *Mechanism and Machine Theory*, 96:290–307, 2016.
- [moradi2013-phd] Moradi A. Stiffness analysis of cable-driven parallel robot. Ph.D. Thesis, Queen's University, Kingston, April 2013. **Keywords:** wire robot, stiffness, mechanical architecture, trajectory planning, safety.
- [moreira2015] Moreilra E. and others . Cable robot for non-standard architecture and construction: A dynamic positioning system. In *IEEE International Conference on Industrial Technology (ICIT)*, 2015.
- [morgan2002] Morgan J., Miller J., and Wynn D.A. Simulation of airborne satellite communications using a platform motion emulator. In *IEE Conf. Simulation and Modelling of satellite systems*, pages 7/1–4, London, April, 23, 2002.
- [mori2002] O. Mori, Yamawaki T., and Omata T. Control of self-reconfigurable parallel robot by coupling open kinematic chains with unactuated joints. In 41st SICI Ann. Conf., pages 3002–3005, Osaka, August, 5-7, 2002.
- [morizono97] Morizono T., Kurahashi K., and Kawamura S. Realization of a virtual sports training system with parallel wire mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 3025–3030, Albuquerque, April, 21-28, 1997.
- [morizono98] Morizono T., Kurahashi K., and Kawamura S. Analysis and control of a force display system driven by parallel wire mechanism. *Robotica*, 16(5):551–563, September 1998.
- [morizono2003] Morizono T., Yamada Y., and Umetani Y. Design of a new exoskeletal mechanism for a shoulder joint of a wearable robots: the wearable HEXA mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 2323–2329, Taipei, September, 14-19, 2003.
- [morlock2015] Morlock M.B., Burkhardt M., and Seifried R. Friction compensation, gain scheduling and curvature control for a flexible parallel kinematics robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2354–2359, Hamburg, Germany, September 28- October 2, 2015.
- [morlock2021] Morlock M.B. and others . Real-time trajectory tracking control of a parallel robot with flexible links. *Mechanism and Machine Theory*, 158, 2021.
- [moroz2010] Moroz G. and others . Cusp points in the parameter space of  $R\underline{P}R 2P\underline{R}R$  parallel manipulators. In 3rd European Conf. on Mechanism Science (Eucomes), Cluj-Napoca, September, 14-17, 2010.
- [moroz2010-1] Moroz G., Rouiller F., Chablat D., and Wenger P. On the determination of cusp points of 3-RPR parallel manipulators. *Mechanism and Machine Theory*, 45(11):1555-1567, November 2010.
- [morozovsky2013] Morozovsky N. and Bewley T. Skysweeper: A low dof, dynamic high wire robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Tokyo, November, 3-7, 2013.

- [morris2001] Morris D.M. Force guided assemblies using a novel parallel manipulator. In *IEEE Int. Conf. on Robotics* and Automation, pages 325–330, Seoul, May, 23-25, 2001.
- [mostashiri2020] Mostashiri N. and others . Optimizing the torque distribution of a redundantly actuated parallel robot to study the temporomandibular reaction forces during food chewing. *J. of Mechanisms and Robotics*, 12, October 2020.
- [motahari2013] Motahari A. and others . Discrete kinematic synthesis of discretely actuated hyper-redundant manipulators. *Robotica*, 31:1073–1084, 2013.
- [motevalli2010] Motevalli B., Zohoor H., and Sohrabpour S. Structural synthesis of 5 dofs 3T2R parallel manipulators with prismatic actuators on the base. *Robotics and Autonomous Systems*, 58(3):307–321, March 2010.
- [mottola2017] Mottola G., Gosselin C., and Carricato M. Dynamically-feasible elliptical trajectories for fully constrained 3-dof cable-suspended parallel robots. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [mottola2018] Mottola G., Gosselin C., and Carricato M. Dynamically feasible periodic trajectories for generic spatial three-degree-of-freedom cable-suspended parallel robots. *J. of Mechanisms and Robotics*, 10(3), 2018.
- [mottola2019] Mottola G., Gosselin C., and Carricato M. Dynamically feasible motions of a class of purely-translational cable-suspended parallel robots. *Mechanism and Machine Theory*, 132:193 206, 2019.
- [mou2004] Mou J-I. and Chin C-T. Micro parallel kinematic mechanism design and fabrication, September, 24, 2004. WIPO Patent n° WO 2004/081991, A2. **Keywords:** planar robot,micro robot,patent.
- [mouly92] Mouly N. and Merlet J-P. Singular configurations and direct kinematics of a new parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 338–343, Nice, May, 12-14, 1992.
- [mouly93] Mouly N. Développement d'une famille de robots parallèles à motorisation électrique. Ph.D. Thesis, École des Mines de Paris, Sophia, May, 11, 1993. **Keywords:** kinematics, workspace, mechanical architecture, 6 dof robot, applications, actuators.
- [mourrain93] Mourrain B. The 40 generic positions of a parallel robot. In Bronstein M., editor, *ISSAC'93*, ACM press, pages 173–182, Kiev (Ukraine), July 1993.
- [mourrain94] Mourrain B. Enumeration problems in Geometry, Robotics and Vision. In *MEGA*, Santander, April, 5-9, 1994.
- [mousavi2014] Mousavi M.A., Masouleh M.T., and Karimi A. On the maximal singularity-free ellipse of planar 3-RPR parallel mechanisms via convex optimization. *Robotics and Computer-Integrated Manufacturing*, 30:218–227, 2014.
- [mousavi2016] Mousavi M. and others . Sensory feedback performance improvement on RoboCab: an experimental approach to wire–driven parallel manipulator. In 4th International Conference on Robotics and Mechatronics, Teheran, October, 26-28, 2016.
- [mousavi2022] Mousavi M. and others . Rapid and safe wire tension distribution scheme for redundant cable-driven parallel manipulators. Robotica, 40(7):2295-2408, July 2022.
- [mu2002] Mu Z. and Kazerounian K. A real parameter continuation method for complete solution of forward position analysis of the general Stewart platform. ASME J. of Mechanical Design, 124(2):236–244, June 2002.
- [mu2019] Mu Z. and others . Dynamic feedforward control of spatial cable-driven hyper-redundant manipulators for on-orbit servicing. *Robotica*, 37:18–38, 2019.
- [muglitz95] Muglitz J. and Kunad G. Multilink, trunklike spatial mechanisms. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 13–17, Milan, August 30- September 2, 1995.
- [mukherjee2001] Mukherjee S. and Murlidhar S. Massively parallel binary manipulators. ASME J. of Mechanical Design, 123(1):68–73, March 2001.
- [muller-k2014] Müller K., Reichert C., and Bruckmann T. Analysis of a real-time capable force computation method. In 2nd Int. Conf. on cable-driven parallel robots (Cable Con), Duisburg, August, 24-27, 2014.

- [muller-k2014-1] Müller K., Reichert C., and Bruckmann T. Analysis of geometrical force calculation algorithms for cable-driven parallel robots with a threefold redundancy. In *ARK*, Ljulbjana, June 29- July 3, 2014.
- [muller2001] Müller A. and Maisser P. Kinematic and dynamic properties of parallel manipulators. *Multibody System Dynamics*, 5:223–249, 2001.
- [muller2002] Müller A. Higher order local analysis of singularity of parallel mechanisms. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [muller2003] Müller A. Manipulability and static stability of parallel manipulators. *Multibody System Dynamics*, 9:1–23, 2003.
- [muller2005] Müller A. Internal preload control of redundantly actuated parallel manipulators. In *IEEE Int. Conf.* on Robotics and Automation, pages 960–965, Barcelona, April, 19-22, 2005.
- [muller2005-1] Müller A. Internal preload control of redundantly actuated parallel manipulators-Its application to backlash avoiding control. *IEEE Trans. on Robotics*, 21(4):668–677, August 2005.
- [muller2006] Müller A. Stiffness control of redundantly actuated parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1153–1158, Orlando, May, 16-18, 2006.
- [muller2007] Müller A. and Maisser P. Generation and application of prestress in redundantly full-actuated parallel manipulators. *Multibody System Dynamics*, 18:259–275, 2007.
- [muller2008] Müller A. Parallel manipulators, Towards new applications, chapter Redundant actuation of parallel manipulators, pages 87–108. ITECH, April 2008. **Keywords:** redundant robot,dynamics,control,state of the art.
- [muller2009] Müller A. Effects of geometric imperfections to the control of redundantly actuated parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1782–1787, Kobe, May, 14-16, 2009.
- [muller2010] Müller A. Consequences of geometric imperfections for the control of redundantly actuated parallel manipulators. *IEEE Trans. on Robotics*, 26(1), February 2010.
- [muller2011] Müller A. and Hufnagel T. A projection method for the elimination of contradicting control forces in redundantly actuated PKM. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [muller2012] Müller A. and Ruggiu M. Self calibration of redundantly actuated PKM based on motion reversal point. In ARK, pages 75–82, Innsbruck, June, 25-28, 2012.
- [muller2012-1] Müller A. and Hufnagel T. Model-based control of redundantly actuated parallel manipulators in redundant coordinates. *Robotics and Autonomous Systems*, 60:563–571, 2012.
- [muller2013] Müller A. On the terminology and geometric aspects of redundant parallel manipulators. *Robotica*, 31(1):137–147, January 2013.
- [muller2018] Müller A. Kinematic topology and constraints of multi-loop linkages. Robotica, 36:1641–1663, 2018.
- [muller2022] Müller A. A constraint embedding approach for dynamics modeling of parallel kinematic manipulators with hybrid limbs. *Robotics and Autonomous Systems*, 155, 2022.
- [muralidharan2018] Muralidharan V. and others . A comparative study of the configuration-space and actuator-space formulations of the lagrangian dynamics of parallel manipulators and the effects of kinematic singularities on these. *Mechanism and Machine Theory*, 130:401–434, 2018.
- [muralidharan 2020] Muralidharan V. and others. Methods for dimensional design of parallel manipulators for optimal dynamic performance over a given safe working zone. *Mechanism and Machine Theory*, 147, 2020.
- [muralidharan 2022] Muralidharan V., Wenger P., and Chevallereau C. Kinematic and static analysis of a cable-driven 2-X tensegrity manipulator for two actuation strategies. In *ARK*, Bilbao, June, 26-30, 2022.
- [murareci97-phd] Murareci D. Contribution à la modélisation géométrique et à l'étalonnage des robots séries et parallèles. Ph.D. Thesis, Ecole Centrale, Nantes, March, 7, 1997. **Keywords:** calibration.

- [murphy2007] Murphy W.S. Determination of a position using approximate distances and trilateration. Master's thesis, Colorado School of Mines, Golden, July 2007. **Keywords:** forward kinematics.
- [murray-m2006] Murray M., Hovland G., and Brogardh T. Collision-free workspace design of the 5-axis Gantry-Tau parallel kinematic machine. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Beijing, October, 9-15, 2006.
- [murray96] Murray A.P., Pierrot F., Dauchez P., and McCarthy J.M. On the design of parallel manipulators for a prescribed workspace: a planar quaternion approach. In *ARK*, pages 349–357, Portoroz-Bernadin, June, 22-26, 1996.
- [murray97] Murray A.P., Pierrot F., Dauchez P., and McCarthy J.M. A planar quaternion approach to the kinematic synthesis of a parallel manipulator. *Robotica*, 15(4):361–365, July August , 1997.
- [murray98] Murray A.P. and Pierrot F. N-position synthesis of parallel planar RPR platforms. In *ARK*, pages 69–78, Strobl, June 29- July 4, 1998.
- [murray99] Murray A.P. and McCarthy J.M. Burmester lines of spatial five position synthesis from the analysis of a 3-CPC platform. ASME J. of Mechanical Design, 121(1):45–49, March 1999.
- [murthy90-phd] Murthy V.S. Kinematics of serial manipulators and their parallel duals. Ph.D. Thesis, Ohio State University, 1990. **Keywords:** duality.
- [murthy92] Murthy V. and Waldron K.J. Position kinematics of the generalized lobster arm and its series-parallel dual. ASME J. of Mechanical Design, 114(3):406–413, September 1992.
- [mustafa2005] Mustafa S. K. and others . A biologically-inspired anthropocentric shoulder joint rehabilitator: Workspace analysis & optimization. In *International Conference on Mechatronics & Automation*, Niagara Falls, 2005.
- [mustafa2007] Mustafa S. K. and others . Self-identification of the joint centre of a cable-driven shoulder rehabilitator. In *IEEE Int. Conf. on Robotics and Automation*, Roma, April, 10-14, 2007.
- [mustafa2008] Mustafa S. K. and others . Kinematic calibration of a 7-dof self-calibrated modular cable-driven robotic arm. In *IEEE Int. Conf. on Robotics and Automation*, pages 1288–1293, Pasadena, May, 19-23, 2008.
- [nabat2005] Nabat V. and others . Par4: very high speed parallel robot for pick-and-place. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Edmonton, August, 2-6, 2005.
- [nabavi2020] Nabavi S.N. and others . Parametric design and multi-objective optimization of a general 6-PUS parallel manipulator. *Mechanism and Machine Theory*, 152, 2020.
- [nabipour 2016] Nabipour M.S. and others . Visual servoing in a cable robot using Microsoft Kinect v2 sensor. In 4th International Conference on Robotics and Mechatronics, Teheran, October, 26-28, 2016.
- [naccarato2003] Naccarato F. and Hughes P. Inverse kinematics of variable-geometry-truss manipulators, 2003. Communication personelle. **Keywords:** truss.
- [nag2017] Nag A., Mohan S., and Bandyopadhyay S. Forward kinematic analysis of the  $3-\underline{RP}RS$  parallel manipulator. Mechanism and Machine Theory, 116:262–273, 2017.
- [nag2018] Nag A. and Bandyopadhyay S. Analytical determination of a sphere inside the which the Stewart platform translates without suffering any leg interference. In *ARK*, pages 74–82, Bologna, July, 1-5, 2018.
- [nag2021] Nag A. and Bandyopadhyay S. Singularity-free spheres in the position and orientation workspaces of Stewart platform manipulators. *Mechanism and Machine Theory*, 155, 2021.
- [nag2021-1] Nag A., V S., and Bandyopadhyay S. A uniform geometric-algebraic framework for the forward kinematic analysis of 6-6 Stewart platform manipulators of various architectures and other related 6-6 spatial manipulators. *Mechanism and Machine Theory*, 155, 2021.
- [nagai2003] Nagai K. and others . Development of parallel manipulator "ninja" with ultra-high-acceleration. In *IEEE Int. Conf. on Robotics and Automation*, pages 3678–3685, Taipei, September, 14-19, 2003.

- [nagai2008] Nagai K. and Liu Z. A systematic approach to stiffness analysis of parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 1543–1548, Pasadena, May, 19-23, 2008.
- [nagai2009] Nagai K. and Liu Z. Re-design of force redundant parallel mechanisms by introducing kinematical redundancy. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, St Louis, October, 11-15, 2009.
- [nagua2018] Nagua L. and others . Design and performance validation of a cable-driven soft robotic neck. In *Spanish Robotics Conference*, June, 14-15, 2018.
- [nahavandi2008] Nahavandi S. and others . Heavy tools manipulation by low powered direct-drive five-bar parallel robot. *Mechanism and Machine Theory*, 43(11):1450–1461, November 2008.
- [nahon91] Nahon M. and Angeles J. Real-time force optimization in parallel kinematics chains under inequality constraints. In *IEEE Int. Conf. on Robotics and Automation*, pages 2198–2203, Sacramento, April, 11-14, 1991.
- [nahvi94] Nahvi A., Hollerbach J.M., and Hayward V. Calibration of a parallel robot using multiple kinematics closed loops. In *IEEE Int. Conf. on Robotics and Automation*, pages 407–412, San Diego, May, 8-13, 1994.
- [nahvi96] Nahvi A. and Hollerbach J.M. The noise amplification index for optimal pose selection in robot calibration. In *IEEE Int. Conf. on Robotics and Automation*, pages 647–654, Minneapolis, April, 24-26, 1996.
- [nair92] Nair P. On the kinematics geometry of parallel robot manipulators. Master's thesis, Université du Maryland, College Park, 1992. **Keywords:** forward kinematics.
- [nair94] Nair P. On the forward kinematics of parallel manipulators. *Int. J. of Robotics Research*, 13(2):171–188, April 1994.
- [najafi2016] Najafi F. and Bakhshizadeh M. Development a fuzzy pid controller for a parallel cable robot with flexible cables. In 4th International Conference on Robotics and Mechatronics, Teheran, October, 26-28, 2016.
- [nakamura89] Nakamura Y. and Ghodoussi M. Dynamics computation of closed-link robot mechanisms with nonredundant and redundant actuators. *IEEE Trans. on Robotics and Automation*, 5(3):294–302, June 1989.
- [nakamura91] Nakamura Y., Kimura Y., and Arora G. Optimal use of non-linear electromagnetic force for micro motion wrist. In *IEEE Int. Conf. on Robotics and Automation*, pages 1040–1045, Sacramento, April, 11-14, 1991.
- [nakano2009] Nakano T. and others. A parallel robot to assist vitreoretinal surgery. Int. J. of Computer Assisted Radiology and Surgery, 4(6), November 2009.
- [nakashima92] Nakashima K. and others . Development of the parallel manipulator. In *IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems*, pages 419–424, Kobe, September, 16-20, 1992.
- [nakashima94] Nakashima K. A six-axis motion base and a study of a parallel manipulator. Advanced Robotics, 8(6):609, December 1994.
- [nanua89] Nanua P. and Waldron K.J. Direct kinematic solution of a Stewart platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 431–437, Scottsdale, May, 14-19, 1989.
- [nanua90] Nanua P. and Waldron K.J. Direct kinematic solution of a special parallel robot structure. In 8th RoManSy, pages 134–142, Cracow, July, 2-5, 1990.
- [nanua91] Nanua P. and Waldron K.J. Direct kinematic solution of a Stewart platform. *IEEE Trans. on Robotics and Automation*, 6(4):438–444, August 1991.
- [narayanan2017] Narayanan T. and others. A cable driven parallel robot for coconut farm. In Int. Conf. on Advances in Computing, Communications and Informatics (ICACCI), 2017.
- [nastase2007] Nastase A. The class of hybrid parallel mechanisms 3(JRS). In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [natal2012] Natal G.S., Chemori A., and Pierrot F. Dual space adaptive control of redudantly actuated parallel manipulators for extremely fast operations with changes. In *IEEE Int. Conf. on Robotics and Automation*, pages 253–259, Saint Paul, May, 14-18, 2012.

- [natal2016] Natal G.S., Chemori A., and Pierrot F. Nonlinear control of parallel manipulators for very high accelerations without velocity measurement: stability analysis and experiments on par2 parallel manipulator. *Robotica*, 34(1):43–70, January 2016.
- [navarro2010] Navarro J.S and others. Kinematics of a robotic 3UPS1S spherical wrist designed for laparoscopic applications. Int. J. of Computer Assisted Radiology and Surgery, 6, 2010.
- [nawratil2010] Nawratil G. Main theorem on Schönfliess-singular planar Stewart Gough platforms. In ARK, pages 107–116, Piran, June 28- July 1, 2010.
- [nawratil2010-1] Nawratil G. Special cases of Schönflies-singular planar Stewart Gough platforms. In 3rd European Conf. on Mechanism Science (Eucomes), Cluj-Napoca, September, 14-17, 2010.
- [nawratil2006] Nawratil G. The control number as index for Stewart-Gough platforms. In ARK, pages 15–22, Ljubljana, June, 26-29, 2006.
- [nawratil2009] Nawratil G. A new approach to the classification of architecturally singular parallel manipulators. In *Computational Kinematics*, Duisburg, May, 6-8, 2009.
- [nawratil2009-1] Nawratil G. New performance indices for 6-dof UPS and 3-dof RPR parallel manipulators. *Mechanism and Machine Theory*, 44(1):208–221, January 2009.
- [nawratil2009-2] Nawratil G. All planar parallel manipulators with cylindrical singularity surface. *Mechanism and Machine Theory*, 44(12):2179–2186, December 2009.
- [nawratil2012] Nawratil G. Self-motions of planar projective Stewart Gough platforms. In ARK, pages 27–34, Innsbruck, June, 25-28, 2012.
- [nawratil2014] Nawratil G. Correcting Duporcq's theorem. Mechanism and Machine Theory, 73(12):282–295, March 2014
- [nawratil2017] Nawratil G. and Schicho J. Self-motions of pentapods with linear platform. Robotica, 35:832–860, 2017.
- [nayak2018] Nayak A., Caro S., and Wenger P. Comparison of 3-[PP]S parallel manipulators based on their singularity free orientation workspace, parasitic motions and complexity. *Mechanism and Machine Theory*, 129, 2018.
- [nayak2018-1] Nayak A. and others . Operation mode analysis of 3-RPS parallel manipulators based on their design parameters. *Computer Aided Geometric Design*, 63, 2018.
- [nayak2018-2] Nayak A., Caro S., and Wenger P. Comparison of 3-[PP]S parallel manipulators based on their singularity free orientation workspace, parasitic motions and complexity. *Mechanism and Machine Theory*, 129:293–315, 2018.
- [nayak2019] Nayak A., Caro S., and Wenger P. Kinematic analysis of the 3-RPS-3-SPR series-parallel manipulator. *Robotica*, 37(7), 2019.
- [nedic2014] Nedic N. and others . Optimal cascade hydraulic control for a parallel robot platform by PSO. *The International Journal of Advanced Manufacturing Technology*, 72:1085–1098, 2014.
- [nedic2015] Nedic N. and others . Optimal control of hydraulically driven parallel robot platform based on firefly algorithm. *Nonlinear Dynamics*, 82:1457–1473, 2015.
- [nelson2017] Nelson C.A. On improving stiffness of cable robots. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [nenchev96] Nenchev D.N. and Uchiyama M. Singularity-consistent path planning and control of parallel robot motion through instantaneous-self-motion type. In *IEEE Int. Conf. on Robotics and Automation*, pages 1864–1870, Minneapolis, April, 24-26, 1996.
- [nenchev97] Nenchev D.N., Bhattacharya S., and Uchiyama M. Dynamic analysis of parallel manipulator under the singularity-consistent parameterization. *Robotica*, 15(4):375–384, July August , 1997.
- [nenchev98] Nenchev D.N. and Uchiyama M. Para-arm: a five-bar parallel manipulator with singularity-perturbed design. *Mechanism and Machine Theory*, 33(5):453–462, July 1998.

- [neugebauer 97] Neugebauer R. and others . Hexapod werkzeug-machine für die hochgeschwindigkeit bearbeitung. ZWF, 92(9):447–449, 1997.
- [neugebauer98] Neugebauer R. and others. Experiences with a hexapod-based machine-tool. In *First European-American Forum on Parallel Kinematic Machines*, pages 313–326, Milan, August 31- September 1, 1998.
- [neugebauer2002] Neugebauer R. and others . Parallel kinematic structures in manufacturing. In 3rd Chemnitzer Parallelkinematik Seminar, pages 17–47, Chemnitz, April, 23-25, 2002.
- [neugebauer2002-1] Neugebauer R. and others . Hybrid struts with smart piezo actuators for high dynamic parallel kinematics. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 131–140, Braunschweig, May, 29-30, 2002.
- [neugebauer 2002-2] Neugebauer R. and others . Intelligent strut. In 3rd Chemnitzer Parallelkinematik Seminar, pages 277–284, Chemnitz, April, 23-25, 2002.
- [neugebauer2002-3] Neugebauer R. and Weidermann F. Structure optimization of machine tools with parallel kinematics. In 3rd Chemnitzer Parallelkinematik Seminar, pages 105–118, Chemnitz, April, 23-25, 2002.
- [neugebauer2002-4] Neugebauer R. and others. Improvement of the calibration accuracy by a new measurement process. In 3rd Chemnitzer Parallelkinematik Seminar, pages 443–453, Chemnitz, April, 23-25, 2002.
- [neugebauer 2002-5] Neugebauer R. and others. Application of the parallel kinematic machine principle in a new hydraulic powered, flexible bending machine for tubes and profiles. In 3rd Chemnitzer Parallelkinematik Seminar, pages 629–638, Chemnitz, April, 23-25, 2002.
- [neugebauer 2002-6] Neugebauer R. and others. Interaction between machine-tool and process: modelling, simulation of miling operations on hexapod 6X Hexa. In 2nd NCG Application Conf. on Parallel Kinematics Machine, pages 833–841, Chemnitz, April, 23-25, 2002.
- [neugebauer 2005] Neugebauer R. and others. Parallel kinematics as a potential for boosting efficiency for handling equipement in forming machines. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 269–284, Braunschweig, May, 10-11, 2005.
- [neugebauer 2006] Neugebauer R. and others . A virtual reality-based engineering tool for fast configuration of machine-tool with parallel kinematic-vrax. In 5th Chemnitzer Parallelkinematik Seminar, pages 39–62, Chemnitz, April, 25-26, 2006.
- [neugebauer2006-1] Neugebauer R. and others . The 3rd generation of an actuator-sensor unit for tripod structures. In 5th Chemnitzer Parallelkinematik Seminar, pages 325–340, Chemnitz, April, 25-26, 2006.
- [neugebauer2006-2] Neugebauer R. and others . Method for the optimization of kinematic and dynamic properties of parallel kinematic machines. *Annals of the CIRP*, 55(1):403–406, 2006.
- [neumann-r2005] Neumann R. and others . Parallel robots with pneumatic drives. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 171–184, Braunschweig, May, 10-11, 2005.
- [neumann88] Neumann K.E. Robot, March, 22, 1988. United States Patent n° 4,732,525, Neos Product HB Norrtalje Suède. **Keywords:** mechanical architecture,4 dof robot,3 dof robot,patent.
- [neville96] Neville A.B. and Sanderson A.C. Tetrobot family tree: modular synthesis of kinematic structures for parallel robotics. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 382–388, Osaka, November, 5-8, 1996.
- [newman2017] Newman M., Zygielbaum A., and Terry B. Static analysis and dimensional optimization of a cable-driven parallel robot. In 3rd Int. Conf. on cable-driven parallel robots (Cable Con), Québec, 2017.
- [nguyen-av2015] Nguyen A.V. and others . Static and dynamic characterization of the 6-dofs parallel robot  $3\underline{C}$ RS. Mechanism and Machine Theory, 93:65–82, November 2015.
- [nguyen-dq2013] Nguyen D.Q. and others . On the simplification of cable model in static analysis of large dimension cable-driven parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 928–934, Tokyo, November, 3-7, 2013.

- [nguyen-dq2014] Nguyen D.Q. and others . On the analysis of large-dimension reconfigurable suspended cable-driven parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 5728–5735, Hong-Kong, 7 November 31- June , 2014.
- [nguyen-dq2014-1] Nguyen D.Q. and Gouttefarde M. On the improvement of cable collision detection algorithm. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 29–40, Duisburg, August, 24-27, 2014.
- [nguyen-dq2014-2] Nguyen D.Q. and Gouttefarde M. Study of reconfigurable suspended cable-driven parallel robots for airplane maintenance. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Chicago, September, 14-18, 2014.
- [nguyen-dq2014-3] Nguyen D.Q. and Gouttefarde M. Stiffness matrix of 6-dof cable-driven parallel robots and its homogenization. In ARK, Ljulbjana, June 29- July 3, 2014.
- [nguyen-tt2012] Nguyen T.T and others . Identification du modèle phénoménologique d'un robot parallèle aâ câbles. Journal européen des systèmes automatisés, 6-7, 2012.
- [nguyen-vl2020] Nguyen V.L., Lin C-Y., and Kuo C-H. Gravity compensation design of Delta parallel robots using gear-spring modules. *Mechanism and Machine Theory*, 154, 2020.
- [nguyen88] Nguyen C.C. and Pooran F.J. Closed-kinematic chain robot manipulator. Research Report CR-183031, NASA, July 1988.
- [nguyen89] Nguyen C.C. and Pooran F.J. Dynamic analysis of a 6 d.o.f. CKCM robot end-effector for dual-arm telerobot systems. *Robotics and Autonomous Systems*, 5(4):377–394, 1989.
- [nguyen89-1] Nguyen C.C. and Pooran F.J. Kinematic analysis and workspace of a 6 d.o.f. CKCM robot end-effector. Journal of Mechanical Working Technology, 20:283–294, 1989.
- [nguyen91] Nguyen C.C. and others . Experimental study of motion control and trajectory planning for a Stewart platform robot manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 1873–1878, Sacramento, April, 11-14, 1991.
- [nguyen91-1] Nguyen C.C. and others . Efficient computation of forward kinematics and jacobian matrix of a Stewart platform-based manipulator. In *IEEE Proc. of the Southeast Conf'91*, pages 869–874, Williamsburg, April, 7-10, 1991.
- [nguyen91-2] Nguyen C.C., Antrazi S.S., and Zhou Z-L. Analysis and implementation of a Stewart platform-based force sensor for passive compliant robotic assembly. In *IEEE Proc. of the Southeast Conf'91*, pages 880–884, Williamsburg, April, 7-10, 1991.
- [nguyen91-3] Nguyen C.C. and others . Analysis and implementation of a 6 d.o.f Stewart platform-based robotic wrist. Computers Elec. Eng., 17(3):191–203, 1991.
- [nguyen92] Nguyen C.C. and others . Trajectory planning and control of a Stewart platform-based end-effector with passive compliance for part assembly. *J. of Intelligent and Robotic Systems*, 6(2-3):263–281, December 1992.
- [nguyen92-1] Nguyen C.C. and others . Analysis and experimentation of a Stewart platform-based force/torque sensor. *Int. J. of Robotics and Automation*, 7(3):133–141, 1992.
- [nguyen93] Nguyen C.C. and others . Adaptive control of a Stewart platform-based manipulator. J. of Robotic Systems, 10(5):657-687, July 1993.
- [niaritsiry2003] Niaritsiry F-T., Fazenda N., and Clavel R. Simulation analysis of the source of inaccuracy of a parallel manipulator. In *IEEE Int. Conf. on Robotics, Intelligent Systems and Signal Processing*, pages 266–271, Changsha, China, October, 8-13, 2003.
- [niaritsiry2004] Niaritsiry F-T., Fazenda N., and Clavel R. Study of the source of inaccuracy of a 3 dof flexure hinge-based parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 4091–4096, New Orleans, April, 28-30, 2004.
- [nielsen96] Nielsen J. and Roth B. The direct kinematics of the general 6-5 Stewart-Gough mechanism. In ARK, pages 7–16, Portoroz-Bernadin, June, 22-26, 1996.

- [nierenberger 2014] Nierenberger M. and others . Multiaxial testing of materials using a Stewart platform: case study of the Nooru-Mohamed test. *Experimental Techniques*, 38:74–83, 2014.
- [nishiwaki2002] Nishiwaki K. and others. A six axis force sensor with parallel support mechanism to measure the ground reaction force of huamnoid robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 2277–2282, Washington, May, 11-15, 2002.
- [niyetkaliyev2014] Niyetkaliyev A. and Shintemirov A. An approach for obtaining unique kinematic solutions of a spherical parallel manipulator. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 1355–1360, Besancon, July, 8-11, 2014.
- [nokleby2005] Nokleby S.B. and others. Force capabilities of redundantly-actuated parallel manipulators. *Mechanism and Machine Theory*, 40(5):578–599, May 2005.
- [nokleby 2007] Nokleby S.B. and others . Force-moment capabilities of redundantly-actuated planar-parallel architectures. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [nombrail93-phd] Nombrail N. Analyse et commande d'une famille de robots manipulateurs a structure parallèle et redondante. Ph.D. Thesis, École Nationale Supérieure de l'Aéronautique et de l'Espace, Toulouse, December, 2, 1993. **Keywords:** redundant robot.
- [notash96] Notash L. and Podhorodeski R.P. Forward displacement analysis of uncertainty configurations of parallel manipulators with a redundant branch. *J. of Robotic Systems*, 13(9):587–601, September 1996.
- [notash98] Notash L. Uncertainty configurations of parallel manipulators. Mechanism and Machine Theory, 33(1/2):123-138, January 1998.
- [notash2000] Notash L. Joint sensor fault detection for fault tolerant parallel manipulators. J. of Robotic Systems, 17(3):149–157, 2000.
- [notash2003] Notash L. and Huang L. On the design of fault tolerant parallel manipulators. *Mechanism and Machine Theory*, 38(1):85–101, January 2003.
- [notash2007] Notash L. and Kamalzadeh A. Inverse dynamics of wire-actuated parallel manipulators with constraining linkages. *Mechanism and Machine Theory*, 42(9):1103–1118, September 2007.
- [notash2011] Notash L. A methodology for actuator failure recovery in parallel manipulators. *Mechanism and Machine Theory*, 46(4):454–465, April 2011.
- [notash2012] Notash L. On the twist recovery methodologies after failure. In ARK, pages 11–18, Innsbruck, June, 25–28, 2012.
- [notash2012-1] Notash L. Failure recovery for wrench capability of wire-actuated parallel manipulators. *Robotica*, 30(6):941–950, September 2012.
- [notash2014] Notash L. Impact of perturbation on wire tension vector. In ARK, pages 41–49, Ljulbjana, June 29–July 3, 2014.
- [notash2017] Notash L. Manipulator deflection for optimum tension of cable-driven robots with parameter variations. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [novin2016] Novin R.S. and others . Optimal motion planning for parallel robots via convex optimization and receding horizon. Advanced Robotics, 30(17-18):1145-1163, 2016.
- [novin2018] Novin R.S., Masouleh M.T., and Yazdani M. A new neural gas network approach for obtaining the singularity-free workspace of 3-dof planar parallel manipulators. *Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science*, 232(1), 2018.
- [nuelle2020] Nuelle K. and others . Modeling, calibration, and evaluation of a tendon-actuated planar parallel continuum robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October, 25-29, 2020.

- [nurahmi2014] Nurahmi L. and others . Motion capability of the 3-RPS cube parallel manipulator. In ARK, Ljulbjana, June 29- July 3, 2014.
- [nurahmi2015] Nurahmi L. and others. Kinematic analysis of the 3-RPS Cube parallel manipulator. J. of Mechanisms and Robotics, 7(1), 2015.
- [nurahmi2016] Nurahmi L. and others . Reconfiguration analysis of a 4-RUU parallel manipulator. *Mechanism and Machine Theory*, 96:269–289, February 2016.
- [nurahmi2017] Nurahmi L. and others . Dimension synthesis of suspended eight cables-driven parallel robot for search-and-rescue operation. In *Int.Conf on Advanced Mechatronics*, *Intelligent Manufacture*, and *Industrial Automation (ICAMIMIA)*, 2017.
- [nurahmi2019] Nurahmi L., Caro S., and Solichin M. A novel ankle rehabilitation device based on a reconfigurable 3-RPS parallel manipulator. *Mechanism and Machine Theory*, 134:135–150, 2019.
- [nzue2010] Nzue R-M.A. and others. Comparative analysis of the repeatability performance of a serial and parallel robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Taipei, October, 18-22, 2010.
- [obrien2001] O'Brien J.F. and Wen J.T. On kinematic instability of parallel robots. In F.C. Park C.C. Iurascu, editor, Computational Kinematics, pages 279–290. EJCK, May, 20-22, 2001. **Keywords:** singularity.
- [obrien2001-1] O'Brien J.F. and Wen J.T. Kinematic control of parallel robots in the presence of unstable singularities. In *IEEE Int. Conf. on Robotics and Automation*, pages 3154–3159, Seoul, May, 23-25, 2001.
- [obrien2005] O'Brien J.F., Jafari F., and Wen J.T. Self-motion in spatial parallel mechanisms with more than three legs. In *IEEE Int. Conf. on Robotics and Automation*, pages 966–971, Barcelona, April, 19-22, 2005.
- [oen2007] Oen K-T. and Wang L-C T. Optimal dynamic trajectory planning for linearly actuated platform type parallel manipulators having task space redundant degree of freedom. *Mechanism and Machine Theory*, 42(7):727–750, June 2007.
- [oetomo2008] Oetomo D., Daney D., Shirinzadeh B., and Merlet J-P. Certified workspace analysis of 3RRR planar parallel flexure mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 3838–3843, Pasadena, May, 19-23, 2008.
- [oetomo2009] Oetomo D., Daney D., Shirinzadeh B., and Merlet J-P. An interval-based method for workspace analysis of planar flexure-jointed mechanism. ASME J. of Mechanical Design, 131(1), January 2009.
- [oftadeh2010] Oftadeh R., Aref M.M., and Taghirad H.D. Forward kinematic analysis of a planar cable driven redundant parallel manipulator using force sensors. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2295–2300, Taipei, October, 18-22, 2010.
- [ogawa2006] Ogawa H. and Simojo M. Development of 2-dof haptic device driven directly by shaft motors. *J. of Robotics and Mechatronics*, 18(4):392–399, August 2006.
- [oh2003] Oh S-R. and Agrawal S.K. Cable-suspended planar parallel robots with redundant cables: controller with positive cable tensions. In *IEEE Int. Conf. on Robotics and Automation*, pages 3023–3028, Taipei, September, 14-19, 2003.
- [oh2004] Oh S-R. and others . Dynamic modeling and robust controller design of a two-stage parallel cable robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 3678–3683, New Orleans, April, 28-30, 2004.
- [oh2005] Oh S-R. and others. A dual stage planar cable robot: dynamic modeling and design of a robust controller with positive inputs. ASME J. of Mechanical Design, 127(4):612–620, July 2005.
- [oh2005-1] Oh S-R. and others . Dynamic modeling and robust controller design of a two-stage parallel cable robot. Multibody System Dynamics, 13:385–399, 2005.
- [oh2006] Oh S-R. and Agrawal S.K. Generation of feasible set points and control of a cable robot. *IEEE Trans. on Robotics and Automation*, 22(3):551–558, July 2006.

- [oh2006-1] Oh S-R. and Agrawal S.K. The feasible workspace analysis of a set point control for a cable-suspended robot with input constraints and disturbances. *IEEE Trans. on Control Systems Technology*, 14(4):751–742, July 2006.
- [oh2007] Oh S-R. and Agrawal S.K. A control Lyapunov approach for feedback control of cable-suspended robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 4544–4549, Roma, April, 10-14, 2007.
- [oh2007-1] Oh S-R. and Agrawal S.K. A control lyapunov approach for feedback control of cable-suspended robots. In *IEEE Int. Conf. on Robotics and Automation*, Roma, April, 10-14, 2007.
- [oiwa2000] Oiwa T. and Tamaki M. Study on Abbe's principle in parallel kinematics. In 2nd Chemnitzer Parallelkine-matik Seminar, pages 345–353, Chemnitz, April, 12-13, 2000.
- [oiwa2005] Oiwa T. Error compensation system for joints, links and machine frame of parallel kinematics machines. *Int. J. of Robotics Research*, 24(12):1087–1102, December 2005.
- [oiwa2007] Oiwa T. Ultra-precision machine tool or coordinate measuring machine using hexapod-type measurement device for six degree-of-freedom relative motions between cutting tool/probe and workpiece. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [ojala94] Ojala P., Arai T., Tanikawa T., and Koivo H. Motion optimization and control of the 7 d.o.f micro manipulator. In *Scandinavian Symposium on Robotics*, pages 132–136, October, 4-6, 1994.
- [ojala94-1] Ojala P., Arai T., and Tanikawa T. Kinematic analysis and motion control of a redundant micro manipulator. In 2nd Japan-France Congress on Mechatronics, pages 473–476, Takamatsu, November, 1-3, 1994.
- [olarra2017] Olarra A. and others . Machine with the WalkingHex: a walking parallel kinematic machine-tool for in situ operation. *Annals of the CIRP*, 66:361–364, 2017.
- [olds2015] Olds K.C. Global indices for kinematic and force transmission performance in parallel robots. *IEEE Trans. on Robotics*, 31(2):494–500, April 2015.
- [olea2000] Olea G., Plitea N., and Takamusa K. Kinematical analysis and simulation of a new parallel mechanism for robotics application. In ARK, pages 403–410, Piran, June, 25-29, 2000.
- [olea2003] Olea G., Takamasu K., and Hirose K. Development of parallel positioning systems for precise micro/mini applications. In *Int. Precision Assembly Seminar IPAS'2003*, pages 95–101, Bad Hofgastein, March, 17-19, 2003.
- [oliviers95] Oliviers M.P. and Mayer J.R.R. Global kinematic calibration of a Stewart platform. ASME DSC, 57(1):129-136, 1995.
- [orin81] Orin D.E. and Oh S.Y. Control of force distribution in robotic mechanisms containing closed kinematic chains. ASME J. of Dynamic Systems, Measurement and Control, 102(2):134–141, June 1981.
- [orozcomuniz2017] Orozco-Muniz J.J., J.D. aned Cervantes-Sanchez and Rico-Martínez J.M. Dexterity indices for planar parallel manipulators. *Robotics and Computer-Integrated Manufacturing*, 46:144–155, 2017.
- [orsino2015] Orsino R.M.M. and others . Analytical mechanical approaches in the dynamic modelling of Delta mechanism. *Robotica*, 33(4):953–973, May 2015.
- [osumi2000] Osumi H. and others . Development of a manipulator suspended to parallel wire structure. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Takamatsu, Japan, October 30- November 5, 2000.
- [ota98] Ota Y. and others . Reseairch on a six-legged walking robot with parallel mechanism. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Victoria, October 1998.
- [otis2009] Otis M.J.D. and others . Interference estimated time of arrival on a 6-dof cable-driven haptic foot platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 1067–1072, Kobe, May, 14-16, 2009.
- [otis2009-1] Otis M.J.D. and others . Cable tension control and analysis of reel transparancy for 6-dof haptic foot platform on a cable-driven locomotion interface. J. of Electrical, Computer & Systems Eng, pages 16–29, 2009.

- [otis2009-2] Otis M.J.D. and others. Determination and management of cable interferences between two 6-dof foot platforms in a cable-driven locomotion interface. *IEEE Trans. on Systems, Man, and Cybernetics Part A:* systems and Humans, 39(3), May 2009.
- [otis2010] Otis M.J.D. and others. Human safety algorithms for a parallel cable-driven haptic interface. In *Brain*, *Body and Machine*, pages 187–200, 2010.
- [ottaviano2001] Ottaviano E. and Ceccarelli M. Optimal design of CAPAMAN (Cassino parallel manipulator) with prescribed workspace. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 35–44. EJCK, May, 20-22, 2001. **Keywords:** design, optimal design, workspace.
- [ottaviano2001-1] Ottaviano E. *Progettazione ottimizzata di manipulatori paralleli*. Ph.D. Thesis, University of Cassino, Cassino, November 2001. **Keywords:** 3 dof robot, optimal design, mechanical architecture.
- [ottaviano2001-2] Ottaviano E., Gosselin C.M., and Ceccarelli M. Singularity analysis of CaPaMan: a three-degree of freedom spatial parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 1295–1300, Seoul, May, 23-25, 2001.
- [ottaviano2002] Ottaviano E. and Ceccarelli M. Optimal design of CAPAMAN (Cassino parallel manipulator) with a specific orientation workspace. *Robotica*, 20(2):159–166, March 2002.
- [ottaviano2002-1] Ottaviano E. and others . CaTraSys (Cassino Traking System): A wire system for experimental evaluation of robot workspace. *Robotics and Mechatronics*, 14(1):78–87, 2002.
- [ottaviano2003] Ottaviano E., Ceccarelli M., and Thomas F. Singularity configurations of a 6-wire parallel architecture. In RAAD, Cassino, May, 7-10, 2003.
- [ottaviano2003-1] Ottaviano E. and Carbone G. A procedure for the multi objective design of parallel manipulators. In RAAD, Cassino, May, 7-10, 2003.
- [ottaviano2005] Ottaviano E. and others . Analysis, design and construction of a discretely-actuated multi-module parallel manipulator. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [ottaviano2005-1] Ottaviano E. and others . A low-cost easy operation 4-cables driven parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 4019–4024, Barcelona, April, 19-22, 2005.
- [ottaviano2007] Ottaviano E., Ceccarelli M., and Palmucci F. Experimental identification of kinematic parameters and joint mobility of human limbs. In 2nd Int. Congress, Design and Modelling of mechanical systems, Monastir, March, 19-21, 2007.
- [ottaviano2007-1] Ottaviano E. and Ceccarelli M. Numerical and experimental characterization of singularity of a six-wire parallel architecture. *Robotica*, 25(3):315–324, May 2007.
- [ottaviano2007-2] Ottaviano E. A system for tension monitoring in cable-based parallel architectures. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [ottaviano2007-3] Ottaviano E., Ceccarelli M., and De Ciantis M. A 4-4 cable-based parallel manipulator for an application in hospital environment. In 15th Mediterranean Conf. on Control and Automation, Athens, July, 27-29, 2007.
- [ottaviano2008] Ottaviano E. Design issues and application of cable-based parallel manipulators for rehabilitation therapy. *Applied Bionics and Biomechanics*, 5(2):65–75, June 2008.
- [ottiviano2009] Ottaviano E., Ceccarelli M., and Grande S. An experimental evaluation of human walking. In 3eme Congrès International Conception et Modélisation des Systèmes Mécaniques CMSM, Hammamet, March, 16-18, 2009.
- [ottaviano2010] Ottaviano E., Ceccarelli M., and Plamucci F. An application of CaTraSys, a cable-based parallel measuring system for an experimental characterization of human walking. *Robotica*, 28(1):119–133, January 2010.
- [ottaviano2021] Ottaviano E., Arena A., and Gattuli V. Geometrically exact three-dimensional modeling of cable-driven parallel manipulators for end-effector positioning. *Mechanism and Machine Theory*, 155, 2021.

- [ottoboni2007] Ottoboni A. and others. Equivalent spatial mechanisms for modelling passive motion of the human knee. J. of Biomechanics, 40(0):S144–S144, 2007.
- [ouerfelli91] Ouerfelli M. and Kumar V. Optimization of a spherical five bar parallel drive linkage. In ASME Design Automation Conf., Miami, September, 22-25, 1991.
- [ouerfelli94] Ouerfelli M. and Kumar V. Optimization of a spherical five bar parallel drive linkage. ASME J. of Mechanical Design, 116(1):166–173, March 1994.
- [ouyang 2002] Ouyang P.R., Zhang W.J., and Wu F.X. Nonlinear PD control for trajectory tracking with consideration of the design for control methodology. In *IEEE Int. Conf. on Robotics and Automation*, pages 4126–4131, Washington, May, 11-15, 2002.
- [ouyang 2014] Ouyang B. and Shang W-W. Wrench-feasible workspace based optimization of the fixed and moving platforms for cable-driven parallel manipulators. *Robotics and Computer-Integrated Manufacturing*, 30(6):629–635, December 2014.
- [ouyang 2015] Ouyang B. and Shang W-W. A new computation method for the force-closure workspace of cable-driven parallel manipulators. *Robotica*, 33(3):537–547, March 2015.
- [overholt91] Overholt J.L. and Zeid A.A. Partial state feedback linearization based control for a Stewart platform (Part I: Theory). In 23th Summer Computer Simulation Conf., pages 512–517, Baltimore, July, 22-24, 1991.
- [ozdemir2016] Özdemir M. Singularity-consistent payload locations for parallel manipulators. *Mechanism and Machine Theory*, 97:171–189, March 2016.
- [ozdemir2017] Özdemir M. Dynamic analysis of planar parallel robots considering singularities and different payloads. Robotics and Computer-Integrated Manufacturing, 46:114–121, 2017.
- [ozdemir2017-1] Özdemir M. Removal of singularities in the inverse dynamics of parallel robots. *Mechanism and Machine Theory*, 107:71–86, 2016.
- [ozdemir2019] Özdemir M. High-order singularities of 5R planar parallel robots. Robotica, 37:233–245, 2019.
- [ozgoren2019] Ozgoren M.K. Kinematic and kinetostatic analysis of parallel manipulators with emphasis on position, motion, and actuation singularities. *Robotica*, 37:599–625, 2019.
- [ozgur2010] Özgür E., Andreff N., and Martinet P. Vector-based dynamic modeling and control of the Quattro parallel robot by means of leg orientations. In *IEEE Int. Conf. on Robotics and Automation*, pages 638–643, Anchorage, May, 3-8, 2010.
- [ozgur2012] Özgür E. From Lines To Dynamics of Parallel Robots. Ph.D. Thesis, Université Blaise Pascal, Clermont-Ferrand, July, 13, 2012. **Keywords:** dynamics,control.
- [ozgur2013] Özgür E. High speed parallel kinematic manipulator state estimation from leg observation. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 424–429, Tokyo, November, 3-7, 2013.
- [ozgur2014] Özgür E. A vision-based generic dynamic model of PKMs and its experimental validation on the Quattro parallel robot. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, Besancon, July, 8-11, 2014.
- [paccot2007] Paccot F., Andreff N., and Martinet P. Enhancing tracking performances of parallel kinematic machines. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [paccot2008] Paccot F. and others . A vision-based computed torque control for parallel kinematic machines. In *IEEE Int. Conf. on Robotics and Automation*, pages 1556–1561, Pasadena, May, 19-23, 2008.
- [paccot2009] Paccot F., Andreff N., and Martinet P. A review on the dynamic control of parallel kinematic machines: theory and experiments. *Int. J. of Robotics Research*, 28(3):395–416, March 2009.
- [padmanabhan92] Padmanabhan B. and others . Closed-form inverse kinematic analysis of variable-geometry truss manipulator. ASME J. of Mechanical Design, 114(3):438–443, September 1992.
- [paganelli2007] Paganelli D. Avoiding parallel singularities of 3UPS and 3UPU spherical wrists. In *IEEE Int. Conf.* on Robotics and Automation, pages 1201–1206, Roma, April, 10-14, 2007.

- [pagis2013] Pagis G. and others . Optimal motion generation for exiting a parallel manipulator from a type 2 singularity. In ASME IDETC/CIE, Portland, August 2103.
- [pagis2015] Pagis G. and others . Enlarging parallel robot workspace through type-2 singularity crossing. *Control Eng. Practice*, 39:1–11, 2015.
- [pagis2015-phd] Pagis G. Augmentation de la taille de l'espace de travail opérationnel des robots parallèles en traversant les singularités de Type 2: génération de trajectoires optimales et commande avancée. Ph.D. Thesis, Ecole Centrale de Nantes, Nantes, January, 13, 2015. **Keywords:** singularity, workspace.
- [palmieri2018] Palmieri G. and others . Vision-based kinematic calibration of a small-scale spherical parallel kinematic machine. *Robotics and Computer-Integrated Manufacturing*, 49:162–169, 2018.
- [palpacelli2015] Palpacelli M. and others . Analysis and design of a reconfigurable 3-dof parallel manipulator for multimodal tasks. *IEEE/ASME Trans. on Mechatronics*, 20(4):1975–1985, August 2015.
- [palpacelli2016] Palpacelli M. Static performance improvement of an industrial robot by means of a cable-driven redundantly actuated system. *Robotics and Computer-Integrated Manufacturing*, 38:1–8, 2016.
- [pan2014] Pan Y. and Gao F. Mechanism topology design for novel parallel- parallel hexapod robot. In *UKACC International Conference on Control*, Loughborough, July, 9-11, 2014.
- [pan2019] Pan Y., Chen Y., and Li L. Analysis of kinematic dexterity and stiffness performance based on spring's wire-driven 4-SPS/U rigid–flexible parallel trunk joint mechanism. *International Journal of Structural Integrity*, 10(6):850–867, 2019.
- [pang93] Pang H. and Shahinpoor M. Analysis of static equilibrium of a parallel manipulator. *Robotica*, 11(5):433–443, 1993.
- [pang94] Pang H. and Shahinpoor M. Inverse dynamics of a parallel manipulator. *J. of Robotic Systems*, 11(8):693–702, December 1994.
- [parenti90] Parenti-Castelli V. and Innocenti C. Direct displacement analysis for some classes of spatial parallel mechanisms. In 8th RoManSy, pages 123–130, Cracow, July, 2-6, 1990.
- [parenti90-1] Parenti-Castelli V. and Innocenti C. Forward displacement analysis of parallel mechanisms: closed-form solution of PRR-3S and PPR-3S structures. In *ASME Proc. of the the 21th Biennial Mechanisms Conf.*, pages 263–269, Chicago, September, 16-19, 1990.
- [parenti92] Parenti-Castelli V. Recent techniques for direct position analysis of the generalized Stewart platform mechanism. In ARK, pages 129–135, Ferrare, September, 7-9, 1992.
- [parenti92-1] Parenti-Castelli V. and Innocenti C. Forward displacement analysis of parallel mechanisms: closed-form solution of PRR-3S and PPR-3S structures. ASME J. of Mechanical Design, 114(1):68–73, March 1992.
- [parenti95] Parenti-Castelli V. and Di Gregorio R. A three-equation numerical method for the direct kinematics of the generalized Gough-Stewart platform. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 837–841, Milan, August 30- September 2, 1995.
- [parenti96] Parenti-Castelli V. and Di Gregorio R. A real-time computation scheme for the direct position analysis of the 6-3 Stewart platform. In 27th Int. Symp. on Industrial Robots (ISIR), pages 581–585, Milan, October, 6-8, 1996.
- [parenti98] Parenti-Castelli V. and Di Gregorio R. Real-time computation of the actual posture of the general geometry 6-6 fully parallel mechanism using only two extra rotary sensors. ASME J. of Mechanical Design, 120(4):549–554, December 1998.
- [parenti99] Parenti-Castelli V. and Di Gregorio R. Determination of the actual configuration of the general Stewart platform using only one additional sensor. ASME J. of Mechanical Design, 121(1):21–25, March 1999.
- [parenti2000] Parenti-Castelli V. and Di Gregorio R. A new algorithm based on two extra sensors for real-time computation of the actual configuration of the generalized Stewart-Gough manipulator. ASME J. of Mechanical Design, 122(3):294–298, September 2000.

- [parenti2000-1] Parenti-Castelli V. and Di Gregorio R. Parallel mechanisms applied to the human knee passive motion simulation. In ARK, pages 333–344, Piran, June, 25-29, 2000.
- [parenti2000-2] Parenti-Castelli V. and Di Gregorio R. Influence of manufacturing errors on the kinematic performance of the 3-UPU parallel mechanism. In 2nd Chemnitzer Parallelkinematik Seminar, pages 85–99, Chemnitz, April, 12-13, 2000.
- [parenti2001] Parenti-Castelli V. and Di Gregorio R. Real-time actual pose determination of the general fully parallel spherical wrist, using only one extra sensor. *J. of Robotic Systems*, 18(12):723–729, 2001.
- [parenti2002] Parenti-Castelli V. and Venanzi S. On the joint clearance effects in serial and parallel manipulators. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, pages 215–223, Québec, October, 3-4, 2002.
- [parenti2004] Parenti-Castelli V. and others. On the modeling of passive motion of the human knee joint by means of equivalent planar and spatial parallel mechanisms. *Autonomous Robots*, 16(2):219–232, 2004.
- [park-jh2015] Park J-H., Stegall P., and Agrawal S.K. Dynamic brace for correction of abnormal postures of the human spine. In *IEEE Int. Conf. on Robotics and Automation*, pages 5922–5927, Seattle, May, 26-30, 2015.
- [park-y2020] Park Y. and others. WeHAPTIC: a wearable haptic interface for accurate position tracking and interactive force control. *Mechanism and Machine Theory*, 153, 2020.
- [park96] Park M.K. and Kim J.W. Kinematic manipulability of closed chains. In ARK, pages 99–108, Portoroz-Bernadin, June, 22-26, 1996.
- [park2001] Park M.K. and others . Development of the PNU vehicle driving simulator and its performance evaluation. In *IEEE Int. Conf. on Robotics and Automation*, pages 2325–2330, Seoul, May, 23-25, 2001.
- [parrish73] Parrish R.V. and others. Motion software for a synergistic six-degree-of-freedom motion base. Research Report D-7350, NASA, December 1973.
- [parsa2010] Parsa S.S, Daniali H.M., and Ghaderi R. Optimization of parallel manipulator trajectory for obstacle and singularity avoidances based on neural network. *The International Journal of Advanced Manufacturing Technology*, 51:811–816, 2010.
- [parsa2015] Parsa S.S, Boudreau R., and Carretero J.A. Reconfigurable mass parameters to cross direct kinematics singularities in parallel manipulators. *Mechanism and Machine Theory*, 85:53–63, 2015.
- [parushev90] Parushev P. and Chakarov D. Structural investigation of manipulators with linear drivers. In 8th RoManSy, pages 148–155, Cracovie, July, 2-6, 1990.
- [pashkevich2005] Pashkevic A., Wenger P., and Chablat D. Design strategies for the geometric synthesis of Orthoglidetype mechanisms. *Mechanism and Machine Theory*, 40(8):907–930, August 2005.
- [pashkevich2006] Pashkevic A., Chablat D., and Wenger P. Kinematics and workspace analysis of a three-axis parallel manipulator: the Orthoglide. *Robotica*, 24(1):39–49, January 2006.
- [pashkevich2007] Pashkevic A., Wenger P., and Chablat D. Kinematic and stiffness analysis of the Orthoglide, a PKM with simple, regular workspace and homogeneous performances. In *IEEE Int. Conf. on Robotics and Automation*, pages 549–554, Roma, April, 10-14, 2007.
- [pashkevich2008] Pashkevic A., Wenger P., and Chablat D. Stiffness analysis of 3-d.o.f. overconstrained translational parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1562–1567, Pasadena, May, 19-23, 2008.
- [pashkevich2008-1] Pashkevic A. and others . *Parallel manipulators, New Developments*, chapter Calibration of 3-d.o.f. translational parallel manipulator using leg observations, pages 225–240. ITECH, April 2008. **Keywords:** 3 dof robot, calibration.
- [pashkevich2010] Pashkevic A., Klimchik A., and Chablat D. Stiffness analysis of parallel manipulators with preloaded passive joints. In ARK, pages 465–474, Piran, June 28- July 1, 2010.

- [pashkevich2010-1] Pashkevic A. and others . Stiffness modelling of parallelogram-based parallel manipulators. In 3rd European Conf. on Mechanism Science (Eucomes), pages 675–682, Cluj-Napoca, September, 14-17, 2010.
- [pashkevich2010-2] Pashkevic A. and others . Performance evaluation of parallel manipulators for milling application. In 20th CIRP Design conference, pages 675–682, Nantes, April, 19-20, 2010.
- [pasila2012] Pasila F. and otehrs . Inverse static analysis of massive parallel arrays of three-state actuators via artificial intelligence. In *RoManSy*, Paris, June, 12-15, 2012.
- [pasqui-boutard-94-phd] Pasqui-Boutard V. Méthode systématique pour la modélisation et l'analyse cinématique des mécanismes complexes. Ph.D. Thesis, Université Pierre et Marie Curie, Paris, August, 29, 1994. **Keywords:** kinematics, singularity, workspace, mechanism theory.
- [pastorelli2009] Pastorelli S. and Batterezzato A. Singularity analysis of a 3 degrees-of-freedom parallel manipulator. In *Computational Kinematics*, pages 331–340, Duisburg, May, 6-8, 2009.
- [patarinski93] Patarinski S.P. and Uchiyama M. Position/orientation decoupled parallel manipulator. In *ICAR*, pages 153–158, Tokyo, November, 1-2, 1993.
- [patarinski94] Patarinski S.P. Parallel robots: a review, 1994. Communication personelle. **Keywords:** state of the art.
- [patel97] Patel A.J. and Ehmann K.F. Volumetric error analysis of a Stewart platform based machine tool. *Annals of the CIRP*, 46/1/1997:287-290, 1997.
- [patra2020] Patra B. and others . Analytical determination of the longest cylinder free of gain-type singularity inside the workspace of a 3-RPS spatial parallel manipulator. In ARK, 2020.
- [paty2021] Paty T. and others. Cable-driven parallel robot modelling considering pulley kinematics and cable elasticity. *Mechanism and Machine Theory*, 159, 2021.
- [pavlovic2006] Pavlovic N., Keimer R., and H-J. Frake. Design of an adaptronic swivel joint for parallel robots based on quasi-statical clearance adjustement. In 5th Chemnitzer Parallelkinematik Seminar, pages 341–355, Chemnitz, April, 25-26, 2006.
- [pazmino2011] Pazmño R.S. and others . Experiences and results from designing and developing a 6 dof underwater parallel robot. *Robotics and Autonomous Systems*, 59(2):101–112, February 2011.
- [pedemonte2020] Pedemonte N. and others . FASTKIT: A Mobile Cable-Driven Parallel Robot for Logistics, pages 141–163. Springer International Publishing, 2020. Keywords: wire robot.
- [pedrammehr2018] Pedrammehr S. and others . Dynamic analysis of Hexarot: axis-symmetric parallel manipulator. *Robotica*, 36:225–240, 2018.
- [pedrammehr2020] Pedrammehr S., Asadi H., and Nahavandi S. A study on vibrations of Hexarot-Based high-g centrifugal simulators. *Robotica*, 38:299–316, 2020.
- [peidro2015] Peidro A. and others. Performing nonsingular transitions between assembly modes in analytic parallel manipulators by enclosing quadruple solutions. ASME J. of Mechanical Design, 137, December 2015.
- [peirs 2000] Peirs J., Reynaerts D., and Van Brussel H. Design of miniature parallel manipulators for integration in a self-propelling endoscope. *Sensors and Actuators*, A(85):409–417, 2000.
- [pendar2007] Pendar H. and others . Kinematic analysis of the spherically actuated platform manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 175–180, Roma, April, 10-14, 2007.
- [pendar2008] Pendar H. and others . Singularity analysis of a 3 dof parallel manipulator using infinite constraint plane method. J. of Intelligent and Robotic Systems, 53(1):21–34, September 2008.
- [pendar2011] Pendar H. and others . Singularity analysis of parallel manipulator using constraint plane method. Mechanism and Machine Theory, 46:33–43, 2011.
- [peng-b2019] Peng B. and others . Kinematics and orientation capability of a family of 3-dof parallel mechanisms. *Mechanism and Machine Theory*, 142, 2019.

- [peng-m-2023] Peng M. and others . Dynamic modeling and characterization of compliant cable-driven parallel robots containing flexible cables. *Robotica*, 41:3160–3174, October 2023.
- [peng2010] Peng Z., Liu F., and Yang L. Control based on double neural networs-pi for parallel mechanism. *Robotics* and Computer-Integrated Manufacturing, 26(3):250–252, June 2010.
- [pennock90] Pennock G.R. and Kassner D.J. Kinematic analysis of a planar eight-bar linkage: application to a platform-type robot. In ASME Proc. of the 21th Biennial Mechanisms Conf., pages 37–43, Chicago, September, 16-19, 1990.
- [pennock91] Pennock G.R. and Kassner D.J. The workspace of a general geometry planar three degree of freedom platform manipulator. In *ASME Design Automation Conf.*, pages 537–544, Miami, September, 22-25, 1991.
- [pennock93] Pennock G.R. and Kassner D.J. The workspace of a general geometry planar three degree of freedom platform manipulator. ASME J. of Mechanical Design, 115(2):269–276, June 1993.
- [perez2004] Perez A. and McCarthy J.M. Dual quaternion synthesis of constrained robotic systems. ASME J. of Mechanical Design, 126(3):425–435, May 2004.
- [perju95] Perju D. and Dolga L. An optimizing study of a 6 components force transducer. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 2925–2929, Milan, August 30- September 2, 1995.
- [pernechele97] Pernechele C., Bortoletto F., and Reif K. Position-control for active secondary mirror of a two-mirror telescope. *Proc. of the SPIE*, 3112:172–180, 1997.
- [pernechele2000] Pernechele C., Bortoletto F., and Giro E. Neural network algorithm controlling a hexapod platform. In *IEEE IJC on Neural Network*, Como, July, 24-27, 2000.
- [pernette96] Pernette E. and Clavel R. Parallel robot and microrobotics. In 6th ISRAM, pages 535–542, Montpellier, May, 28-30, 1996.
- [pernette97] Pernette E. and others . Design of parallel robots in microrobotics. *Robotica*, 15(4):417–420, July August , 1997.
- [perng99] Perng M-H. and Hsiao L. Inverse kinematics solutions for a fully parallel robot with singularity robustness. *Int. J. of Robotics Research*, 18(6):575–583, June 1999.
- [pernkopf2002] Pernkopf F. and Husty M. Singularity analysis of spatial Stewart-Gough platform with planar base and platform. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [pernkopf-2003-phd] Pernkopf F. Workspace analysis of Stewart-Gough platforms. Ph.D. Thesis, Baufakultät, University of Innsbruck, September, 11, 2003. **Keywords:** workspace, singularity.
- [perreault 2008] Perreault S. and Gosselin C.M. Cable-driven parallel mechanisms: application to a locomotion interface. ASME J. of Mechanical Design, 130(10):102301–1/8, October 2008.
- [persson2003] Perssonn JG. and Andersson K. Modeling and model based performance prediction for parallel kinematics manipulators. In *Mechatronics Meeting*, Gothenburg, August, 28-29, 2003.
- [pessi2007] Pessi P. and others . A mobile robot with parallel kinematics to meet the requirements for assembling and machining the ITER vacuum vessel. Fusion Engineering and Design, 82(15-24):2047–2054, October 2007.
- [peters2000] Peters C. and others . Design and construction of the 3.2 Mev cathode assembly for DARHT II. In XX Int. Linac Conf., pages 437–439, Monterey, August, 21-25, 2000.
- [petersen2000] Petersen H.G. Easy and general kinematics for parallel manipulators. In *IASTED Int. Conf. Robotics* and Automation, pages 29–33, Honolulu, August, 14-16, 2000.
- [peterson2001] Peterson R. and Hobson J.C. High frequency motion simulator. In *SPIE*, *Aerosense 2001*, pages 225–237, Orlando, April, 16-20, 2001.
- [peterson2002] Peterson R. and others . 6 dof high-frequency motion simulator phaseII. In SPIE, Aerosense 2002, pages 56–66, Orlando, April, 1-5, 2002.

- [petitt2002] Petitt J.D. and Miller K. Six-dimensional visualisation of end-effector pose using colour spaces. In Australasian Conf. on Robotics and Automation, pages 216–221, Auckland, November, 27-29, 2002.
- [petrovic99] Petrovic P.B. and Milacic V.R. Closed-form resolution scheme of the direct kinematics of parallel link systems based on redundant sensory information. *Annals of the CIRP*, 48(1):341–344, 1999.
- [petuya2005] Petuya V. and others . Resolution of the direct position problem of parallel kinematic platform using the geometrical-iterative method. In *IEEE Int. Conf. on Robotics and Automation*, pages 3255–3260, Barcelona, April, 19-22, 2005.
- [petuya2008] Petuya V. and others . A new general-purpose method to solve the forward position problem in parallel manipulators. *Advanced Robotics*, 22(4):395–409, 2008.
- [peyron2017] Peyron Q., Charpentier I., and Laroche E. Continuation for stability domain determination with application to a cable-driven parallel robot. In 20th IFAC World Congress, 2017.
- [peysah85] Peysah E.E. Determination of the position of the member of three joints and two joints four member. Assur group with rotational pairs. *Machinery*, (5):55–61, 1985. In russian.
- [pfreundschuch91] Pfreundschuch G.H., Kumar V., and Sugar T.G. Design and control of a 3 d.o.f. in-parallel actuated manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 1659–1664, Sacramento, April, 11-14, 1991.
- [pham-cb2005] Pham C.B., Yeo S.H., and Yang G. Tension analysis of cable-driven parallel mechanisms. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Edmonton, August, 2-6, 2005.
- [pham-cb2005-1] Pham C.B., Yang G., and Yeo S.H. Dynamic analysis of cable-driven parallel mechanisms. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, Monterey, July, 24-28, 2005.
- [pham2004] Pham H.H. and Chen I-M. Optimal synthesis for workspace and manipulability of parallel flexure mechanism. In 11th IFToMM World Congress on the Theory of Machines and Mechanisms, Tianjin, April, 1-4, 2004.
- [pham2009] Pham H.H. and Chen I-M. Workspace analysis of fully restrained cable-driven manipulators. *Robotics and Autonomous Systems*, 57(9):901–912, September 2009.
- [pi2011] Pi Y. and Wang X. Trajectory tracking control of a 6-DOF hydraulic parallel robot manipulator with uncertain load disturbances. *Control Eng. Practice*, 19:185–193, 2011.
- [piao2015] Piao J. and others. Simulation of effect of cable robot configuration on natural frequency. In *IEEE International Conference on Mechatronics and Automation*, Bejing, August, 2-5, 2015.
- [piao2017] Piao J. and others . Open-loop position control of a polymer cable-driven parallel robot via a viscoelastic cable model for high payload workspaces. *Advances in Mechanical Engineering*, 9(12), 2017.
- [piao2017-1] Piao J. and others . Development of a high payload cable-driven parallel robot. In 17th International Conference on Control, Automation and Systems (ICCAS), Jeju, October, 18-21, 2017.
- [piao2017-2] Piao J. and others. Development of a high payload cable-driven parallel robot. In 17th International Conference on Control, Automation and Systems (ICCAS), Jeju, October, 18-21, 2017.
- [piao2017-3] Piao J. and others. A polymer cable creep modeling for a cable-driven parallel robot in a heavy paylod application. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [picard2018] Picard E. and others . Pulleys and force sensors influence on payload estimation of cable-driven parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Madrid, October, 1-5, 2018.
- [piccin2009] Piccin O. and others . Kinematic modeling of a 5-dof parallel mechanism for semi-spherical workspace. *Mechanism and Machine Theory*, 44(8):1485–1496, August 2009.
- [pickard-phd2018] Pickard J.K. Analysis and Synthesis Methods for the Appropriate Design of Parallel Mechanisms. Ph.D. Thesis, University of New Brunswick, April 2018. **Keywords:** mechanical architecture, optimal design.

- [pickard2016] Pickard J.K., Carretero J.A., and Merlet J-P. Accounting for tolerances in the design parameters of the 3Rr. In ARK, Grasse, June, 27-30, 2016.
- [pierrot90] Pierrot F., Benoit M., Dauchez P., and Galmiche J-P. High speed control of a parallel robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 949–954, Ibaraki, Japan, July, 3-6, 1990.
- [pierrot90-1] Pierrot F., Reynaud C., and Fournier A. DELTA: a simple and efficient parallel robot. *Robotica*, 8:105–109, 1990.
- [pierrot91] Pierrot F. Robots Pleinement Parallèles Légers : Conception Modélisation et Commande. Ph.D. Thesis, Université Montpellier II, Montpellier, April, 24, 1991. **Keywords:** mechanical architecture, control, applications.
- [pierrot91-1] Pierrot F., Dauchez P., and Fournier A. Towards a fully-parallel 6 d.o.f. robot for high speed applications. In *IEEE Int. Conf. on Robotics and Automation*, pages 1288–1293, Sacramento, April, 11-14, 1991.
- [pierrot91-2] Pierrot F., Dauchez P., and Fournier A. Hexa: a fast six-dof fully parallel robot. In *ICAR*, pages 1159–1163, Pise, June, 19-22, 1991.
- [pierrot91-3] Pierrot F., Dauchez P., and Fournier A. Fast parallel robots. J. of Robotic Systems, 8(6):829–840, December 1991.
- [pierrot92] Pierrot F. and others . Manipulations robotiques à haute vitesse: une solution pleinement parallèle. APII, 26(1):3-14, 1992.
- [pierrot97] Pierrot F. and Chiaccchio P. Evaluation of velocity capabilities for redundant parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 774–779, Albuquerque, April, 21-28, 1997.
- [pierrot99] Pierrot F. and Company O. H4: a new family of 4-dof parallel robots. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 508–513, Atlanta, September, 19-23, 1999.
- [pierrot2001] Pierrot F. Manipulateurs complexes: du laboratoire à l'atelier, March, 7, 2001. Habilitation à diriger les recherches.
- [pierrot2001-1] Pierrot F. and others . H4 parallel robot: modeling, design and preliminary experiments. In *IEEE Int. Conf. on Robotics and Automation*, pages 3256–3261, Seoul, May, 23-25, 2001.
- [pierrot2002] Pierrot F. Parallel mechanisms and redundancy. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 261–277, Braunschweig, May, 29-30, 2002.
- [pierrot2005] Pierrot F. and others . Lower mobility PKM for large tilting angles. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 253–268, Braunschweig, May, 10-11, 2005.
- [pierrot2006] Pierrot F. and others . Four-dof PKM with articulated traveling plate. In 5th Chemnitzer Parallelkine-matik Seminar, pages 677–693, Chemnitz, April, 25-26, 2006.
- [pierrot2009] Pierrot F. and others . Above 40g acceleration for pick-and-place with a new 2-dof PKM. In *IEEE Int. Conf. on Robotics and Automation*, pages 1794–1800, Kobe, May, 14-16, 2009.
- [pierrot2009-1] Pierrot F. and others . Optimal Design of a 4-DOF Parallel Manipulator: From Academia to Industry. *IEEE Trans. on Robotics*, 25(2):213–224, 2009.
- [pietrus92] Pietrus A. Étude numérique des systèmes triangulaires d'équations algébriques: Application à la robotique. Ph.D. Thesis, Université de Poitiers, Poitiers, December, 3, 1992. **Keywords:** forward kinematics.
- [pigani2014] Pigani l. and Gallina P. Cable-direct-driven-robot (cddr) with a 3-link passive serial support. Robotics and Computer-Integrated Manufacturing, 30(3):265–276, June 2014.
- [pile2014] Pile J. and Simaan N. Modeling, design, and evaluation of a parallel robot for cochlear implant surgery. *IEEE/ASME Trans. on Mechatronics*, 19(6):1746–1755, December 2014.
- [ping-lang2013] Ping-Lang Y. and Hung S.S. Cooperative force control of a hybrid cartesian parallel manipulator for bone slicing. *Robotica*, 31(2):183–191, March 2013.

- [ping-lang2019] Ping-Lang Y. and others. Optimization design for a compact redundant hybrid parallel kinematic machine. Robotics and Computer-Integrated Manufacturing, 58:172–180, 2019.
- [pinto2010] Pinto C. and others . A methodology for static stiffness mapping in lower mobility parallel manipulators with decoupled motions. *Robotica*, 28(5):719–735, October 2010.
- [piras 2005] Piras G., Cleghorn W.L., and Mills J.K. Dynamic finite-element analysis of a planar high-speed, high-precision parallel manipulator with flexible links. *Mechanism and Machine Theory*, 40(7):849–862, July 2005.
- [pisla2008] Pisla D., Plitea N., and Vaida C. Kinematic modeling and workspace generation for a new parallel robot used in minimally invasive surgery. In ARK, pages 459–467, Batz/mer, June, 23-26, 2008.
- [pisla2008-1] Pisla D. and Itul T. The influence of motion mode and friction on the dynamics of a parallel robot used for orientation applications. In 2nd European Conf. on Mechanism Science (Eucomes), Cassino, September, 17-20, 2008.
- [pisla2009] Pisla D. and others. Kinematical analysis and design of a new surgical parallel robot. In *Computational Kinematics*, Duisburg, May, 6-8, 2009.
- [pisla2010] Pisla D. and others . Kinematic design of a 5-dof parallel robot used in a minimally invasive surgery. In ARK, pages 99–106, Piran, June 28- July 1, 2010.
- [pisla2010-1] Pisla D. and others . On the dynamics of a 5 dof parallel hybrid robot used in minimally invasive surgery. In 3rd European Conf. on Mechanism Science (Eucomes), pages 691–699, Cluj-Napoca, September, 14-17, 2010.
- [pisla2012] Pisla D. and others . Kinematic modelling of a 5-dof hybrid parallel robot for laparoscopic surgery. *Robotica*, 30(7):1085–1107, December 2012.
- [pisla2013] Pisla D. and others . An active hybrid parallel robot for minimally invasive surgery. *Robotics and Computer-Integrated Manufacturing*, 29(1):203–221, February 2013.
- [pittens93] Pittens K.H. and Podhorodeski R.P. A family of Stewart platforms with optimal dexterity. *J. of Robotic Systems*, 10(4):463–479, June 1993.
- [pittiglio2018] Pittiglio G. and others . Available wrench set for planar mobile cable-driven parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, Brisbane, May, 21-25, 2018.
- [platis2016] Platis A. and others . Isotropic design of the spherical wrist of a cable-driven parallel robot. In ARK, Grasse, June, 27-30, 2016.
- [plitea2008] Plitea N. and others . Dynamic modelling of a parallel robot used in minimally invasive surgery. In 2nd European Conf. on Mechanism Science (Eucomes), Cassino, September, 17-20, 2008.
- [plitea2013] Plitea N. and others . Structural design and kinematics of a new parallel reconfigurable robot. *Robotics and Computer-Integrated Manufacturing*, 29(1):219–235, February 2013.
- [plitea2015] Plitea N., Szilaghyi S., and Pisla D. Kinematic analysis of a new 5-dof modular parallel robot for brachytherapy. *Robotics and Computer-Integrated Manufacturing*, 31:70–80, February 2015.
- [plooij2018] Plooij M. and others . Design of RYSEN: an intrinsically safe and low-power three-dimensional overground body weight support. *IEEE Robotics and Automation Letters*, 3(3), July 2018.
- [podhorodeski92] Podhorodeski R. Three branch hybrid-chain manipulators. In ARK, pages 150–155, Ferrare, September, 7-9, 1992.
- [podhorodeski92-1] Podhorodeski R. and Pittens K.H. Three branch hybrid-chain manipulators:design consideration. In *ISRAM*, pages 351–356, Santa-Fe, November, 11-13, 1992.
- [podhorodeski92-2] Podhorodeski R. and Pittens K.H. A class of hybrid-chain manipulators based on kinematically simple branches. In 22nd Biennial Mechanisms Conf., pages 59–64, Scottsdale, September, 13-16, 1992.
- [poduraev2006] Poduraev J., Ihlenfeldt S., and Loginov A. Development of a control approach for PKMs with scissor kinematics. In 5th Chemnitzer Parallelkinematik Seminar, pages 175–192, Chemnitz, April, 25-26, 2006.

- [poignet2003] Poignet P., Ramdani N., and Vivas O.A. Ellipsoidal estimation of parallel robot dynamic parameters. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3300–3305, Las Vegas, October, 27-31, 2003.
- [pollard42] Pollard W.L.V. Position controlling apparatus, June, 16, 1942. United States Patent n° 2,286,571. **Keywords:** mechanical architecture,3 dof robot,4 dof robot,patent.
- [pond2007] Pond G. and Carretero J.A. Quantitative dexterous workspace comparison of parallel manipulators. *Mechanism and Machine Theory*, 42(10):1388–1400, October 2007.
- [pond2008] Pond G. and Carretero J.A. *Parallel manipulators, New Developments*, chapter Quantitative dextrous workspace comparison of serial and parallel planar mechanism, pages 199–212. ITECH, April 2008. **Keywords:** planar robot,workspace,isotropy.
- [pond2009] Pond G. and Carretero J.A. Architecture optimisation of three  $3 \underline{P}RS$  variants for parallel kinematic machining. Robotics and Computer-Integrated Manufacturing, 25(1):64–72, February 2009.
- [pooran89] Pooran F.J. Dynamics and control of robot manipulators with closed-kinematic chain mechanism. Ph.D. Thesis, The Catholic University of America, Washington D.C., 1989. **Keywords:** dynamics, workspace, maximal workspace.
- [porta2002] Porta J.M. and others . Solving multi-loop linkages by iterating 2D clippings. In ARK, pages 255–264, Caldes de Malavalla, June 29- July 2, 2002.
- [porta2003] Porta J.M. and others . A branch-and-prune algorithm for solving systems of distance constraints. In *IEEE Int. Conf. on Robotics and Automation*, Taipei, September, 14-19, 2003.
- [porta2017] Porta J.M. and Thomas F. Closed form position analysis of variable geometry truss. *Mechanism and Machine Theory*, 109:14–21, 2017.
- [porta2018] Porta J.M. and Thomas F. The forward kinematics of doubly-planar Gough-Stewart platforms and the position analysis of strips of tetrahedra. In *ARK*, Bologna, July, 1-5, 2018.
- [portman2000] Portman V.T., Sandler B-Z, and Zahavi E. Rigid 6x6 parallel platform for precision 3D micromanipulation: theory and design application. *IEEE Trans. on Robotics and Automation*, 16(6):629–643, December 2000.
- [portman2002] Portman V.T. and Sandler B-Z. Tripod robot with cylindrically actuated limbs: structure and kinematics. *Mechanism and Machine Theory*, 37(12):1447–1463, December 2002.
- [portman2012] Portman V.T., Chapsky V.S., and Shneor Y. Workspace of parallel kinematics machines with minimum stiffness limits: Collinear stiffness value based approach. *Mechanism and Machine Theory*, 49, 2012.
- [portman2014] Portman V.T., Chapsky V.S., and Shneor Y. Evaluation and optimization of dynamic stiffness values of the PKMs: Collinear stiffness value approach. *Mechanism and Machine Theory*, 74:216–244, April 2014.
- [pott-pp2011] Pott P.P. and others . Inverse dynamic model and a control application of a novel 6-dof hybrid kinematics manipulator. J. of Intelligent and Robotic Systems, 63(1):3–23, July 2011.
- [pott2004] Pott A., Franitza D., and Hiller M. Orientation workspace verification for parallel kinematic machines with constant legs length. In *Mechatronics and Robotics Conf.*, Aachen, September, 13-15, 2004.
- [pott2004-1] Pott A. and Hiller M. A new approach to error analysis in parallel kinematic structures. In ARK, Sestri-Levante, June 28- July 1, 2004.
- [pott2006] Pott A., Boye T., and Hiller M. Design and optimization of parallel kinematic machines under process requirements. In 5th Chemnitzer Parallelkinematik Seminar, pages 193–212, Chemnitz, April, 25-26, 2006.
- [pott2006-1] Pott A. and Hiller M. A framework for the analysis, synthesis and optimization of parallel kinematic machines. In ARK, pages 103–112, Ljubljana, June, 26-29, 2006.
- [pott2007] Pott A. Analyse und synthese von werkzeugmaschinen mit paralleler kinematic. Research Report 409, Fortschritt-Berichte VDI, Düsseldorf, 2007.

- [pott2008] Pott A. and Hiller M. Parallel manipulators, Towards new applications, chapter Kinematic modeling, linearization and first order analysis, pages 155–174. ITECH, April 2008. **Keywords:** planar robot, redundant robot, statics, performance analysis.
- [pott2009] Pott A., Bruckmann T., and Mikelsons L. Closed-form force distribution for parallel wire robots. In *Computational Kinematics*, pages 25–34, Duisburg, May, 6-8, 2009.
- [pott2010] Pott A. An algorithm for real-time forward kinematics of cable-driven parallel robots. In ARK, pages 529–538, Piran, June 28- July 1, 2010.
- [pott2010-1] Pott A., Meyer C., and Verl A. Large-scale assembly of solar power plants with parallel cable robots. In *ROBOTIK 2010*, 2010.
- [pott2012] Pott A. Influence of pulley kinematics on cable-driven parallel robots. In ARK, pages 197–204, Innsbruck, June, 25-28, 2012.
- [pott2012-1] Pott A.. and others . IPAnema: a family of cable-driven parallel robots for industrial applications. In 1st Int. Conf. on cable-driven parallel robots (CableCon), pages 119–134, Stuttgart, September, 3-4, 2012.
- [pott2013] Pott A. and others . Cable-driven parallel robots for industrial applications: the IPAnema system family. In ISR, 2013.
- [pott2014] Pott A. On the limitations on the lower and upper tensions for cable-driven parallel robots. In ARK, pages 243–251, Ljulbjana, June 29- July 3, 2014.
- [pott2015] Pott A. and Schmidt V. On the forward kinematics of cable-driven parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, September 28- October 2, 2015.
- [pott2016] Pott A. and Kraus W. Determination of the wrench-closure translational workspace in closed-form for cable-driven parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, Stockholm, May, 16-20, 2016.
- [pott2017] Pott A. Determination of the cable span and cable deflection of cable-driven parallel robots. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [pott2018] Pott A. Cable-Driven Parallel Robots. Theory and Application. Springer, 2018. **Keywords:** wire robot, state of the art.
- [pott2018-1] Pott A. and Tempel P. A unified approach to forward kinematics for cable-driven parallel robots based on energy. In ARK, Bologna, July, 1-5, 2018.
- [pottmann98] Pottmann H., Peternell M., and Ravani B. Approximation in line space. Applications in robot kinematics. In ARK, pages 403–412, Strobl, June 29- July 4, 1998.
- [potton83] Potton S.L. Gec advanced device for assembly. Manufacturing systems, 13(2):130–144, 1983.
- [potton83-1] Potton S.L. Gec advanced device for assembly. In *Proc. of the CIRP Conf. on Assembly Automation*, pages 126–128, June, 20-22, 1983.
- [powell82] Powell I.L. The kinematic analysis and simulation of the parallel topology manipulator. *The Marconi Review*, XLV(226):121–138, Third Quarter 1982.
- [prajapati2020] Prajapati P., Parekh S., and Vashista V. On the human control of a multiple quadcopters with a cable-suspended payload system. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [prause 2015] Prause I. and Burkhard C. Dynamic modeling of the RPC-manipulator with prismatic or revolute joint actuation for different frame configurations. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 4105–4112, Hamburg, Germany, September 28- October 2, 2015.
- [preault2019] Préault C. and others . Optimal design and evaluation of a dexterous 4 dofs haptic device based on Delta architecture. *Robotica*, 37:1267–1288, 2019.
- [preda2015] Preda N. nd others. Motion planning for a multi-arm surgical robot using both sampling-based algorithms and motion primitives. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1422–1427, Hamburg, Germany, September 28- October 2, 2015.

- [prieto2013] Prieto P.J. and others . Proxy-based sliding mode control on platform of 3 degree of freedom (3-dof). Advanced Robotics, 27(10):773–784, 2013.
- [pritschow2002] Pritschow G., Eppler C., and Lehner W-D. Highly dynamic drives for parallel kinematic machines with constant arm length. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 199–211, Braunschweig, May, 29-30, 2002.
- [pritschow2002-1] Pritschow G., Eppler C., and Garber T. Influence of the dynamic stiffness on the accuracy of PKM. In 3rd Chemnitzer Parallelkinematik Seminar, pages 313–333, Chemnitz, April, 23-25, 2002.
- [pugazhenti-2002] S. Pugazhenti and others . Optimal trajectory planning for a hexapod machine-tool. *Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science*, 216(12):1247–1257, December 2002.
- [pugliti2013] Pugliti L.J. and others . Design and kinematic analysis of 3-PSS-1S wrist for needle insertion guidance. Robotics and Autonomous Systems, 61(5):417–427, May 2013.
- [pulloquinga 2021] Pulloquinga J.L. Experimental analysis of Type II singularities and assembly change points in a 3UPS + RPU parallel robot. Mechanism and Machine Theory, 158, 2021.
- [pulloquinga 2022] Pulloquinga J.L. and others . Trajectory planner for type II singularities avoidance based on output twist screws. In ARK, Bilbao, June, 26-30, 2022.
- [pusey2003] Pusey J. and others . Design and workspace analysis of a 6-6 cable-suspended parallel robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October 2003.
- [pusey2004] Pusey J. and others . Design and workspace analysis of a 6-6 cable-suspended parallel robot. *Mechanism and Machine Theory*, 139(7):761–778, July 2004.
- [qazani2015] Qazani M.R.C. and others. Kinematics analysis and workspace determination of hexarot-a novel 6-dof paralle manipulator with a rotation-symmetric arm system. *Robotica*, 33(8):1686–1703, October 2015.
- [qazani2020] Qazani M.R.C. and others . A new Gantry-Tau-based mechanism using spherical wrist and model predictive control-based motion cueing algorithm. *Robotica*, 38:1359–1380, 2020.
- [qi-kq-2017] Qi K-Q. and others . A novel 2-dof compound compliant parallel guiding mechanism. *Mechanism and Machine Theory*, 117:21–34, 2017.
- [qi-r2019] Qi R. and others . Decoupled modeling and model predictive control of a hybrid cable-driven robot (HCDR). *Robotics and Autonomous Systems*, 118, 2019.
- [qi-y2018] Qi Y. and Song Y. Coupled kinematic and dynamic analysis of parallel mechanism flying in space. *Mechanism and Machine Theory*, 124:104–117, 2018.
- [qi2007] Qi Z. and McInroy J.E. Nonlinear image based visual servoing using parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 1715–1720, Roma, April, 10-14, 2007.
- [qi2007-1] Qi Z., McInroy J.E., and Jafari F. Trajectory tracking with parallel robots using low chattering fuzzy sliding mode controller. *J. of Intelligent and Robotic Systems*, 48(3):333–356, March 2007.
- [qi2008] Qi Z. and McInroy J.E. Improved image based visual servoing with parallel robot. *J. of Intelligent and Robotic Systems*, 53(4):359–379, December 2008.
- [qian2018] Qian S, Bao K., Zi B., and Wang N. Kinematic calibration of a cable-driven parallel robot for 3D printing. Sensors, 2018.
- [qian2018-1] Qian S and others . A review on cable-driven parallel robots. *Chinese J. of Mechanical Engineering*, pages 31–66, 2018.
- [qian2018-2] Qian S and others. Development of modular cable-driven parallel robotic systems. IEEE Access, 2018.
- [qian2019] Qian S, Bao K., Zi B., and Zhu W. Dynamic trajectory planning for a 3-dof cable-driven parallel robot using quintic B-splines. ASME J. of Mechanical Design, pages 1–10, 2019.
- [qin-y2013] Qin Y. and others . Modeling and anlysis of a rigid-compliant parallel mechanism. *Robotics and Computer-Integrated Manufacturing*, 29(4):33–40, August 2013.

- [qin2010] Qin Z., Baron L., and Birglen L. A new approach to the dynamic parameter identification of robotic manipulators. *Robotica*, 28(4):539–547, July 2010.
- [qu2011] Qu H., Fang Y., and Guo S. A new method for isotropic analysis of limited parallel manipulators with terminal constraints. *Robotica*, 29(4):563–569, July 2011.
- [qu2017] Qu H., Guo S., and Zhang Y. A novel relative degree-of-freedom criterion for a class of parallel manipulators with kinematic redundancy and its applications. *Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science*, 231(22):4227–4240, 2017.
- [qu2018] Qu H., Zhang C., and S. Guo. Structural synthesis of a class of kinematically redundant parallel manipulators based on modified G–K criterion and RDOF criterion. *Mechanism and Machine Theory*, 130:47–70, 2018.
- [raabe2012] Raabe D., Dogramadzi S., and Atkins R. Semi-automatic percutaneous reduction of intra-articular joint fractures, an initial analysis. In *IEEE Int. Conf. on Robotics and Automation*, pages 2879–2884, Saint Paul, May, 14-18, 2012.
- [rabenorosoa2015] Rabenorosoa K. and others . Squipabot: a mesoscale parallel robot for a laser phonosurgery. International Journal of Optomechatronics, 9(4):310–324, 2015.
- [rachedi2015] Rachedi M. and Hermici M., B.and Bouri. Design of an  $H_{\infty}$  controller for the Delta robot: experimental results. Advanced Robotics, 29(18):1165–1181, 2015.
- [rachedi2015-1] Rachedi M., Bouri M., and Hermici B. Robust control of a parallel robot. In *International Conference* on Advanced Robotics (ICAR), 2015.
- [racila2007] Racila L. and Dahan M. Bricard mechanism used as translator. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [rad-sa2020] Rad S.A. and others. Experimental study on robust adaptive control with insufficient excitation of a 3-DOF spherical parallel robot for stabilization purposes. *Mechanism and Machine Theory*, 153, 2020.
- [rad2016] Rad F.P. and others. Analytical compliance analysis and finite element verification of spherical flexure hinges for spatial compliant mechanisms. *Mechanism and Machine Theory*, 101:168–180, 2016.
- [radermacher2002] Radermacher K. and others . Computer- und Robotertechnik für die bildgeführte Orthopädische Chirurgie. Automatisierungtechnik, 50:317–325, 2002.
- [raghavan91] Raghavan M. The Stewart platform of general geometry has 40 configurations. In ASME Design and Automation Conf., volume 32-2, pages 397–402, Chicago, September, 22-25, 1991.
- [raghavan93] Raghavan M. The Stewart platform of general geometry has 40 configurations. ASME J. of Mechanical Design, 115(2):277–282, 1993.
- [raghavan95] Raghavan M. and Roth B. Solving polynomial systems for the kinematic analysis of mechanisms and robot manipulators. ASME J. of Mechanical Design, 117(2):71–79, June 1995.
- [rahimi99] Rahimi M.A., Hemami H., and Zheng Y.F. Experimental study of a cable-driven suspended platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 1758–1763, Detroit, May, 10-15, 1999.
- [rahman2012] Rahman T. and others . Kinematic synthesis of nonspherical orientation manipulators: maximization of dexterous regular workspace by multiple response optimization. ASME J. of Mechanical Design, 134, July 2012.
- [rahman2017] Rahman T. and others. Application of response surface methodology for performing kinematic calibration of a  $3 \underline{P}SS/S$  parallel kinematic mechanism. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Vancouver, September, 24-28, 2017.
- [rahmani2020] Rahmani A. and Faroughi S. Application of a novel elimination algorithm with developed continuation method for nonlinear forward kinematics solution of modular hybrid manipulators. *Robotica*, 38:1963–1983, 2020.
- [rahul2019] Rahul K., Raheman H., and Paradkar V. Design and development of a 5R 2DOF parallel robot arm for handling paper pot seedlings in a vegetable transplanter. *Computers and Electronics in Agriculture*, 166, 2019.

- [rakhodaei2016] Rakhodaei h. and others . Path planning of the hybrid parallel robot for ankle rehabilitation. *Robotica*, 34(1):175–184, January 2016.
- [rakotomanga2008] Rakotomanga N., Chablat D., and Caro S. Kinetostatic performance of a planar parallel mechanism with variable actuation. In ARK, pages 311–320, Batz/mer, June, 23-26, 2008.
- [ramachandran92] Ramachandran S. and others. A finite element approach to the design and dynamic analysis of platform type manipulators. Finite elements in Analysis and Design, 10(4):335–350, 1992.
- [ramadour2014] Ramadour R., Chaumette F., and Merlet J-P. Grasping objects with a cable-driven parallel robot designed for transfer operation by visual servoing. In *IEEE Int. Conf. on Robotics and Automation*, pages 4463–4468, Hong-Kong, May 31- June 7, 2014.
- [ramadour2014-1] Ramadour R. and Merlet J-P. Computing safe trajectories for an assistive cable-driven parallel robot by selecting the cables under tension and using interval analysis. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 1349–1354, Besancon, July, 8-11, 2014.
- [ramdani2008] Ramdani N., Gouttefarde M., Pierrot F., and Merlet J-P. First results on the design of high speed parallel robots in presence of uncertainty. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2410–2415, Nice, France, September, 22-26, 2008.
- [ramesh2022] Ramesh S. and others . Forward kinematics of a novel 6-dof spatial hybrid manipulator. In ARK, Bilbao, June, 26-30, 2022.
- [ramrkahyani2004] Ramrkahyani D.S. and Lesieutre G.A. Aircraft structure morphing using tendon actuated compliant cellular trusses. In 45th AIAA Structures, Structural & Materials Conf., Palm Springs, April, 19-22, 2004.
- [ranganath2004] Ranganath R. and others. A force-torque sensor based on a Stewart platform in a near-singular configuration. *Mechanism and Machine Theory*, 39(9):971–998, September 2004.
- [rao-abk-2003] Rao A.B.K and others . Workspace and dexterity analyses of Hexaslide machine-tool. In *IEEE Int. Conf. on Robotics and Automation*, pages 4104–4109, Taipei, September, 14-19, 2003.
- [rao-abk-2006] Rao A.B.K and others . Dynamics modelling of Hexaslides using the decoupled natural orthogonal complement matrices. *Multibody System Dynamics*, 15:159–180, 2006.
- [rao-nm-2006] Rao N.M. and Rao K.M. Multi-position dimensional synthesis of a spatial 3-RPS parallel manipulator. ASME J. of Mechanical Design, 128(4):815–819, July 2006.
- [rao95] Rao A.C. Topological characteristics of linkage mechanisms with particular reference to platform type robots. *Mechanism and Machine Theory*, 30(1):33–42, January 1995.
- [rao97] Rao A.C. Platform-type planar robots: topology-based selection for rigidity and workspace. *J. of Robotic Systems*, 14(5):355–364, 1997.
- [rao97-1] Rao A.C. and Jagadeesh A. Structure-based dynamic characteristics of planar linkages including platform-type robots. *J. of Robotic Systems*, 14(8):621–629, 1997.
- [rao2004] Rao A.C. Parallelism in planar kinematic chains (manipulators). *Mechanism and Machine Theory*, 39(10):1111–1122, October 2004.
- [rao2006] Rao A.C. Parallelism in planar manipularos:a measure. ASME J. of Mechanical Design, 128(1):66–68, January 2006.
- [raoofian2017] Raoofian A., Kamali A., and Taghvaeipour A. Forward dynamic analysis of parallel robots using modified decoupled natural orthogonal complement method. Mechanism and Machine Theory, 115:197–217, 2017.
- [raparelli2002] Raparelli T. and others . Design of a parallel robot actuated by shape memory alloy wires. *Materials Transactions*, 43(5):1015–1022, 2002.
- [raparelli2002-1] Raparelli T. and others . A robot actuated by shape memory alloy wires. In *Int. Symp. on Industrial Electronics (ISIE)*, pages 420–423, L'Aquila, July, 8-11, 2002.

- [raparelli2008] Raparelli T. and others . Mechnical design of a 3-dof parallel robot actuated by smart wires. In 2nd European Conf. on Mechanism Science (Eucomes), Cassino, September, 17-20, 2008.
- [rasheed2017] Rasheed T. and others . Tension distribution algorithm for planar mobile cable-driven parallel robots. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [rasheed2018] Rasheed T. and others . Available wrench set for planar mobile cable-driven parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 962–967, Brisbane, May, 21-25, 2018.
- [rasheed2018-1] Rasheed T. and others . Kinematic modeling and twist feasibility of mobile cable-driven parallel robots. In ARK, Bologna, July, 1-5, 2018.
- [rasheed2019] Rasheed T. and others . Optimization based trajectory planning of mobile cable-driven parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Macau, November, 4-8, 2019.
- [rasheed2019-phd] Rasheed T. Collaborative mobile cable-driven parallel robots. Ph.D. Thesis, Ecole Centrale de Nantes, Nantes, 2019. **Keywords:** wire robot, applications.
- [rasheed2020] Rasheed T., Long P., and Caro S. Wrench-feasible workspace of mobile cable-driven parallel robots. *J. of Mechanisms and Robotics*, 12(3), 2020.
- [rastegar2005] Rastegar J., Yuan L., and Zhang J. Smart actuator displacement transmissibility in serial and parallel robot manipulators for performance enhancement. ASME J. of Mechanical Design, 127(4):589–595, July 2005.
- [rath2012] Rath G. and Zaev E. Cable driven robot for camera motion with six degrees of freedom. In *Mediterranean Conference on Embedded Computing*, Bar, 2012.
- [rauf2001] Rauf A. and Ryu J. Fully autonomous calibration of parallel manipulators by imposing position constraint. In *IEEE Int. Conf. on Robotics and Automation*, pages 2389–2394, Seoul, May, 23-25, 2001.
- [rauter2010] Rauter G. and others . A tendon-based parallel robot applied to motor learning in sports. In *Int. Conf. on Biomedical Robotics and Biomechatronics*, Tokyo, September, 26-29, 2010.
- [rebman88] Rebman J. Object manipulator, August, 23, 1988. United States Patent n° 4,765,795 Lord Corporation, Eric, Pa. **Keywords:** mechanical architecture,4 dof robot, patent, flexible robot.
- [reboulet85] Reboulet C. and Robert A. Hybrid control of a manipulator with an active compliant wrist. In 3rd ISRR, pages 76–80, Gouvieux, France, October, 7-11, 1985.
- [reboulet88] Reboulet C. Technique de la Robotique. Hermès, Paris, 1988. Keywords: state of the art.
- [reboulet90] Reboulet C. and Pigeyre R. Hybrid control of a 6 d.o.f. in parallel actuated micro-macro manipulator mounted on a Scara robot. In *ISRAM*, volume 3, pages 293–298, Burnaby, July, 18-20, 1990. ASME Press Series.
- [reboulet 90-1] Reboulet C. and others . Rapport d'avancement projet VAP, thème 7, phase 2. Research Report 7716-c, CNES/DERA, September 1990.
- [reboulet90-2] Reboulet C. Les nouvelles architectures de robots: performances et perspectives liées aux robots parallèles. In *8ieme journées Robotique et Productique du CETIM*, St Etienne, 1990.
- [reboulet91] Reboulet C. and others . Rapport d'avancement projet VAP, thème 7, phase 3. Research Report 7743, CNES/DERA, January 1991.
- [reboulet91-1] Reboulet C. and Berthomieu T. Dynamic model of a six degree of freedom parallel manipulator. In *ICAR*, pages 1153–1157, Pise, June, 19-22, 1991.
- [reboulet91-2] Reboulet C. and Lambert C. Les robots manipulateurs à structure parallèle, 1991. CERT-DERA Publication 1991. **Keywords:** state of the art.
- [reboulet92] Reboulet C., Lambert C., and Nombrail N. A parallel redundant manipulator: SPEED-R-MAN and its control. In *ISRAM*, pages 285–291, Santa-Fe, November, 11-13, 1992.
- [reboulet92-1] Reboulet C. and Pigeyre R. Hybrid control of a 6 d.o.f. in parallel actuated micro-manipulator mounted on a SCARA robot. *Int. J. of Robotics and Automation*, 7(1):10–14, 1992.

- [reboulet96] Reboulet C. and Leguay S. The interest of redundancy for the design of a spherical parallel manipulator. In ARK, pages 369–378, Portoroz-Bernadin, June, 22-26, 1996.
- [reboulet 96-1] Reboulet C. Parallel-structure manipulator device for displacing and orienting an object in a cylindrical workspace, July, 23, 1996. United States Patent n° 5,539,291 ONERA. **Keywords:** mechanical architecture, patent.
- [rees-jones79] Rees Jones J. Cross-coordinate control of a robot manipulator. In *Int. Workshop on Nuclear Robotics Technologies and Applications: Present and Future*, pages 1–10, University of Lancaster, -Juillet June, 26-1, 1979.
- [refaat2006] S. Refaat and others . Asymmetrical three-dof rotational-translational parallel-kinematic mechanism based on Lie group theory.  $European\ Journal\ of\ Mechanics\ A/Solids,\ 25(3):550–558,\ March\ -\ April\ ,\ 2004.$
- [refaat2007] S. Refaat and others. Two-mode overconstrained three-dofs rotational-translational linear-mode-based parallel-kinematics mechanism for machine tool applications. *Robotica*, 25(4):461–466, July 2007.
- [regelbrugge99] Regelbrugge M.E. Some aspect of precision positionning using hexapods. In 9th Int. Conf. on adaptive Structures and Technologies, pages 283–293, 1999.
- [rehsteiner99] Rehsteiner F. and others . Putting parallel kinematics machines (PKM) to productive work. *Annals of the CIRP*, 48(1):345–350, 1999.
- [reichert2014] Reichert C., Müller K., and Bruckmann T. Robust internal force-based impedance control for cable-driven parallel robots. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), pages 131–143, Duisburg, August, 24-27, 2014.
- [reichert2016] Reichert C. and others . Sensitivity analysis of the design parameters for the calibration of cable-driven parallel robots. *Proc. Appl. Math. Mech. (PAMM)*, pages 859–860, 2016.
- [reinholtz87] Reinholtz C.F. and Gokhale D. Design and analysis of variable geometry truss robots. In 9th Annual Conf. on Applied Mechanisms, pages 1–5, Oklahoma State University, 1987.
- [ren2005] Ren L., Mills J.K., and Sun D. Controller design applied to planar parallel manipulators for trajectory tracking control. In *IEEE Int. Conf. on Robotics and Automation*, pages 980–985, Barcelona, April, 19-22, 2005.
- [ren2006] Ren L., Mills J.K., and Sun D. Convex synchronized control for a 3-dof planar parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 1129–1134, Orlando, May, 16-18, 2006.
- [renaud2003] Renaud P. and others . Vision-based kinematic calibration of a H4 parallel mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 1191–1196, Taipei, September, 14-19, 2003.
- [renaud2003-1] Renaud P. and others . Optimal pose selection for vision-based kinematic calibration of parallel mechanisms. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October 2003.
- [renaud2003-2] Renaud P. Apport de la vision pour l'identification géométrique de mécanismes parallèles. Ph.D. Thesis, Université Blaise Pascal, Clermont-Ferrand, 2003. **Keywords:** calibration.
- [renaud2004] Renaud P., Andreff N., Pierrot F., and Martinet P. Combining end-effector and legs observation for kinematic calibration of parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 4116–4121, New Orleans, April, 28-30, 2004.
- [renaud2005] Renaud P. and others. Kinematic calibration of parallel mechanisms: a novel approach using legs observation. *IEEE Trans. on Robotics*, 21(4):529–538, August 2005.
- [renaud2006] Renaud P. and others . Kinematic and dynamic identification of parallel mechanisms. *Control Eng. Practice*, 14:1099–1109, 2006.
- [reveles-r2016] Reveles R D., Pamanes G J.A., and Wenger P. Trajectory planning of kinematically redundant parallel manipulators by using multiple working modes. *Mechanism and Machine Theory*, 98:216–230, April 2016.
- [rey1999] Rey L. and Clavel R. The Delta parallel robot. In Parallel Kinematic Machines, pages 401–417, 1999.

- [rezaei2012] Rezaei A., Akbarzadeh A., and Akbarzah-T M-R. An investigation on stiffness of a 3-PSP spatial parallel mechanism with flexible moving platform using invariant form. *Mechanism and Machine Theory*, 51:185–216, 2012.
- [rezaei2013] Rezaei A. and Akbarzadeh A. Position and stiffness analysis of a new asymmetric 2PRR–PPR parallel CNC machine. *Advanced Robotics*, 27(2):133–145, 2013.
- [rezaei2018] Rezaei A. and Akbarzadeh A. Influence of joints flexibility on overall stiffness of a 3<u>PRUP</u> compliant parallel manipulator. *Mechanism and Machine Theory*, 126:108–140, 2018.
- [rezagi2013] Rezagi A. and others. Position, jacobian and workspace analysis of a 3-PSP spatial parallel manipulator. Robotics and Computer-Integrated Manufacturing, 29(1):158–173, February 2013.
- [ribeiro2012] Ribeiro J.F. and others. Robot for wrist rehabilitation. In 4th European Conf. on Mechanism Science (Eucomes), pages 451–458, Santander, September, 19-21, 2012.
- [richard2007] Richard P.L., Gosselin C.M., and Kong X. Kinematic analysis and prototyping of a partially decoupled 4-dof 3TR1 parallel manipulator. ASME J. of Mechanical Design, 129(7):611–616, June 2007.
- [rico2002] Rico J.M. and Ravani B. Group theory can explain the mobility of paradoxical linkages. In ARK, pages 245–254, Caldes de Malavalla, June 29- July 2, 2002.
- [rico2006] Rico J.M. and others . A more general mobility criterion for parallel platforms. ASME J. of Mechanical Design, 128(1):207–219, January 2006.
- [rico2007] Rico J.M. and others. Mobility determination of displacement set fully parallel platforms. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [rico2008] Rico J.M. and others . New considerations on the theory of type synthesis of fully parallel platforms. ASME J. of Mechanical Design, 130(11):112302–1/9, November 2008.
- [ridgeway96] Ridgeway S.C., Crane C.M., and Duffy J. A forward analysis of two degree of freedom parallel manipulator. In *ARK*, pages 431–440, Portoroz-Bernadin, June, 22-26, 1996.
- [ridgeway2001] Ridgeway S.C. and Crane C.M. Optimized kinematics of a 6-6 parallel mechanism considering position and orientation errors. In *Florida Conf. on Recent Advances in Robotics*, Tallahassee, May, 10-11, 2001.
- [ridgeway2004] Ridgeway S.C. and Crane C.M. Control considerations in the design of a parallel kinematic machine with separate actuation and metrology mechanisms. In 12th Mediterranean Conf. on Control and Automation (MED'04), Kusadasi, June 2004.
- [riechel2004] Riechel A.T. and Ebert-Uphoff I. Force-feasible workspace analysis for underconstrained point-mass cable robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 4956–4962, New Orleans, April, 28-30, 2004.
- [riechel2004-1] Riechel A.T. and others . Concept paper: cable-driven robots for use in hazardous environments. In 10th Int. Topical Meeting on Robotics in hazardous environments, Gainesville, 2004.
- [riehl2009] Riehl N. and others . Effects of non-negligible cable mass on the static behavior of large workspace cable-driven parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 2193–2198, Kobe, May, 14-16, 2009.
- [riehl2010] Riehl N. and others . On the determination of cable characteristics for large dimension cable-driven parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 4709–4714, Anchorage, May, 3-8, 2010.
- [riehl2010-1] Riehl N. and others . On the static workspace of large dimension cable-suspended robots with non negligible cable mass. In 34th Annual Mechanisms and Robotics Conference, Montréal, August, 15-18, 2010.
- [rivera2014] Rivera J.A. and Kim C.J. Spatial parallel soft robotic architectures. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Chicago, September, 14-18, 2014.
- [rizk2007] Rizk R. and others . A semi-analytical stiffness model of parallel robots from the Isoglide family via the sub-structuring principle. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.

- [roberts98] Roberts R.G., Graham T., and Lippit T. On the inverse kinematics, statics and fault tolerance of cable-suspended robots. J. of Robotic Systems, 15(10):581–597, 1998.
- [roberts99] Roberts R.G. Minimal realization of a spatial stiffness matrix with simple springs connected in parallel. *IEEE Trans. on Robotics and Automation*, 15(5):953–958, October 1999.
- [roberts2000] Roberts R.G. Minimal realization of an arbitrary spatial stiffness matrix with a parallel connection of simple and complex springs. *IEEE Trans. on Robotics and Automation*, 16(5):603–608, October 2000.
- [roberts2007] Roberts R.G. and others . Characterizing optimally fault-tolerant manipulators based on relative manipulability indices. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3925–3930, San Diego, September, 22-26, 2007.
- [roberts2008] Roberts H.G, R.G. amd Yu and Maciejewski A.A. Fundamental limitations on designing optimally fault-tolerant redundant manipulators. *IEEE Trans. on Robotics and Automation*, 24(5), October 2008.
- [roberts97] Roberts R.G., Graham T., and Trumpower J.M. On the inverse kinematics and statics of cable-suspended robots. In *IEEE International Conference on Systems, Man, and Cybernetics*, pages 4291–4296, Orlando, October, 12-15, 1997.
- [robertz2010] Robertz S.G. and others . Precise robot motions using dual motor control. In *IEEE Int. Conf. on Robotics and Automation*, pages 5613–5620, Anchorage, May, 3-8, 2010.
- [robinson2012] Robinson J.D. and Hayes M.J.D. Velocity level kinematic analysis of serial nA chains. In *ARK*, pages 389–396, Innsbruck, June, 25-28, 2012.
- [rocher2017] Rocher X. Arm device, October, 25, 2017. INPI n° EP3233450. **Keywords:** wire robot, applications, patent.
- [rodriguesbarroso2020] Rodriguez-Barroso A. and Saltaren R. Tension planner for cable-driven suspended robots with unbounded upper cable tension and two degrees of redundancy. *Mechanism and Machine Theory*, 144, 2020.
- [rodriguezleal2009] Rodriguez-Leal E., Dai J., and Pennock G.R. Inverse kinematics and motion simulation of a 2-dof parallel manipulator with  $3 \underline{P}UP$  legs. In *Computational Kinematics*, pages 85–92, Duisburg, May, 6-8, 2009.
- [rogers72] Rogers W.F. Appolo experience report lunar module landing gear subsystem. Research Report D-6850, NASA, June 1972.
- [rognant2007] Rognant M. and Maurine P. Elasto-geometrical modelling of a pantographic linkage used as coordinate measuring arm for PKM applications. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [rognant2017] Rognant M. and Courteille E. Improvement of cable tension observability through a new cable driving unit design. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [rojas2010] Rojas N.. and Thomas F. A robust forward kinematics analysis of 3RPR planar platforms. In ARK, pages 23–32, Piran, June 28- July 1, 2010.
- [rojas2011] Rojas N.. and Thomas F. The forward kinematics of a  $3-r\underline{P}r$  planar robots: a review and a distance-based formulation. *IEEE Trans. on Robotics*, 27(1):143–156, February 2011.
- [rojas2012] Rojas N.., Borras J., and Thomas F. The octahedral manipulator revisited. In *IEEE Int. Conf. on Robotics and Automation*, pages 2293–2298, Saint Paul, May, 14-18, 2012.
- [rojas2013] Rojas N.. and Thomas F. The univariate closure condition of all fully parallel planar robots derived from a single polynomial. *IEEE Trans. on Robotics*, 29(3):758–765, June 2013.
- [rojeski-72-phd] Rojeski P. J. A systems analysis approach to landing gear design. Ph.D. Thesis, Cornell University, May 1972. **Keywords:** applications.
- [rolland99] Rolland L.H. The Manta and the Kanuk novel 4-dof parallel mechanisms for industrial handling. In ASME Int. Mech. Eng. Congress, Nashville, November, 14-19, 1999.

- [rolland2001] Rolland L. Méthodes algébriques pour la résolution du modèle géométrique de robot parallèle: applications à haute cadence et grande précision. In *Quatrième Journées du Pôle Micro-robotique*, Lyon, July, 4-5, 2001.
- [rolland2001-1] Rolland L. Introduction to algebraic methods for solving the forward kinematics problem of parallel robots applied to high throughput and high accuracy. In 3rd European-Asian Congress on Mechatronics, Besancon, October, 9-11, 2001.
- [rolland2003-phd] Rolland L. Outils algébriques pour la résolution de problèmes géométriques et l'analyse de trajectoire de robot parallèles prévus pour des applications à haute cadence et grande précision. Ph.D. Thesis, Université Henri Poincaré, Nancy, December, 11, 2003. **Keywords:** forward kinematics.
- [rolland2005] Rolland L. Certified solving of the forward kinematics problem with an exact algebraic method for the general parallel manipulator. *Advanced Robotics*, 19(9):995–1025, 2005.
- [rolland2006] Rolland L. Synthesis on forward kinematics problem algebraic modeling for the planar parallel manipulator: displacement-based equation systems. *Advanced Robotics*, 20(9):1035–1065, 2006.
- [rolland2015] Rolland L. Path Planning Kinematics Simulation of CNC Machine Tools Based on Parallel Manipulators, pages 147–192. Springer, 2015. **Keywords:** machine-tool, simulation, trajectory planning.
- [rolland2016] Rolland L. and Chandra R.. The forward kinematics of the 6-6 parallel manipulator using an evolutionary algorithm based on generalized generation gap with parent-centric crossover. *Robotica*, 34(1):1–22, 2016.
- [romdhane95] Romdhane L. Orientation workspace of fully parallel mechanisms. Eur. J. of Mechanics, 13(4):541–553, 1994.
- [romdhane99] Romdhane L. Design and analysis of a hybrid serial-parallel manipulator. *Mechanism and Machine Theory*, 34(7):1037–1055, October 1999.
- [romdhane2002] Romdhane L., Affi Z., and Fayet M. Design and singularity analysis of a 3-translational-dof in-parallel manipulator. ASME J. of Mechanical Design, 124(3):419–426, September 2002.
- [romiti90] Romiti A. and Sorli M. Flexible sensorized micro-assembly by a small parallel manipulator. In *Int. FAMOS Seminar*, pages 181–189, Besançon, September, 18-19, 1990.
- [romiti92] Romiti A. and Sorli M. Force and moment measurement on a robotic assembly hand. Sensors and Actuators, A(32):531–538, April 1992.
- [romiti93] Romiti A., Sorli M., and N. Zhmud'. Design and properties of the Turin 6 d.o.f. parallel robot for deburring operations. In 3rd Int. Symp. on Measurement and Control in Robotics, pages Bm.III–1,Bm.III–6, Turin, September, 21-24, 1993.
- [ronchi2004] Ronchi S. and others . PRP planar parallel mechanism in configurations improving displacement resolution. In 1st Int. Conf. on Positioning Technology, Hamamatsu, June, 9-11, 2005.
- [rong91] Rong H. and Liang C.G. A direct displacement solution to the triangle-platform 6-SPS parallel manipulator. In 8th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1237–1239, Prague, August, 26-31, 1991.
- [ronga92] Ronga F. and Vust T. Stewart platforms without computer? In Conf. Real Analytic and Algebraic Geometry, pages 197–212, Trento, 1992.
- [rooney83] Rooney J. and Earl C.F. Manipulator postures and kinematics assembly configurations. In 6th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1014–1020, New Dehli, 1983.
- [ropponen95] Ropponen T. and Arai T. Accuracy analysis of a modified Stewart platform manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 521–525, Nagoya, May, 25-27, 1995.
- [rosati2007] Rosati G., Gallina P., and Masiero S. Design, implementation and clinical test of a wire-based robot for neurorehabilitation. *IEEE Trans. on Neural Systems and Rehabilitation Engineering*, 15(4):560–569, December 2007.

- [rosati2007-1] Rosati G. and others. Trajectory planning of a two-link rehabilitation robot arm. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [roschel98] Röschel O. and Mick S. Characterisation of architecturally shaky platforms. In ARK, pages 465–474, Strobl, June 29- July 4, 1998.
- [rose2008] Röse A. and Schlaak H.F. A parallel kinematic mechanism for highly flexible laparoscopic instrument. In 4th Europen Conf. of the Int. Federation for Medical and Biological Engineering, pages 903–906, Antwerp, 2008.
- [rose2009] Röse A. and others . A novel piezoelectric driven laparoscopic instrument with multiple degree of freedom parallel kinematic structure. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, St Louis, October, 11-15, 2009.
- [rosenzveig2013] Rosenzveig V., Briot S., and Martinet P. Minimal representation for the control of the adept quattro with rigid platform via leg observation considering a hidden robot model. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 430–435, Tokyo, November, 3-7, 2013.
- [rosenzveig2015-phd] Rosenzveig V. Sensor-based design an control of high-speed manipulators. Ph.D. Thesis, Ecole Centrale de Nantes, Nantes, September, 25, 2015. **Keywords:** control.
- [rosheim2003] Rosheim M.E. Robotic manipulator, May, 8, 2003. IPN n° WO 03/037573. **Keywords:** applications,patent,2 dof robot,wrist.
- [rosyid2018] Rosyid A. and others . Genetic and hybrid algorithms for optimization of non-singular 3PRR planar parallel kinematics mechanism for machining application. *Robotica*, 36:839–864, 2018.
- [rouhani2016] Rouhani E. and Nategh M.J. An elastokinematic solution to the inverse kinematics of microhexapod manipulator with flexure joints of varying rotation center. *Mechanism and Machine Theory*, 97:127–140, 2016.
- [rouillier95] Rouillier F. Real roots counting for some robotics problems. In J-P. Merlet B. Ravani, editor, *Computational Kinematics*, pages 73–82. Kluwer, 1995.
- [rubbert2012-phd] Rubbert L. Conception de mécanismes compliants pour la robotique chirurgicale. Ph.D. Thesis, Université de Strasbourg, Strasbourg, 2012. **Keywords:** medical,3 dof robot,passive compliance,optimal design,piezo-electric.
- [rubbert2012] Rubbert L. and others . A planar compliant mechanism with RRP mobilities based on the singularity analysis of a 3-US parallel mechanism. In ARK, pages 381–388, Innsbruck, June, 25-28, 2012.
- [rubbert2014] Rubbert L. and others . Using singularities of parallel manipulators for enhancing the rigid-body replacement design method of compliant mechanisms. ASME J. of Mechanical Design, 136, 2014.
- [rubio2000] Rubio A., Avello A., and Florez J. On the use of virtual springs to avoid singularities and workspace boundaries in force-feedback teleoperation. In *IEEE Int. Conf. on Robotics and Automation*, pages 2690–2695, San Francisco, April, 24-28, 2000.
- [ruggiu2009] Ruggiu M. Position analysis, workspace and optimization of a  $3 \underline{P}PS$  spatial manipulator. ASME J. of Mechanical Design, 131(5):051010-1/051010-9, May 2009.
- [ruggiu2010] Ruggiu M. and Carretero J.A. Actuation strategy based on the acceleration method for the  $3 \underline{P}R\underline{P}R$  redundant planar parallel manipulator. In ARK, pages 91–98, Piran, June 28- July 1, 2010.
- [ruggiu2012] Ruggiu M. and Kong X. Mobility and kinematic analysis of a parallel mechanism with both PPR and planar operation modes. *Mechanism and Machine Theory*, 55:77–90, 2012.
- [ruiz2018] Ruiz A.G. and others. On redundancy resolution and energy consumption of kinematically redundant planar parallel manipulators. *Robotica*, 36:809–821, 2018.
- [ruiztorres2012] Ruiz-Torres M.F., Castillo-Castaneda E., and Briones-Leon J.A. Design and analysis of CICABOT, a novel translation parallel manipulator based on two 5-bars mechanisms. *Robotica*, 30(3):449–456, May 2012.
- [ruscelli2018] Ruscelli F. and others . A fail-safe semi-centralized impedance controller: validation on a parallel kinematics ankle. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Madrid, October, 1-5, 2018.

- [rushton2017] M. Rushton. and Khajepour A. Transverse vibration control in planar cable-driven robotic manipulators. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [rushton2019] M. Rushton., Jamshidifar H., and Khajepour A. Multiaxis reaction system (MARS) for vibration control of planar cable-driven parallel robots. *IEEE Trans. on Robotics*, 35(4), August 2019.
- [russo2018] Russo M. and others . Kinematic analysis and multi-objective optimization of a 3-UPR parallel mechanism for a robotic leg. *Mechanism and Machine Theory*, 120:192–202, 2018.
- [russo2020] Russo M. and Dong X. A calibration procedure for reconfigurable Gough-Stewart manipulators. *Mechanism and Machine Theory*, 152, 2020.
- [ryu-d-2003] Ryu D. and others . Design of a 6 DOF haptic master for teleoperation of a mobile manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3243–3248, Taipei, September, 14-19, 2003.
- [ryu98] Ryu R.J. and others. Eclipse: an overactuated parallel mechanism for rapid machining. In 12th RoManSy, pages 79–86, Paris, July, 6-9, 1998.
- [ryu2001] Ryu J. and Cha J. Optimal architecture design of parallel manipulators for best accuracy. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Maui, Hawaii, October 29- November 3, 2001.
- [ryu2003] Ryu J. and Cha J. Volumetric error analysis and architecture optimization for accuracy of HexaSlide type parallel manipulators. *Mechanism and Machine Theory*, 38(3):227–240, March 2003.
- [saadatzi2011] Saadatzi M.H. and others . On the optimum design of  $3 R\underline{P}R$  parallel mechanisms. In 19th Iranian Conference on Electrical Engineering, 2011.
- [saafi2015] H. Saafi., Laribi M.A., and Zeghloul S. Optimal haptic control of a redundant 3-RRR spherical parallel manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, September 28- October 2, 2015.
- [saafi2015-1] H. Saafi., Laribi M.A., and Zeghloul S. Redundantly acctuated 3-RRR spherical parallel manipulator used as a haptic device: improving dexterity and eliminating singularities. *Robotica*, 33(5):1113–1130, June 2015.
- [saafi2015-2] H. Saafi., Laribi M.A., and Zeghloul S. Forward kinematic model improvement of a spherical parallel manipulator using an extra sensor. *Mechanism and Machine Theory*, 91:102–119, 2015.
- [saafi2017] H. Saafi., Laribi M.A., and Zeghloul S. Optimal torque distribution for a redundant 3-RRR spherical parallel manipulator used as a haptical medical device. *Robotics and Autonomous Systems*, 89:40–50, 2017.
- [saafi2020] H. Saafi. and Lamine H. Comparative kinematic analysis and design optimization of redundant and nonredundant planar parallel manipulators intended for haptic use. *Robotica*, 38:1463–1477, 2020.
- [sabahi2014] Sabahi F., Khosravi M.A., and Taghirad H.D. Implementation of analytic iterative redundancy resolution technique on KNTU cable robot. In 2nd RSI/ISM International Conference on Robotics and Mechatronics, Teheran, October, 15-17, 2014.
- [sabater 2004] Sabater J.M., Saltarén R.J., and Aracil R. Design, modelling and implementation of a 6 URS parallel haptic device. *Robotics and Autonomous Systems*, 47(1):1–10, May 2004.
- [sabater 2005] Sabater J.M. and others . Magister-P; a 6-URS parallel haptic device with open control architecture. *Robotica*, 23(2):177–187, March 2005.
- [sadjadian2005] Sadjadian H. and Taghirad H.D. Comparison of different methods for computing the forward kinematics of a redundant parallel manipulator. J. of Intelligent and Robotic Systems, 44(3), November 2005.
- [sadjadian2006] Sadjadian H. and Taghirad H.D. Kinematics, singularity and stiffness analysis of the hydraulic shoulder: a 3-dof redundant parallel manipulator. *Advanced Robotics*, 20(7):763–781, 2006.
- [saenz2002] Saenz A.J. New automation solutions in aeronautics through parallel kinematic systems. In 3rd Chemnitzer Parallelkinematik Seminar, pages 563–578, Chemnitz, April, 23-25, 2002.

- [saglia2009] Saglia J.A. and others. High performance 2-dof over-actuated parallel mechanism for ankle rehabilitation. In *IEEE Int. Conf. on Robotics and Automation*, pages 2180–2186, Kobe, May, 14-16, 2009.
- [saglia2009-1] Saglia J.A. and others . A high-performance redundantly actuated parallel mechanism for ankle rehabilitation. *Int. J. of Robotics Research*, 28(9):1216–1227, September 2009.
- [saglia2009-2] Saglia J.A. and others. Inverse-kinematics-based control of a redundantly actuated platform for rehabilitation. *Proc. Instn Mech Engrs, Part I: J. of Systems and Control Engineering*, 223(53), 2007.
- [saglia2010] Saglia J.A. and others . Control strategies for ankle rehabilitation using a high performance ankle exerciser. In *IEEE Int. Conf. on Robotics and Automation*, pages 2221–2227, Anchorage, May, 3-8, 2010.
- [sahin2007] Sahin S. and Notash L. Force and stiffness analyses of wireactuated parallel manipulators. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [saidouni2007] Saidouni T., Bessaoudi M., and Terki A. Design and analysis of a mechanism actuating a sight device. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [saied2017] Saied H. and others . From non-model-based to model-based control of PKMs: a comparative study. In *International Congress for the Advancement of Mechanism, Machine, Robotics and Mechatronics Sciences*, Beyrouth, 2017.
- [saied2019] Saied H. and others . A new time-varying feedback RISE control of PKMs: theory and application. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Macau, 2019.
- [salah2017] Salah B. and others . Design and simulation based validation of the control architecture of a stacker crane based on an innovative wire-driven robot. *Robotics and Computer-Integrated Manufacturing*, 44:117–128, April 2017.
- [salcudean94] Salcudean S.E. and others . A six degree-of-freedom, hydraulic, one person motion simulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 2437–2443, San Diego, May, 8-13, 1994.
- [salcudean 94-1] Salcudean S.E., Bachmann S., and Ben-Dov D. A six degree-of-freedom wrist with pneumatic suspension. In *IEEE Int. Conf. on Robotics and Automation*, pages 2444–2450, San Diego, May, 8-13, 1994.
- [salgado2007] Salgado O. and others. Type synthesis of a family of 3T1R fully-parallel manipulators using a group-theoretic approach. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- $[salgado 2007-1] \ Salgado \ O. \ and \ others. \ A \ parallelogram-based \ parallel \ manipulator \ for Schönflies \ motion. \ ASME \ J. \ of \ Mechanical \ Design, \ 129(12):1243-1250, \ \ December \ \ 2007.$
- [salgado2008] Salgado O. and others . Synthesis and design of a novel 3T1R fully-parallel manipulator. ASME J. of Mechanical Design, 130(4):042305–1/8, April 2008.
- [saltaren2007] Saltarén R. and others . Exploring deep sea by teleoperated robot. *IEEE Robotics and Automation Magazine*, 14(3):65–75, September 2007.
- [saltaren2007-1] Saltarén R. and others . Performance evaluation of spherical parallel platforms for humanoid robots. Robotica, 25(3):257-267, May 2007.
- [saltaren2009] Saltaren R. and others . Underwater parallel robot for oceanic measuring and observations-REMO I: development and navigation control advances. In *OCEANS 2009-EUROPE*, Bremen, 2009.
- [saltaren2011] Saltaren R. and others . Experiences and results from designing and developing a 6 dof underwater parallel robot. *Robotics and Autonomous Systems*, 59, 2011.
- [sanchez96] Sanchez J-C. Intérêt d'une redondance cinématique pour la commande en effort d'un robot manipulateur. Applications au robot parallèle et redondant SPEED-R-MAN. Ph.D. Thesis, ENSAE, Toulouse, June, 11, 1996. **Keywords:** control, redundant robot, dynamics.
- [sanchezlopez2013] Sanchez-Lopez J.L. Toward visual autonomous ship board landing of a VTOL UAV. In *International Conference on Unmanned Aircraft Systems (ICUAS)*, Atlanta, 2013.

- [sancisi2007] Sancisi N. and Parenti-Castelli V. On the synthesis of a 5-5 parallel mechanism reproducing the knee passive motion by means of the Burmester theory. In 2nd Int. Congress, Design and Modelling of mechanical systems, Monastir, March, 19-21, 2007.
- [sancisi2007-1] Sancisi N. and Parenti-Castelli V. A 1-dof parallel spherical wrist for the modelling of the knee passive motion. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [sancisi2010] Sancisi N. and Parenti-Castelli V. A 1-dof parallel spherical wrist for the modelling of the knee passive motion. *Mechanism and Machine Theory*, 45(4):658–665, April 2010.
- [sancisi2012] Sancisi N. and Parenti-Castelli V. On the role of passive structures in the knee loaded motion. In ARK, pages 445–452, Innsbruck, June, 25-28, 2012.
- [sang-nd2018] Sang N.D. and others. Kinematic design of five-bar parallel robot by kinematically defined performance index for energy consumption. In *EUCOMES*, pages 239–247, Aachen, September, 4-6, 2018.
- [sang99] Sang L.H. and Han M-C. The estimation for forward kinematic solution of Stewart platform using the neural network. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Kyongju, October, 17-21, 1999.
- [sanjuan2018] Sanjuan J., Serje D., and Pacheco J. Closed form solution for direct and inverse kinematics of a US-RS-RPS 2-dof parallel robot. *Scientia Iranica*, 25(4):2144–2154, 2018.
- [santangelo2005] Santangelo B.G. and Sinatra R. Static balancing of a six-degree-of-freedon parallel mechanism with six two-link revolute legs. *Int. J. of Robotics and Automation*, 20(4):222–230, 2005.
- [santos2020] Santos J.C., Chemori A., and Gouttefarde M. Redundancy resolution integrated model predictive control of CDPRs: concept, implementation and experiments. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [saputra2010] Saputra V.B., Ong S.K., and Nee A.Y.C. A PSO algorithm for mapping the workspace boundary of parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 4691–4696, Anchorage, May, 3-8, 2010.
- [sarkar2018] Sarkar B.K. Modeling and validation of a 2-dof parallel manipulator for pose control application. *Robotics and Computer-Integrated Manufacturing*, 50:234–241, 2018.
- [sarkisov2020] Sarkisov Y.S. and others. Optimal oscillation damping control of cable-suspended aerial manipulator with a single imu sensor. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [sarkissyan89] Sarkissyan Y.L. and Parikyan T.F. Direct position problem for 6 (sps) linkage and associated synthesis problem. In 5th IFToMM Int. Symp. on linkages and CAD methods, volume II-2, pages 543–550, Bucharest, 1989. in russian.
- [sarkissyan90] Sarkissyan Y.L. and Parikyan T.F. Analysis of special configurations of parallel topology manipulator. In 8th RoManSy, pages 156–163, Cracovie, July, 2-6, 1990.
- [sarkissyan90-1] Sarkissyan Y.L. and Parikyan T.F. Manipulator, 1990. Russian Patent n° 1585144. **Keywords:** mechanical architecture,6 dof robot,patent.
- [sarkissyan95] Sarkissyan Y.L. and Parikyan T.F. Direct position problem for Stewart platform and multiple points of 5(SS) linkage coupler curve. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1614–1618, Milan, August 30- September 2, 1995.
- [sarma92] Sarma R., Kramer S.N., and Ramamurti V. The dynamic equations of motion and actuation scheme for the tetrahedron based variable geometry truss manipulator. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 173–178, Scottsdale, September, 13-16, 1992.
- [sato2001] Sato D. and others . 3D graphics-based off-line task teaching for a force-controlled high-speed parallel robot. In *IEEE Int. Symp. on Assembly and Task planning*, pages 122–127, Fukuoka, May, 28-29, 2001.
- [sato2003] Sato D., Shitashimizu T., and Uchiyama M. Task teaching to a force-controlled high-speed parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 4110–4115, Taipei, September, 14-19, 2003.

- [sato2006] Sato D. and others. Task teaching system for a force-controlled parallel robot using multiple teaching modes with human demonstration data. In *IEEE Int. Conf. on Robotics and Automation*, pages 3960–3965, Orlando, May, 16-18, 2006.
- [savall2008] Savall J. and others . High-performance linear cable transmission. ASME J. of Mechanical Design, 130(6):064501-1/064501-5, June 2008.
- [savoure 2006] Savoure L. and others . An improved method for the geometrical calibration of parallelogram based parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 769–776, Orlando, May, 16-18, 2006.
- [sayapin2002] Sayapin S.N. Application of parallel kinematics machines for active vibration isolation and pointing of high-precision large deployable space structure (HLDSS). In 3rd Chemnitzer Parallelkinematik Seminar, pages 957–962, Chemnitz, April, 23-25, 2002.
- [scalera2018] Scalera L. and others . Cable-based robotic crane (cbrc): design and implementation of overhead traveling cranes based on variable radius drum. *IEEE Trans. on Robotics*, 34(2):474–494, April 2018.
- [scalera2020] Scalera L., Gasparetto A., and Zanotto D. Design and experimental validation of a 3-dof underactuated pendulum-like robot. *IEEE/ASME Trans. on Mechatronics*, 25(1):217–228, 2020.
- [schadlbauer2014] Schadlbauer J., Walter D.R., and Husty M. The 3-RPS parallel manipulator from an algebraic viewpoint. *Mechanism and Machine Theory*, 75:161–176, May 2014.
- [schappler2022] Schappler M. Structural and dimensional synthesis of overconstraint symmetric 3T2R parallel robots using Tait-Bryan-angle kinematic constraints. In ARK, Bilbao, June, 26-30, 2022.
- [schappler2022-1] Schappler M. Inverse kinematics for functional redundancy of symmetric 3T1R parallel manipulators using Tait-Bryan-angle kinematic constraints. In ARK, Bilbao, June, 26-30, 2022.
- [schenk2015] Schenck C., Bülthoff H.H., and Masone C. Robust adaptive sliding mode control of a redundant cable-driven parallel robot. In *Int. Conf. on System Theory, Control and Computing*, Cheile Gradisteil, October, 14-16, 2015.
- [schenk2016] Schenck C. and others . Modeling and analysis of cable vibrations for a cable-driven parallel robot. In *IEEE Int. Conf. on Information and Automation*, Ningho, 2016.
- [schenk2017] Schenck C. and others . Application of a differentiator-based adaptive super-twisting controller for a redundant cable-driven parallel robot. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [schenk2018] Schenck C. and others . Port hamiltonian modeling of a cable-driven parallel robot. In 6th IFAC Workshop on Lagrangian and Hamiltonian Methods for Nonlinear Control, Valparaiso, May, 1-4, 2018.
- [schmid98] Schmid H.A. Spreizbandmechanik in parallelen maschinen. In New machine concepts for handling and manufacturing devices on the basis of parallel structures, pages 95–100, Braunschweig, November, 10-11, 1998.
- [schmid2001] Schmid H.A. Spreadbands drive parallel robots. Industrial Robot, 28(4):320–327, 2001.
- [schmidt-v2012] Schmidt V. and Pott A. Implementing extended kinematics of a cable-driven parallel robot in realtime. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [schmidt-v2014] Schmidt V. and others . Extending dynamic trajectories of cable-driven parallel robots as a novel robotic roller coaster. In *Robotik 2014*, 2014.
- [schmidt-v2014-1] Schmidt V., Kraus W., and Pott A. Presentation of experimental results on stability of a 3 dof 4-cable parallel robot without constraints. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), Duisburg, August, 24-27, 2014.
- [schmidt-v2016-1] Schmidt V. and Pott A. Increase of position accuracy for cable-driven parallel robots using a model for elongation of plastic fiber ropes. In *Eucomes*, Nantes, September, 20-23, 2016.
- [schmidt-v2016-2] Schmidt V. and Pott A. Investigating the effect of cable force on winch winding accuracy for cable-driven parallel robots. *Proc. Instn Mech Engrs, Part K: J. Multi-body dynamics*, 230(3):237–241, 2016.

- [schmidt-v2017] Schmidt V. and others. Black-box accuracy compensation for a cable-driven parallel robot. In *Int. Conf. on Control, Automation and Systems (ICCAS)*, Jeju, October, 18-20, 2017.
- [schmidt-v2017-1] Schmidt V.. and Pott A. Bending cycles and cable properties of polymer fiber cables for fully constrained cable-driven parallel robots. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [schmidt-v2016] Schmidt V.L. Modeling Techniques and Reliable Real-Time Implementation of Kinematics for Cable-Driven Parallel Robots using Polymer Fiber Cables. Ph.D. Thesis, Université Stuttgart, June, 20, 2016. Keywords: wire robot,kinematics.
- [schneider2013] Schneider U. Compensation of errors in robot machining with a parallel 3D-piezo compensation mechanism. In 46th CIRP Conference on Manufacturing Systems, pages 305–310, Sesimbra, May, 29-31, 2013.
- [schonherr90-1-m] Schönherr M. Der messwagen für ultraleicht-flugzeuge läuft, August 1990. DULV,Nr. 3. **Keywords:** applications.
- [schonherr90-m] Schönherr M. Vorrichtung zur messung des Kräfte und momente ruhender and bewegte objkete, June, 9, 1990. German Patent DE 4018558C2. **Keywords:** applications,patent,force sensor.
- [schonherr98] Schönherr J. and Weidermann F. Bewertung und optimale auslegung von bewegunssystem mit parallelkinematik. In *New machine concepts for handling and manufacturing devices on the basis of parallel structures*, pages 35–49, Braunschweig, November, 10-11, 1998.
- [schonherr98-m] Schönherr M. Neun jahre praxiserfahrung mit dem ersten elektromotorisch angetriebenen hexapodroboter. In *New machine concepts for handling and manufacturing devices on the basis of parallel structures*, pages 221–242, Braunschweig, November, 10-11, 1998.
- [schoppe2002] Schoppe E. and others . Tripod machine SKM 400, design, calibration and practical applications. In 3rd Chemnitzer Parallelkinematik Seminar, pages 579–594, Chemnitz, April, 23-25, 2002.
- [schorr2017] Schorr S.B. and Okamura A.M. Three-dimensional skin deformation as force substitution: Wearable device design and performance during haptic exploration of virtual environments. *IEEE Trans. on Haptics*, 10(3):418–430, 2017.
- [schottler 2008] Schöttler K., Raatz A., and hesselbach J. Parallel manipulators, Towards new applications, chapter Size adapted parallel and hybrid parallel robot for sensor guided micro-assembly, pages 225–244. ITECH, April 2008. **Keywords:** planar robot, passive joints, 3 dof robot, 4 dof robot, micro robot, hybrid robot.
- [schreiber 2003] Schreiber H. and Gosselin C.M. Analyse et conception d'une manipulateur parallèle à cinq degré de liberté. *Mechanism and Machine Theory*, 38(6):535–548, June 2003.
- [schreiber 2018] Schreiber T. and Gosselin C.M. Kinematically redundant planar parallel mechanisms: Kinematics, workspace and trajectory planning. *Mechanism and Machine Theory*, 119:91–105, 2018.
- [schulz2017] Schulz S. and others . Sensor concept for solving the direct kinematics problem of the Stewart-Gough platform. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Vancouver, September, 24-28, 2017.
- [schulz2018] Schulz S., Seibel A., and Schlattmann J. Solution for the direct kinematics problem of the general Stewart-Gough platform by using only linear actuator orientations. In *ARK*, Bologna, July, 1-5, 2018.
- [schulz2019] Schulz S., Seible A., and Schlattmann J. Performance of an IMU-based sensor concept for solving the direct kinematics problem of the Stewart-Gough platform. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Macau, 2019.
- [schulz2019-1] Schulz S. On using inertial measurement units for solving the direct kinematics problem of parallel mechanisms. *Robotics*, November 2019.
- [schutz2010] Schütz D., Raatz A., and Hesselbach J. The development of a reconfigurable parallel robot with binary actuators. In ARK, pages 225–232, Piran, June 28- July 1, 2010.
- [schutz2012] Schütz D. and others . Type synthesis of binary actuated parallel mechanisms. In ARK, pages 131–138, Innsbruck, June, 25-28, 2012.

- [schutz2013] Schütz D., Raatz A., and Hesselbach J. Adapated task configuration of a reconfigurable binary parallel robot with PRRRP structure. *Robotica*, 31(2):285–293, March 2013.
- [schwaar2002] Schwaar M. and others . Mechatronic design, experimental property analysis and machining strategy for a 5-strut PKM. In 3rd Chemnitzer Parallelkinematik Seminar, pages 671–681, Chemnitz, April, 23-25, 2002.
- [sefrioui92] Sefrioui J. and Gosselin C. Singularity analysis and representation of planar parallel manipulators. *Robotics* and Autonomous Systems, 10(4):209–224, 1992.
- [sefrioui92-1] Sefrioui J. Problème géométrique direct et lieux de singularité des manipulateurs parallèles. Ph.D. Thesis, Université Laval, Québec, November, 2, 1992. **Keywords:** forward kinematics, singularity.
- [sefrioui94] Sefrioui J. and Gosselin C. Étude et représentation des lieux de singularités des manipulateurs parallèles sphériques à trois degrés de liberté avec actionneurs prismatiques. *Mechanism and Machine Theory*, 29(4):559–579, May 1994.
- [sefrioui95] Sefrioui J. and Gosselin C.M. On the quadratic nature of the singularity curves of planar three-degree-of-freedom parallel manipulators. *Mechanism and Machine Theory*, 30(4):533–551, May 1995.
- [seguchi86] Seguchi Y., Tanaka M., and others. Evolution of mast-type truss to robot arm. In *Japan-USA Symp. on Flexible Automation*, pages 251–259, Osaka, July, 14-18, 1986.
- [seguchi88] Seguchi Y., Tanaka M., and others. Motion and dynamics of flexible arm of a mast-type statically determinate truss. In *Int. Conf. on Computational Engineering Science*, pages 42.iii.1–42.iii.4, Atlanta, April, 10-14, 1988.
- [seguchi90] Seguchi Y., Tanaka M., and others . Dynamic analysis of a truss-type flexible robot arm.  $JSME\ Int.\ J.$ ,  $33(2):183-190,\ 1990.$
- [seguchi90-1] Seguchi Y., Tanaka M., and others. Criteria-oriented configuration control of adaptive structure and its modular neural network representation. In *First Joint USA/Japan Conf. on adaptive structure*, pages 402–421, Maui, Hawaii, November, 13-15, 1990.
- [seibold2005] Seibold U., Kübler B., and Hirzinger G. Prototype of instrument for minimally invasive surgery with 6-axis force sensing capability. In *IEEE Int. Conf. on Robotics and Automation*, pages 498–503, Barcelona, April, 19-22, 2005.
- [selfridge2000] Selfridge R.G. and Matthew G.K. Forward assembly of some special Stewart platforms. *J. of Robotic Systems*, 17(10):517–526, 2000.
- [selig99] Selig J.M. and McAree P.R. Constrained robot dynamics II: parallel machines. *J. of Robotic Systems*, 16(9):487–498, 1999.
- [selig2001] Selig J.M. and Ding X. Theory of vibrations in Stewart platforms. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2190–2195, Maui, Hawaii, October 29- November 3, 2001.
- [selig2008] Selig J.M. and Donelan P. A screw syzygy with applications to robot singularity computation. In ARK, pages 147–154, Batz/mer, June, 23-26, 2008.
- [selig2009] Selig J.M. and Li H. A geometric Newton-Raphson method for Gough-Stewart platform. In *Computational Kinematics*, pages 183–190, Duisburg, May, 6-8, 2009.
- [sellaouti2002] Sellaouti R., Konno A., and Ouezdou F.B. Design of a 3 DOFs parallel actuated mechanism for a biped hip joint. In *IEEE Int. Conf. on Robotics and Automation*, pages 1161–1166, Washington, May, 11-15, 2002.
- [sellaouti2005] Sellaouti R. and Ouezdou F.B. Design and control of a 3DOFs parallel actuated mechanism for biped application. *Mechanism and Machine Theory*, 40(12):1367–1393, December 2005.
- [sellet2019] Sellet H. and others . Active damping of parallel robots driven by flexible cables using cold-gas thrusters. In *IEEE Int. Conf. on Robotics and Automation*, Montréal, May, 20-24, 2019.

- [sellgren2002] Sellgren U. Modeling of mechanical interfaces in a systems context. In *Int. ANSYS Conf.*, Pittsburgh, April 2002.
- [sen-s-2003] Sen S., Dasgupta B., and Mallik A.K. Variational approach for singularity-path planning of parallel manipulators. *Mechanism and Machine Theory*, 38(11):1165–1183, November 2003.
- [sen98] Sen D. and Mruthyunjaya T.S. A centro-based characterization of singularities in the workspace of planar closed-loop manipulators. *Mechanism and Machine Theory*, 33(8):1091–1104, November 1998.
- [seo2013] Seo J-T. and others. Design of an antagonistically counter-balancing parallel mechanism. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Tokyo, November, 3-7, 2013.
- [seon2016] Seon J-A. and others . Cable configuration analysis to increase the rotational range of suspended 6-dof cable driven parallel robots. In 16th International Conference on Control, Automation and Systems (ICCAS), Gyeongju, October, 16-19, 2016.
- [sergiienko2016] Sergiienko N.Y., Cazzolato B.S., Ding B., and Arjomandi M. An optimal arrangement of mooring lines for the three-tether submerged point-absorbing wave energy converter. *Renewable Energy*, 93:27–37, 2016.
- [sergiu-dan2007] Sergiu-Dan S., Maties V., and Balan R. A multicriteria approach for the optimal design of 2 dof parallel robots used in construction applications. In *Int. Symp. on Automation and Robotics in Construction (ISARC)*, Madras, September, 19-21, 2007.
- [seriani2015] Seriani S., Seriani M., and Gallina P. Workspace optimization for a planar cable-suspended direct-driven robot. Robotics and Computer-Integrated Manufacturing, 34:1–7, August 2015.
- [seriani2015-1] Seriani S. and Gallina P. A storable tubular extensible member (STEM) parallel robot. *Mechanism and Machine Theory*, 90:95–107, 2015.
- [seriani2015phd] Seriani S. Large Workspace Robots. Ph.D. Thesis, University of Trieste, Trieste, 2015. **Keywords:** wire robot, applications.
- [seriani2016] Seriani S., Gallina P., and Wedler A. A modular cable robot for inspection and light manipulation on celestial bodies. *Acta Astronautica*, 123:145–153, 2016.
- [serracin2012] Serracin J.R. and others . Kinematic analysis of a novel 2-dof orientation device. Robotics and Autonomous Systems, 60(6):852-861, June 2012.
- [sevillano2008] Sevillano G. and others . Gait simulator based on the parallel Stewart-Gough platform. In 1st Conf. on Interdisciplinary Applications in Kinematics, Lima, January, 9-11, 2008.
- [shah2017] Shah M. N. and others . Forward kinematics modelling and verification of a 3-dof cable driven ankle rehabilitation robot. *International Journal of Mechanical & Mechatronics Engineering*, 17(3), June 2017.
- [shahidi2017] Shahidi S.A. and others . A survey on precision of redundantly actuated DELTA-type parallel kinematic mechanisms. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Vancouver, September, 24-28, 2017
- [shahinpoor92] Shahinpoor M. Kinematics of a parallel-serial (hybrid) manipulator. J. of Robotic Systems, 9(1):13–36, 1992.
- [shahmiri2016] Shahmiri F. and Gentry R. A survey of cable-suspended parallel robots and their applications in architecture and construction. In XX Congress of the Iberoamerican Society of Digital Graphics, Buenos Aires, November, 9-11, 2016.
- [shan2018] Shan X. and Cheng G. Structural error and friction compensation control of a 2(3PUS + S) parallel manipulator. *Mechanism and Machine Theory*, 124:92–103, 2018.
- [shang-w2014] Shang W. and Cong S. Robust nonlinear control of a planar 2-dof parallel manipulator with redundant actuation. *Robotics and Computer-Integrated Manufacturing*, 30(6):597–604, December 2014.
- [shang-w2015] Shang W. and Cong S. Dexterity and adaptive control of planar parallel manipulators with and without redundant actuation. ASME Journal of Computational and Nonlinear Dynamics, 10, January 2015.

- [shang-w2019] Shang W. and others . Synchronization control in the cable space for cable-driven parallel robots. IEEE Trans. on Industrial Electronics, 66(6):4544-4560, June 2019.
- [shang-w2020] Shang W. and others . Adaptive cross-coupled control of cable-driven parallel robots with model uncertainties. *IEEE Robotics and Automation Letters*, 5(3), 2020.
- [shang-w2020-1] Shang W. and others . Dual-space adaptive synchronization control of redundantly-actuated cable-driven parallel robots. *Mechanism and Machine Theory*, 152, 2020.
- [shang2012] Shang W-W., Cong S., and Ge Y. Adaptive computed torque control for a parallel manipulator with redundant actuation. *Robotica*, 30(3):457–466, April 2012.
- [shangying 2004] Shangying Z., Junwei H., and Hui Z. RCP and RT control of 6-dof parallel robot. In 4th Int. Workshop on Robot Motion and Control (RoMoCo), pages 133–137, Puszczykowo Poznan, June, 17-20, 2004.
- [shanker2012] Shanker V. and Bandyopadhyay S. Singular manifold of the general hexagonal Stewart platform manipulator. In ARK, pages 397–404, Innsbruck, June, 25-28, 2012.
- [shao-p2019] Shao P. and others . Dynamic modeling of a two-dof rotational parallel robot with changeable rotational axes. *Mechanism and Machine Theory*, 131:318–335, 2019.
- [shao2011] Z-F Shao and others . Driving force analysis for the secondary adjustable system in FAST. Robotica, 29(6):903-915, November 2011.
- [shareef2017] Shareef Z. and others . Design and control of cooperative ball juggling DELTA robots without visual guidance. *Robotica*, 35:384–400, 2017.
- [sharifinia2016] Sharifinia M. and Akbarzadeh A. Approximate analytical solution for vibration of a 3-PRP planar parallel robot with flexible moving platform. *Robotica*, 34(1):71–97, January 2016.
- [sharifzadeh2017] Sharifzadeh M. and others . An experimental study on the direct & indirect dynamic identification of an over-constrained 3-dof decoupled parallel mechanism. *Mechanism and Machine Theory*, 116:178–202, 2017.
- [sharifzadeh2018] Sharifzadeh M. and others . An experimental dynamic identification & control of an overconstrained 3-dof parallel mechanism in presence of variable friction and feedback delay. *Robotics and Autonomous Systems*, 102:27–43, 2018.
- [shaw2001] Shaw D. and Chen Y-S. Cutting path generation of the Stewart platform-based milling machine using an end-mill. *Int. J. Prod. Res.*, 39(7):1367–1383, 2001.
- [shayya2013] Shayya S. and others . A novel (3T-1R) redundant parallel mechanism with large operational workspace and rotational capability. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 436–443, Tokyo, November, 3-7, 2013.
- [shayya2014] Shayya S. and others . A novel (3T-2R) parallel mechanism with large operational workspace and rotational capability. In *IEEE Int. Conf. on Robotics and Automation*, pages 5712–5719, Hong-Kong, 7 November 31- June , 2014.
- [shayya2014-1] Shayya S. and others . Dynamic analysis of 4 degrees of freedom redundant parallel manipulator. In ARK, Ljulbjana, June 29- July 3, 2014.
- [shekarforoush2013] Shekarforoush S.M.M., Eghtesad M., and Farid M. Kinematic and static analyses of statically balanced spatial tensegrity mechanism with active compliant components. *J. of Intelligent and Robotic Systems*, 71(3-4):287–302, September 2013.
- [sheldon95] Sheldon P.C. Six axis machine tool, February, 14, 1995. United States Patent n° 5,388,935 Giddings & Lewis. **Keywords:** mechanical architecture,applications,machine-tool,patent.
- [sheldon96] Sheldon P.C. and others . Metrology instrument arm system, February, 6, 1996. United States Patent  $n^{\circ}$  5,489,168 Giddings & Lewis. **Keywords:** applications, patent.
- [shelef89] Shelef G. Six degree of freedom micromanipulator, April, 11, 1989. United States Patent n° 4,819,496 Air Force Washington. **Keywords:** mechanical architecture,6 dof robot,patent.

- [shen-h2005] Shen H. and others. Structure and analysis of a novel three-translation parallel mechanism. *Mechanism and Machine Theory*, 40(10):1181–1194, October 2005.
- [shen-h2016] Shen H. and others . The design methodology for fewer input—more output parallel mechanisms. *Mechanism and Machine Theory*, 104:43–58, 2016.
- [shen-h2017] Shen H. and Angeles J. Research on rolling parallel robot with hydraulic driven antiparallelogram chain. J. of Mechanisms and Robotics, 9(1), 2017.
- [shen-h2018] Shen H. and others . Design and direct position analysis of a new 3T1R parallel manipulator with low coupling degree. In *EUCOMES*, pages 333–339, Aachen, September, 4-6, 2018.
- [shen-h2020] Shen H. and others . Evaluation of topological properties of parallel manipulators based on the topological characteristic indexes. *Robotica*, 38:1381–1399, 2020.
- [shen-h2021] Shen H. and others. Kinematic sensitivity, parameter identification and calibration of a non-fully symmetric parallel Delta robot. *Mechanism and Machine Theory*, 161, July 2021.
- [shen-x2019] X. Shen and others . A smooth and undistorted toolpath interpolation method for 5-dof parallel kinematic machines. *Robotics and Computer-Integrated Manufacturing*, 57:347–356, 2019.
- [shen2002] Shen G. and others . A kinematic calibration of in-parallel actuated mechanisms using Fourier series (evaluation index for determination of the set of measurement paths). In ARK, pages 3–10, Caldes de Malavalla, June 29- July 2, 2002.
- [shi-h2014] Shi H., Duan X., and Su H-J. Optimization of the workspace of a mems hexapod nanopositioner using an adaptive genetic algorithm. In *IEEE Int. Conf. on Robotics and Automation*, pages 4043–4048, Hong-Kong, 7 July 31- June, 2014.
- [shi-j2011] Shi J., Li Z., and Wu Y. A new quantitative performance index for low mobility parallel kinematic manipulators' accuracy. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [shi-k2019] Shi K. and others . Cable-driven 4-dof upper limb rehabilitation robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Macau, 2019.
- [shi92] Shi X. and Fenton R.G. Solution to the forward instantaneous kinematics for a general 6 d.o.f. Stewart platform. Mechanism and Machine Theory, 27(3):251–259, May 1992.
- [shi92-1] Shi X. and Fenton R.G. Structural instabilities in platform-type parallel manipulators due to singular configurations. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 347–352, Scottsdale, September, 13-16, 1992.
- [shi94] Shi X. and Fenton R.G. A complete and general solution to the forward kinematics problem of platform-type robotic manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 3055–3062, San Diego, May, 8-13. 1994.
- [shiang2000] Shiang W-J., Cannon D., and Gorman J. Optimal force distribution applied to a robotic crane with flexible cables. In *IEEE Int. Conf. on Robotics and Automation*, pages 1948–1954, San Francisco, April, 24-28, 2000.
- [shiau2008] Shiau T-N., Tsai Y-J., and Tsai M-S. Nonlinear dynamic analysis of a parallel mechanism with consideration of joint effects. *Mechanism and Machine Theory*, 43(4):491–505, April 2008.
- [shihora2022] Shihora N. and Simaan N. Geometric insights into kinematically-singular configurations of planar continuum robots. In ARK, Bilbao, June, 26-30, 2022.
- [shim-hs2013] Shim H-S., Seo T., and Lee J.N. Optimal torque distribution methods for a redundantly actuated 3-RRR parallel robot using a geometrical approach. *Robotica*, 31(4):541–554, July 2013.
- [shim97] Shim J-H. and others . Kinematic design of a six degree-of-freedom in-parallel actuated manipulator for probing task. In *IEEE Int. Conf. on Robotics and Automation*, pages 2967–2973, Albuquerque, April, 21-28, 1997.

- [shim97-1] Shim J-H. and others . Kinematic feature analysis of a 6-degrees-of-freedom in-parallel manipulator for micro-positionning. In *IROS*, pages 1617–1623, Grenoble, September, 7-11, 1997.
- [shim99] Shim J.H., Kwon D.S., and Cho H.S. Kinematic analysis and design of a six D.O.F. 3-prps in-parallel manipulator. *Robotica*, 17(3):269–281, May 1999.
- [shin2011] Shin S. and others . Kinematic optimization for isotropic stiffness of redundantly actuated parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [shintemirov2016] Shintemirov A., Niyetkaliyev A., and Rubagotti M. Numerical optimal control of a spherical parallel manipulator based on unique kinematic solutions. *IEEE/ASME Trans. on Mechatronics*, 21(1):98–109, 2016.
- [shirazi2012] Shirazi A.R., Fakhrabadi M.M.S., and Ghanbari A. Optimal design of a 6-dof parallel manipulator using particle swarm optimization. *Advanced Robotics*, 26(13):1419–1441, 2012.
- [shirazi2014] Shirazi A.R., Fakhrabadi M.M.S., and Ghanbari A. Analysis and optimization of the 5-RPUR parallel manipulator. *Advanced Robotics*, 28(15):1021–1031, 2014.
- [shirkhodaie87] Shirkhodaie A.H. and Soni A.H. Forward and inverse synthesis for a robot with three degree-of-freedom. In 19th Summer Computer Simulation Conf., pages 851–856, Montréal, July, 27-30, 1987.
- [shoham2003] Shoham M. and others. Bone-mounted miniature robot for surgical procedures: concept and clinical applications. *IEEE Trans. on Robotics and Automation*, 19(5):893–901, October 2003.
- [shoham2005] Shoham M. Twisting wire actuator. ASME J. of Mechanical Design, 127(3):441-445, May 2005.
- [shoval2001] Shoval S. and Shoham M. Sensory redundant mobile mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 2275–2278, Seoul, May, 23-25, 2001.
- [shuai2020] Shuai F. and others. A new approach to enhance the stiffness of heavy-load parallel robots by means of the component selection. *Robotics and Computer-Integrated Manufacturing*, 61, 2020.
- [shukla92] Shukla D. and Paul F.W. Motion kinematics of serie-parallel robots using a virtual link concept. In 22nd Biennial Mechanisms Conf., pages 49–57, Scottsdale, September, 13-16, 1992.
- [shum2000] Shum J.C.F. and Zsombor-Murray P.J. Direct kinematics of the double-triangular manipulator: an exercise in geometry thinking. In ARK, pages 385–394, Piran, June, 25-29, 2000.
- [siciliano98] Siciliano B. A study on the kinematics of a class of parallel manipulators. In ARK, pages 29–38, Strobl, June 29- July 4, 1998.
- [siciliano99] Siciliano B. The Tricept robot: inverse kinematics, manipulability analysis and closed-loop direct kinematics algorithm. *Robotica*, 17(4):437–445, July 1999.
- [siciliano2005] Siciliano B., Villani L., and Caccavale F. Kinematics, dynamics and control for a class of parallel robots. In 2nd Int. Colloquium, Collaborative Research Centre 562, pages 109–121, Braunschweig, May, 10-11, 2005.
- [sika98] Šika S., Kočandrle P., and Stejskal V. An investigation of properties of the forward displacement analysis of the generalized Stewart platform by the mean of general optimization method. *Mechanism and Machine Theory*, 33(3):245–253, April 1998.
- [silva2005] Silva L.A. and others . Robotenis: optimal design of a parallel robot with high performance. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Edmonton, August, 2-6, 2005.
- [silver95] Silver R.M., Potzick J., and Hu Y-C. Metrology with the ultraviolet scanning transmission microscope. In *Proc. of the SPIE, Integrated circuit metrology, inspection and process control*, pages 437–445, Santa Clara, February, 20-22, 1995.
- [simaan98] Simaan N. and others . Design considerations of new six degrees-of-freedom parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 1327–1333, Louvain, May, 18-20, 1998.
- [simaan99] Simaan N. Analysis and synthesis of parallel robots for medical applications. Master's thesis, Technion-Israel Institute of Technology, Haifa, 1999. **Keywords:** applications,6 dof robot,medical.

- [simaan2000] Simaan N. and Shoham M. Remarks on "hidden" lines in parallel robots. In ARK, Piran, June, 25-29, 2000.
- [simaan2001] Simaan N. and Shoham M. Singularity analysis of a class of composite serial in-parallel robots. *IEEE Trans. on Robotics and Automation*, 17(3):301–311, June 2001.
- [simaan2002] Simaan N. and Shoham M. Stiffness synthesis of a variable geometry planar robot. In ARK, pages 463–472, Caldes de Malavalla, June 29- July 2, 2002.
- [simaan2003] Simaan N. and Shoham M. Stiffness synthesis of a variable geometry six-degree-of-freedom double planar parallel robot. *Int. J. of Robotics Research*, 22(9):757–775, September 2003.
- [simaan2003-1] Simaan N. and Shoham M. Geometric interpretation of the derivatives of parallel robots' jacobian matrix with application to stiffness control. ASME J. of Mechanical Design, 125(1):33–42, March 2003.
- [simas2019] Simas H. and Di Gregorio R. Position analysis, singularity loci and workspace of a novel 2PRPU Schöenflies-motion generator. *Robotica*, 37:141–160, 2019.
- [simas2022] Simas H., Simoni R., and Di Gregorio R. Wriflex: design and kinematic analysis of a self-aligning parallel wrist. In ARK, Bilbao, June, 26-30, 2022.
- [simionescu2006] Simionescu I. and Ciupitu L. Optimum design of 6-dof Stewart platforms. In 1st Int. Conf. Optimization of Robots and Manipulators, OPTIROB, Predeal, May, 26-28, 2006.
- [simoni2009] Simoni R., Piga Carboni A., and Martins D. Enumeration of parallel manipulators. *Robotica*, 27(4):589–597, July 2009.
- [simoni2013] Simoni R. and others . Symmetry and invariants of kinematic chains and parallel manipulator. *Robotica*, 31(1):61–70, January 2013.
- [simoni2019] Simoni R. and others . Design and kinematic analysis of a 6-DOF foldable/deployable Delta parallel manipulator with spherical wrist for an I-AUV. In *OCEANS 2019*, Marseille, 2019.
- [sinatra2002] Sinatra R. A different kinematic model of the Tricept robot. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [sinatra2008] Sinatra R. and Xi F. Parallel manipulators, Towards new applications, chapter Dynamics of hexapods with fixed-length legs, pages 245–268. ITECH, April 2008. **Keywords:** dynamics, balancing.
- [sincarsin87] Sincarsin W.G. and Hughes P.C. Trussarm : candidate geometries. Research Report 28-611/0401, Dynacon Enterprises Ltd., 1987.
- [singh2015] Singh Y. and others . Inverse dynamics and control of a 3-DOF planar parallel (U-shaped 3-PPR) manipulator. *Robotics and Computer-Integrated Manufacturing*, 34:164–179, August 2015.
- [singh2015-1] Singh Y. and Santhakumar M. Inverse dynamics and robust sliding mode control of a planar (2-PRP and 1-PPR) robot augmented with a nonlinear disturbance observer. *Mechanism and Machine Theory*, 92:29–50, 2015.
- [sirouspour 2001] Sirouspour M.R. and Salcudean S.E. Nonlinear control of a hydraulic parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3760–3765, Seoul, May, 23-25, 2001.
- [sirouspour2001-1] Sirouspour M.R. and Salcudean S.E. Nonlinear control of hydraulic robots. *IEEE Trans. on Robotics and Automation*, 17(2):173–182, April 2001.
- [sisodiya2017] Sisodiya M.S. Optimization of joints and links in planar parallel robot mechanisms. *International Journal of Advances in Scientific Research and Engineering*, 13(4), May 2017.
- [six2017] Six D. and others. A controller avoiding dynamic model degeneracy of parallel robots during singularity crossing. J. of Mechanisms and Robotics, 9(5), October 2017.
- [six2018] Six D. and others . The kinematics, dynamics and control of a flying parallel robot with three quadrotors.  $IEEE\ Robotics\ and\ Automation\ Letters,\ 3(1),\ January\ 2018.$

- [six2018-phd] Six D. Conception et commande de robots parallèles volants. Ph.D. Thesis, Ecole Centrale de Nantes, Nantes, December, 4, 2018. **Keywords:** wire robot, applications.
- [sklar88] Sklar M. and Tesar D. Dynamic analysis of hybrid serial manipulator system containing parallel modules. J. of Mechanisms, Transmissions and Automation in Design, 110(2):109–115, June 1988.
- [skopect2016] Skopect T., Sika Z., and Valasek M. Calibration using adaptive model complexity for parallel and fiber-driven mechanisms. *Robotica*, 34(6):1416–1435, June 2016.
- [slavutin2020] Slavutin M. and Reich Y. Singularity analysis of some multi-platform mechanisms by decomposition and reciprocality. *Mechanism and Machine Theory*, 146, 2020.
- [slutski96] Slutski L. Closed plane mechanisms as a basis of parallel manipulator. In ARK, pages 441–450, Portoroz-Bernadin, June, 22-26, 1996.
- [smartee93] STX Hughes. Smartee, 1993. Technical Note, Hughes STX Corporation, 4400 Forbes Bvd,Lanham, MD 20706,USA. **Keywords:** mechanical architecture,6 dof robot,hardware.
- [smith91] Smith III W.F. and Nguyen C.C. Mechanical analysis and design of a six-degree-of-freedom robotic wrist for Space assembly. In *Proc. 23th South Eastern Symp. on System*, pages 177–181, Columbia, March, 10-12, 1991.
- [smith91-1] Smith III W.F. and Nguyen C.C. On the mechanical design of a Stewart platform-based robotics endeffector. In *IEEE Proc. of the Southeast Conf'91*, pages 875–879, Williamsburg, April, 7-10, 1991.
- [smits2020] Smits J. and others . Synthesis and methodology for optimal design of a parallel remote center of motion mechanism: Application to robotic eye surgery. *Mechanism and Machine Theory*, 151, 2020.
- [snyman2000] Snyman J.A. and Hay A.M. The chord method for the determination of non-convex workspaces of planar parallel platforms. In ARK, pages 285–294, Piran, June, 25-29, 2000.
- [snyman2000-1] Snyman J.A., Du Plessis L.J., and Duffy J. An optimisation approach to the determination of the boundaries of manipulator workspaces. ASME J. of Mechanical Design, 122(4):447–456, December 2000.
- [snyman2002] Snyman J.A. and Smit W.J. The optimal design of a planar parallel platform for prescribed machining tasks. *Multibody System Dynamics*, 8(2):103–115, 2002.
- [snyman2005] Snyman J.A. and Hay A.M. Optimal synthesis for a continuous prescribed dexterity interval of a 3-dof parallel planar manipulator for different prescribed output workspaces. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [so2003] So B.R. and others . Design of a redundantly actuated leg mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 4348–4353, Taipei, September, 14-19, 2003.
- [sokolov2005] Sokolov A. and Xirouchakis P. Kinematics of a 3-dof parallel manipulator with an P-R-S joint structure. *Robotica*, 23(2):207–217, March 2005.
- [sokolov2006] Sokolov A. and Xirouchakis P. Singularity analysi of a 3-dof parallel manipulator with R-P-S joint structure. *Robotica*, 24(1):131–142, January 2006.
- [sokolov2007] Sokolov A. and Xirouchakis P. Dynamic analysis of a 3-dof parallel manipulator with R-P-S structure. Mechanism and Machine Theory, 42(5):541–557, May 2007.
- [solazzi2004] Sloazzi M. and others . Kinematic analysis and singularity loci of a 4-UPU parallel manipulator. In ARK, Ljulbjana, June 29- July 3, 2014.
- [son2017] Son N.N. and others . A novel adaptive feed-forward-pid controller of a scara parallel robot using pneumatic artificial muscle actuator based on neural network and modified differential evolution algorithm. *Robotics and Autonomous Systems*, 96:65–80, 2017.
- [song-se-2010] Song S-E. and others . Development of a pneumatic robot for MRI-guided transperineal prostate biopsy and brachytherapy: New approaches. In *IEEE Int. Conf. on Robotics and Automation*, pages 2580–2585, Anchorage, May, 3-8, 2010.

- [song-sk-2001] Song S.K. and Kwon D-S. New methodology for the forward kinematics of 6-dof parallel manipulators using tetrahedron configurations. In *IEEE Int. Conf. on Robotics and Automation*, Seoul, May, 23-25, 2001.
- [song-sk-2002] Song S.K. and Kwon D-S. New direct kinematics formulation of 6-dof Stewart-Gough platform using the tetrahedron approach. *Trans. on Control, Automation and System Engineering*, 4(3):217–223, September 2002.
- [song-sk-2012] Song S.K. and Kwon D-S. New direct kinematic formulation of a 6 d.o.f. Stewart-Gough platform using the tetrahedron approach. *Trans. on Control, Automation and System Engineering*, 4(2):217–223, September 2012.
- [song-x2019] Song X. and others. Dynamic feedforward control in decoupling space for a four-degree-of-freedom parallel robot. *International Journal of Advanced Robotic Systems*, 2019.
- [song-y2007] Song Y., Li Y., and Huang T. Inverse dynamics of 3-RPS parallel mechanism based on virtual work principle. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [song-y2014] Song Y. and others . A novel five-degree-of-freedom parallel manipulator and its kinematic optimization. J. of Mechanisms and Robotics, 6, November 2014.
- [song-y2018] Song Y. and others. Type synthesis of 1T2R and 2R1T parallel mechanisms employing conformal geometric algebra. *Mechanism and Machine Theory*, 121:475–486, 2018.
- [song-y2020] Song Y. and others. Dynamic characteristic prediction of a 5-dof hybrid machine tool by using scale model considering the geometric distortion of bearings. *Mechanism and Machine Theory*, 145, 2020.
- [song-y2020-1] Song Y., Kang X., and Dai J.S. Instantaneous mobility analysis using the twist space intersection approach for parallel mechanisms. *Mechanism and Machine Theory*, 151, 2020.
- [song98] Song J.I. and others. Nonlinear friction compensation methods for an in-parallel actuated 6-d.o.f. manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 169–174, Louvain, May, 18-20, 1998.
- [soni95] Soni A.H., Tanasi G.C., and Varanasi S. Closed-loop multi-degree freedom mechanisms for surface generation and patching in machining 3d surfaces. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 2668–2674, Milan, August 30- September 2, 1995.
- [sorli93] Sorli M. and Ceccarelli M. On the workspace of a 6 d.o.f. platform with three articulated double-parallelograms. In *ICAR*, pages 147–152, Tokyo, November, 1-2, 1993.
- [sorli93-1] Sorli M. and Zhmud' N. Investigation of force and moment measurement system for a robotic assembly hand. Sensors and Actuators A, 37-38:651–657, July August , 1993.
- [sorli95] Sorli M. and others. Mechanics of Turin parallel robot. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1880–1885, Milan, August 30- September 2, 1995.
- [sorli95-1] Sorli M. and Pastorelli S. Six-axis reticulated structure force/torque sensor with adaptable performances. *Mechatronics*, 5(6):585–601, September 1995.
- [sorli97] Sorli M. and others . Mechanics of Turin parallel robot. *Mechanism and Machine Theory*, 32(1):51–77, January 1997.
- [sovizi2014] Sovizi J. and others . Random matrix based uncertainty model for complex robotic systems. In *IEEE Int. Conf. on Robotics and Automation*, pages 4049–4054, Hong-Kong, 7 January 31- June , 2014.
- [sovizi2018] Sovizi J. and others. Wrench uncertainty quantification and reconfiguration analysis in loosely interconnected cooperative systems. ASCE-ASME Journal of Risk and Uncertainty in Engineering Systems, Part B: Mechanical Engineering, 4(2), 2017.
- [spagnuolo2018] Spagnuolo G. and others . Kinetostatic characterization of a loading system based on a partially-decoupled parallel manipulator. In ARK, Bologna, July, 1-5, 2018.
- [spanos95] Spanos J., Rahman Z., and Blackwood G. A soft 6-axis active vibration isolator. In *American Control Conf.*, pages 412–416, Seattle, June, 21-23, 1995.

- [spanoudakis2000] Spanoudakis P. and others . Extremely high-resolution tip-tilt-piston mirror mechanism for the VLT-NAOS field selector. In SPIE Symp. on Astronomical Telescope & Instrumentation, Munchen, March 2000.
- [spencer2008] Spencer S.J. and others. A low cost parallel robot and trajectory optimization method for wrist and forearm rehabilitation using the Wii. In 2nd Biennial IEEE/RAS-EMBS Int. Conf. Biomedical Robotics and Biomechatronics, Scottsdale, October, 19-22, 2008.
- [sreenivasan92] Sreenivasan S.V. and Nanua P. Solution of the direct position kinematics problem of the general Stewart platform using advanced polynomial continuation. In 22nd Biennial Mechanisms Conf., pages 99–106, Scottsdale, September, 13-16, 1992.
- [sreenivasan94] Sreenivasan S.V., Waldron K.J., and Nanua P. Closed-form direct displacement analysis of a 6-6 Stewart platform. *Mechanism and Machine Theory*, 29(6):855–864, August 1994.
- [sridhar2017] Sridhar D. and Williams II R.L. Kinematics and statics including cable sag for large cable suspended robots. Global Journal of Researches in Engineering: H Robotics & Nano-Tec, 17(1), 2017.
- [srivatsan2013] Srivatsan R.A. and Bandyopadhyay S. On the position kinematics analysis of MaPaMan, a reconfigurable three-degree-fof-freedom spatial parallel manipulator. *Mechanism and Machine Theory*, 62:159–165, April 2013.
- [srivatsan2013-1] Srivatsan R.A., Bandyopadhyay S., and Ghosal A. Analysis of the degrees-of-freedom of spatial parallel manipulators in regular and singular configurations. *Mechanism and Machine Theory*, 69:127–141, 2013.
- [srivatsan2014] Srivatsan R.A. and Bandyopadhyay S. Analysis of constraint equations and their singularities. In ARK, Ljulbjana, June 29- July 3, 2014.
- [staffetti2000] Staffetti E. and Thomas F. Kinestatic analysis of serial and parallel robot manipulators using Grassman-Cayley algebra. In ARK, pages 17–36, Piran, June, 25-29, 2000.
- [staffetti2002] Staffetti E., Bruyninckx H., and De Schutter J. On the invariance of manipulability indices. In ARK, pages 57–66, Caldes de Malavalla, June 29- July 2, 2002.
- [staffettti2004] Staffetti E. Kinestatic analysis of robot manipulators using the Grassmann-Cayley algebra. *IEEE Trans. on Robotics and Automation*, 20(2):200–210, April 2004.
- [staicu2003] Staicu S. and Carp-Ciocardia D.C. Dynamic analysis of Clavel's Delta parallel robot. In *IEEE Int. Conf.* on Robotics and Automation, pages 4116–4121, Taipei, September, 14-19, 2003.
- [staicu2006] Staicu S., Zhang H., and Rugesu R. Dynamic modelling of a 3-dof parallel manipulator using recursive matrix relations. *Robotica*, 24(1):125–130, January 2006.
- [staicu2007] Staicu S. Dynamics of a  $3 \underline{R}RR$  spherical parallel mechanism based on principle of virtual powers. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [staicu2008] Staicu S. and Zhang D. A novel dynamic modelling approach for parallel mechanisms analysis. *Robotics and Computer-Integrated Manufacturing*, 24(1):167–172, February 2008.
- [staicu2009] Staicu S. Recursive modelling in dynamics of Delta parallel robot. Robotica, 27(2):199–207, March 2009.
- [staicu2009-1] Staicu S. Dynamics analysis of the Star parallel manipulator. *Robotics and Autonomous Systems*, 57(11):1057–1064, November 2009.
- [staicu2009-2] Staicu S. Inverse dynamics of the 3-PRR parallel manipulator. *Robotics and Autonomous Systems*, 57(5):556–563, May 2009.
- [staicu2009-3] Staicu S. Recursive modelling in dynamics of Agile Wrist spherical parallel robot. *Robotics and Computer-Integrated Manufacturing*, 25(2):409–416, April 2009.
- [staicu2009-4] Staicu S. Dynamics of the spherical  $3-U\underline{P}S/S$  parallel mechanism with prismatic actuators. *Multibody System Dynamics*, 22:115–132, 2009.

- [staicu2011] Staicu S. Dynamics of the 6-6 Stewart parallel manipulator. Robotics and Computer-Integrated Manufacturing, 27(1):212–220, February 2011.
- [staicu2012] Staicu S. Matrix modeling of inverse dynamics of spatial and planar parallel robots. *Multibody System Dynamics*, 27:239–265, 2012.
- [staicu2015] Staicu S. Dynamics modelling of a Stewart-based hybrid parallel robot. Advanced Robotics, 29(14):929–938, 2015.
- [staicu2018] Staicu S. and others . Kinematic analysis of the X4 translational—rotational parallel robot. *International Journal of Advanced Robotic Systems*, 2018.
- [stamper97] Stamper R.C., Tsai C-W., and Walsh G.C. Optimization of a three dof translational platform for well-conditionned workspace. In *IEEE Int. Conf. on Robotics and Automation*, pages 3250–3255, Albuquerque, April, 21-28, 1997.
- [stan2008] Stan S-D. and others . A novel virtual reality robot interface for Isoglide3 parallel robot. In *ICIRA*, pages 1265–1275, Wuhan, October, 15-17, 2008.
- [stan2008-1] Stan S-D., Maties V., and Balad R. Parallel manipulators, Towards new applications, chapter Optimal design of parallel kinematic machines with 2 degrees of freedom, pages 295–320. ITECH, April 2008. **Keywords:** 2 dof robot, optimal design.
- [stan2088-2] Stan S-D. and others . Kinematics analysis, design, and control of an Isoglide3 parallel robot (IG3PR). In 34th Annual Conference of IEEE Industrial Electronics, pages 2636–2641, 2008.
- [stechert2007] Stechert C. and Franke H-J. Requirement oriented configuration of parallel robotic systems, chapter 4, pages 259–268. Springer, 2007. **Keywords:** modular robot, optimal design.
- [stechert2007-1] Stechert C., Pavlovic N., and Franke H-J. Parallel robots with adaptronic components Design through different knowledge domains. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [stengele2002] Stengele G. CROSS HULLER SPECH Xperimental, a machining center with new hybrid kinematics. In 3rd Chemnitzer Parallelkinematik Seminar, pages 607–627, Chemnitz, April, 23-25, 2002.
- [sternheim87] Sternheim F. Computation of the direct and inverse geometric models of the Delta 4 parallel robot. *Robotersysteme*, 3(4):199–203, 1987.
- [sternheim88] Sternheim F. Tridimensionnal computer simulation of a parallel robot. Results for the Delta 4 machine. In 18th Int. Symp. on Industrial Robots (ISIR), pages 333–340, Lausanne, April, 26-28, 1988.
- [stevens94] Stevens B.S. and Clavel R. The Delta parallel robot, its future in industry. In *ISRAM*, pages 273–278, Hawaï, August, 15-17, 1994.
- [stewart65] Stewart D. A platform with 6 degrees of freedom. *Proc. of the Institution of mechanical engineers*, 180(Part 1, 15):371–386, 1965.
- [stigger2018] Stigger T., Pfurner M., and Husty M. Workspace and singularity analysis of a 3-RUUU parallel manipulator. In *EUCOMES*, pages 325–332, Aachen, September, 4-6, 2018.
- [stigger2018-1] Stigger T. and others . Algebraic analysis of a 3-RUU parallel manipulator. In ARK, Bologna, July, 1-5, 2018.
- [stigger2019] Stigger T. and others . Analysis of a  $3-\underline{R}UU$  parallel manipulator using algebraic constraints. Mechanism and Machine Theory, 136:256–268, 2019.
- [stocco96] Stocco L. and Salcudean T. A coarse-fine approach to force-reflecting hand controller design. In *IEEE Int. Conf. on Robotics and Automation*, pages 404–410, Minneapolis, April, 24-26, 1996.
- [stocco2001] Stocco L. and Salcudean T. Optimal kinematic design of a haptic pen. *IEEE/ASME Trans. on Mechatronics*, 6(3):210–220, September 2001.

- [stock2003] Stock M. and Miller K. Optimal kinematic design of spatial parallel manipulators: application to linear Delta robot. ASME J. of Mechanical Design, 125(2):292–301, June 2003.
- [stoeffler2022] Stoeffler C. and others . Kinematic analysis of a novel humanoid wrist parallel mechanism. In ARK, Bilbao, June, 26-30, 2022.
- [stoica2012] Stoica A. and others. Workspace and singularity analysis for a parallel robot used in surgical operation. In 4th European Conf. on Mechanism Science (Eucomes), pages 149–158, Santander, September, 19-21, 2012.
- [stojanovic2016] Stojanovic V. and Nedic N. A nature inspired parameter tuning approach to cascade control for hydraulically driven parallel robot platform. *J Optim Theory Appl*, 168:332–347, 2016.
- [stoltmann2018] Stoltmann M. and others . Flatness-based feedforward control of a crane manipulator with four load chains. In *EUCOMES*, pages 61–68, Aachen, September, 4-6, 2018.
- [stone98] Stone W.C. and Pfeffer L.E. Automation infrastructure system for a robotic 30-ton bridge crane. In *American Society of Civil Engineers Conf.*, pages 195–201, Albuquerque, April, 26-30, 1998.
- [stoughton87] Stoughton R. and Kokkinis T. Some properties of a new kinematic structure for robot manipulators. In ASME Design Automation Conf., pages 73–79, Boston, June, 28, 1987.
- [stoughton91] Stoughton R. and Arai T. Kinematic optimization of a chopsticks-type micromanipulator, 1991. **Keywords:** mechanical architecture,optimal design,micro robot,design.
- [stoughton91-1] Stoughton R. and Arai T. Optimal sensor placement for forward kinematics evaluation of a 6-dof parallel link manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems*, (*IROS*), pages 785–790, Osaka, November, 3-5, 1991.
- [stoughton93] Stoughton R. and Arai T. Kinematic optimization of a chopsticks-type micro-manipulator. In *Japan-USA Symp. on Flexible Automation*, pages 151–157, San Fransisco, July, 13-15, 1993.
- [stoughton93-1] Stoughton R. and Arai T. A modified Stewart platform manipulator with improved dexterity. *IEEE Trans. on Robotics and Automation*, 9(2):166–173, April 1993.
- [stoughton94] Stoughton R. and others . A redundant, 6-DOF parallel manipulator structure with improved workspace and dexterity. In *ISRAM*, pages 577–581, Hawaï, August, 15-17, 1994.
- [stump2006] Stump E. and Kumar V. Workspaces of cable-actuated parallel manipulators. ASME J. of Mechanical Design, 128(1):159–167, January 2006.
- [su-hj-2003] Su H-J., Dietmaier P., and J.M. McCarthy. Trajectory planning for constrained parallel manipulators. *ASME J. of Mechanical Design*, 125(4):709–716, December 2003.
- [su-hj-2005] Su H-J. and J.M. McCarthy. Dimensioning a constrained parallel robot to reach a set of task positions. In *IEEE Int. Conf. on Robotics and Automation*, pages 4037–4041, Barcelona, April, 19-22, 2005.
- [su-t2018] Su T. and others . Time-optimal trajectory planning for Delta robot based on quintic Pythagorean-Hodograph curves. *IEEE Access*, 2018.
- [su-y2015] Su Y., Quiu Y., and Liu P. The continuity and real-time performance of the cable tension determining for a suspend cable- driven parallel camera robot. *Advanced Robotics*, 291(12):743–752, 2015.
- [su-yx-2001-1] Su Y.X. and others . Development of a large parallel-cable manipulator for the feed-supporting system of a next-generation large radio telescope. J. of Robotic Systems, 18(11):633-643, 2001.
- [su-yx-2001-2] Su Y.X. and others . Genetic design of kinematically optimal fine tuning Stewart platform for large spherical radio telescope. *Mechatronics*, 11(7):821–835, 2001.
- [su-yx-2004] Su Y.X. and others. Disturbance-rejection high-precision motion control of a Stewart platform. *IEEE Trans. on Control Systems Technology*, 12(3):364–374, May 2004.
- [su-yx-2005] Su Y.X. and others . Non-linear PD synchronized control for parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1386–1391, Barcelona, April, 19-22, 2005.

- [su2001] Su X.S. and others . A real coded genetic optimal kinematic design of a Stewart fine tuning platform for a large radio telescope. *J. of Robotic Systems*, 18(9):507–516, 2001.
- [su2002] Su X.S. and others . Singularity analysis of a 6 DOF Stewart platform using genetic algorithm. In *Int. Conf. on Systems, Man and Cybernetics*, volume 7, Hammamet, October, 6-9, 2002.
- [su2003] Su X.S. and others . Singularity analysis of fine-tuning Stewart platform for large radio telescope using genetic algorithm. *Mechatronics*, 13(5):413–425, June 2003.
- [subramaniam92] Subramaniam M. and Kramer S.N. The inverse kinematic solution of the tetrahedron based variable geometry truss manipulator. ASME J. of Mechanical Design, 114(3):433–437, September 1992.
- [subrin2013] Subrin K. and others. New redundant architectures in machining: Serial and parallel robots. *Procedia Engineering*, 61:158–166, 2013.
- [such2009] Such M. and others . An approach based on the catenary equation to deal with static analysis of three dimensional cable structures. *Engineering structures*, 31(9):2162–2170, 2009.
- [sugahara2003] Suguhara Y. and others . Control and experiments of a multi-purpose bipedal locomotor with parallel mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 4342–4347, Taipei, September, 14-19, 2003.
- [sugar2002] Sugar T.G. and Kumar V. Design and control of a compliant parallel manipulator. ASME J. of Mechanical Design, 124(4):676–683, December 2002.
- [sugimoto82] Sugimoto K., Duffy J., and Hunt K.H. Special configurations of spatial mechanisms and robot arms. Mechanism and Machine Theory, 17(2):119–132, 1982.
- [sugimoto87] Sugimoto K. Kinematic and dynamic analysis of parallel manipulators by means of motor algebra. J. of Mechanisms, Transmissions and Automation in Design, 109(1):3–7, March 1987.
- [sugimoto88] Sugimoto K. Computational scheme for dynamic analysis of parallel manipulators. In ASME Proc. of the 20th Biennial Mechanisms Conf., pages 341–351, Kissimmee, Orlando, September, 25-27, 1988.
- [sugimoto89] Sugimoto K. Computational scheme for dynamic analysis of parallel manipulators. *J. of Mechanisms*, Transmissions and Automation in Design, 111(1):29–33, March 1989.
- [sui2003] Sui C. and others . Stiffness study on a 6-dof parallel wire driven robot. In 11th ICAR, pages 1787–1792, Coimbra, June 30- July 3, 2003.
- [sujan2004] Sujan V.A. and Dubowsky S. Design of lightweight hyper-redundant deployable binary manipulator. ASME J. of Mechanical Design, 126(1):29–39, January 2004.
- [sumpter85] Sumpter B. and Soni A.H. Simulation algorithm of Oklahoma Crawdad robot. In 9th Applied Mechanisms Conf., pages VI.1–VI.3, Kansas City, January, 28-30, 1985.
- [sun-d2006"] Sun D. and others . Synchronous tracking control of parallel manipulators using cross-coupling approach. *Int. J. of Robotics Research*, 25(11):1137–1147, November 2006.
- [sun-g2021] Sun G. and others. Direct method for tension feasible region calculation in multi-redundant cable-driven parallel robots using computational geometry. *Mechanism and Machine Theory*, 158, 2021.
- [sun-h2020] Sun H. and others . Dynamic modeling and error analysis of a cable-linkage serial-parallel palletizing robot.  $IEEE\ Access$ , 2020.
- [sun-h2020-1] Sun H. and others . Dynamic response of spatial flexible structures subjected to controllable force based on cable-driven parallel robots.  $IEEE/ASME\ Trans.\ on\ Mechatronics,\ 25(6),\ December\ 2020.$
- [sun-h2021] Sun H. and others. Research on the configuration of cable-driven parallel robots for vibration suppression of spatial flexible structures. Aerospace Science and Technology, 109, 2021.
- [sun-x2020] Sun X. and others . Integrated design, fabrication, and experimental study of a parallel micro-nano positioning-vibration isolation stage. *Robotics and Computer-Integrated Manufacturing*, 66, 2020.

- [sun2016] Sun T. and others . Kinematic calibration of a 3-dof rotational parallel manipulator using laser tracker. Robotics and Computer-Integrated Manufacturing, 41:78–91, 2016.
- [sun2016-1] Sun T., Lian B., and Song Y. Stiffness analysis of a 2-dof over-constrained rpm with an articulated traveling platform. *Mechanism and Machine Theory*, 96:165–178, 2016.
- [sun2018] Sun T. and Lian B. Stiffness and mass optimization of parallel kinematic machine. *Mechanism and Machine Theory*, 120:73–88, 2018.
- [sun2018-1] Sun T., Lian D., and Song Y. Singular-perturbation-based nonlinear hybrid control of redundant parallel robot. *IEEE Trans. on Industrial Electronics*, 66(4), 2018.
- [sun2019] Sun T. and Yang S. An approach to formulate the hessian matrix for dynamic control of parallel robots. *IEEE/ASME Trans. on Mechatronics*, 24(1), February 2019.
- [sun2020] Sun T. and others. Kinematic calibration of serial and parallel robots based on finite and instantaneous screw theory. *IEEE Trans. on Robotics*, 36(3), June 2020.
- [sunkari2006] Sunkari R.P. and Schmidt L.C. Structural synthesis of planar kinematic chains by adapting McKay-type algorithm. *Mechanism and Machine Theory*, 41(9):1021–1030, September 2006.
- [surdilovic2004] Surdilovic D. and Bernhardt R. STRING-MAN: a new wire robot for gait rehabilitation. In *IEEE Int. Conf. on Robotics and Automation*, pages 2031–2036, New Orleans, April, 28-30, 2004.
- [surdilovic2012] Surdilovic D., Radojicic D., and Krüger J. Geometric stiffness analysis of wire-robotsl a mechanical approach. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [surdilovic2014] Surdilovic D., Radijicic J., and Bremer N. Efficent calibration of cable-driven parallel robots with variable structure. In 2nd Int. Conf. on cable-driven parallel robots (CableCon), Duisburg, August, 24-27, 2014.
- [sutter92] Sutter T.R. and others . Structural characterization of a first generation articulated truss joint for space crane application. Research Report TM 4371, NASA Research Center, Langley, June 1992.
- [suzumori94] Suzumori K. Fma hand. Advanced Robotics, 8(6):607, December 1994.
- [svinin2000] Svinin M.M., Ueda K., and Uchiyama M. On the stability conditions for a class of parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 2386–2391, San Francisco, April, 24-28, 2000.
- [svinin2001] Svinin M., Hosoe S., and Uchiyama M. On the stability and stabilizability of elastically suspended rigid bodies. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 155–166. EJCK, May, 20-22, 2001. **Keywords:** stiffness,control.
- [svinin2001-1] Svinin M., Hosoe S., and Uchiyama M. On the stiffness and stability of Gough-Stewart platforms. In *IEEE Int. Conf. on Robotics and Automation*, pages 3268–3273, Seoul, May, 23-25, 2001.
- [szatmari99] Szatmari S. Geometrical errors of parallel robots. *Periodica Polytechnica Ser Mech Eng*, 43(2):155–162, 1999.
- [szilaghyi2012] Szilaghyi A. and others . Kinematic analysis of a parallel surgical robot. In ARK, pages 333–340, Innsbruck, June, 25-28, 2012.
- [taban85] Taban V. and Soni A.H. Design and programming of a lobster arm robot. In 9th Applied Mechanisms Conf., pages V.1–V.6, Kansas City, January, 28-30, 1985.
- [tadakuma2008] Tadakuma K. and others . The experimental study of a precision parallel manipulator with binary actuation: With application to MRI cancer treatment. In *IEEE Int. Conf. on Robotics and Automation*, pages 2503–2508, Pasadena, May, 19-23, 2008.
- [tadjari2017] Tadjari F. and others . Robust control of a 3-dof parallel cable robot using an adaptive neuro-fuzzy inference system. In Artificial Intelligence and Robotics (IRANOPEN), 2017.
- [tadokoro94] Tadokoro S. Control of parallel mechanisms. Advanced Robotics, 8(6):559–571, December 1994.

- [tadokoro94-1] Tadokoro S. A 6 d.o.f. parallel robot wrist joint by a pneumatic actuator drive. *Advanced Robotics*, 8(6):603, December 1994.
- [tadokoro96] Tadokoro S. and others . On fundamental design of wire configuration of wire driven parallel manipulators with redundancy. In *Japan-USA Symp. on Flexible Automation*, pages 151–158, Boston, July, 7-10, 1996.
- [tadokoro2001] Tadokoro S. and others . A parallel cable-driven motion base for virtual acceleration. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Maui, Hawaii, October 29- November 3, 2001.
- [tadokoro2002] Tadokoro S. and others . A motion base with 6-dof by parallel cable driven architecture. IEEE/ASME Trans. on Mechatronics, 7(2):115–123, June 2002.
- [tadokoro99] Tadokoro S. and others . A portable parallel manipulator for search and rescue at large-scale urban earthquakes and an identification algorithm for the installation in unstructured environments. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1222–1227, Kyongju, October, 17-21, 1999.
- [taghavi2012] Taghavi M. and others . Workspace improvement of two-link cable-driven mechanims with spring cables. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [taghavi2017] Taghavi M. and others . Cable-driven parallel robot for curtain wall modules automatic installation. In 34th Int. Symp. on Automation and Robotics in Construction, Taipei, 2018.
- [taghavi2018] Taghavi M. and others . Development of a modular end-effector for the installation of curtain walls with cable-robots. J. of Facade Design & Engineering, 6(2), 2018.
- [taghirad2008] Taghirad H.D. and Nahon M.A. Dynamic analysis of a macro-micro redundantly actuated parallel manipulator. *Advanced Robotics*, 22(9):949–981, 2008.
- [taghirad2011] Taghirad H.D. and Bedoustani Y.D. An analytic-iterative redundancy resolution scheme for cable-driven redundant parallel manipulator. *IEEE Trans. on Robotics*, 27(6):670–676, December 2011.
- [taherifar2016] Taherifar A. and others . Inverse forward dynamics of N-3RPS manipulator with lockable joints. *Robotica*, 34(6):1383–1402, June 2016.
- [tahmasebi91] Tahmasebi F. and Tsai L.-W. Closed form direct kinematics solution of a new parallel minimanipulator. Research Report TR91-92, University of Maryland, 1991.
- [tahmasebi94] Tahmasebi F. and Tsai L.-W. Closed form direct kinematics solution of a new parallel minimanipulator. ASME J. of Mechanical Design, 116(4):1141–1147, December 1994.
- [tahmasebi94-1] Tahmasebi F. and Tsai L.-W. Workspace and singularity analysis of a novel six-dof parallel minimanipulator. J. of Applied Mechanisms and Robotics, 1(2):31–40, March 1994.
- [tahmasebi94-2] Tahmasebi F. and Tsai L.-W. Simplified and symmetrical five-bar linkage driver for manipulating a six-degree-of-freedom parallel minimapulator with three inextensible limbs, April, 12, 1994. United States Patent n° 5,301,566, US Army. **Keywords:** 6 dof robot,patent.
- [tahri2007] Tahri O. and others . Omnidirectional visual-servo of a Gough-Stewart platform. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1326–1331, San Diego, September, 22-26, 2007.
- [tahri2009] Tahri O. and others . Omnidirectional visual-servo of a Gough-Stewart platform. *IEEE Trans. on Robotics*, 25(1):178–183, February 2009.
- [taikawa2003] Takaiwa M. and Noritsugu T. Development of force displaying device using pneumatic parallel manipulator and application to palpation motion. In *IEEE Int. Conf. on Robotics and Automation*, pages 4098–4103, Taipei, September, 14-19, 2003.
- [takaiwa2005] Takaiwa M. and Noritsugu T. Development of wrist rehabilitation equipment using pneumatic parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 2313–2318, Barcelona, April, 19-22, 2005.
- [takamasu99] Takamasu K. and others . Development of nano-CMM and parallel-CMM, CMM in the 21th century. In *Int. Dimensional Metrology Workshop*, Tennessee, May, 10-13, 1999.

- [takanobu92] Takanobu H. and others . Bio-parallel mechanism of mastication robot. In *IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems*, pages 487–492, Kobe, September, 16-20, 1992.
- [takanobu2000] Takanobu H. and others . Mouth opening and closing training with 6-dof parallel robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 1384–1389, San Francisco, April, 24-28, 2000.
- [takanobu2001] Takanobu H. and others . Remote therapy with mouth opening and closing training robot between Tokyo and Yamanashi 120 km. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1584–1589, Maui, Hawaii, October 29- November 3, 2001.
- [takeda93] Takeda Y., Funabashi H., and Sasaki Y. Analysis of working space and motion transmissibility of spherical in-parallel actuated mechanism. In *ICAR*, pages 165–170, Tokyo, November, 1-2, 1993.
- [takeda2002] Takeda Y., Shen G., and Funabashi H. A DBB-based kinematic calibration method for in-parallel actuated mechanisms using a Fourier series. In *ASME Design Engineering Technical Conference*, Montréal, September 29- October 2, 2002.
- [takeda2004] Takeda Y. and others. An in-parallel actuated manipulator with redundant actuators for gross and fine motion. In *IEEE Int. Conf. on Robotics and Automation*, pages 749–754, New Orleans, April, 28-30, 2004.
- [takeda2005] Takeda Y. Kinematic analysis of parallel mechanisms at singular points at which a connecting chain has local mobility. In *Computational Kinematics*, Cassino, May, 4-6, 2005.
- [takeda2005-1] Takeda Y. and others. Development of position-orientation decoupled spatial in-parallel actuated mechanisms with six degrees of freedom. J. of Robotics and Mechatronics, 17(1):59–68, February 2005.
- [takeda2012] Takeda Y. and others . Orientation capability of a 3-RPSR parallel mechanism for a movable-die drive mechanism of pipe bender. In ARK, pages 253–260, Innsbruck, June, 25-28, 2012.
- [takemura2004] Takemura F. and others . Proposition of a human body searching strategy using a cable-driven robot at major disaster. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Sendai, September 28-October 2, 2004.
- [takemura2005] Takemura F. and others. Development of the balloon-cable driven robot for information collection from sky and proposal of the search strategy at a major disaster. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 658–663, Monterey, July, 24-28, 2005.
- [takemura2005-1] Takeda Y. and others . A human body searching strategy using a cable-driven robot with an electromagnetic wave direction finder at major disasters. *Advanced Robotics*, 19(3):331–347, 2005.
- [takemura2006] Takeda Y., Maeda K., and Tadokoro S. Attitude stability of a cable driven balloon robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3504–3509, Beijing, October, 9-15, 2006.
- [talemasouleh2010] Tale Masouleh M., Husty M., and Gosselin C. Forward kinematic problem of  $5-\underline{P}RUR$  parallel mechanism using Study parameters. In ARK, pages 211–221, Piran, June 28- July 1, 2010.
- [talemasouleh2010-1] Tale Masouleh M. and others . Forward kinematic problem and constant orientation workspace of 5-RPRR (3T2R) parallel mechanisms. In 18th Iranian Conf. on Electrical Engineering, 2010.
- [talemasouleh2011] Tale Masouleh M. and others . Forward kinematic problem of  $5 R\underline{P}UR$  parallel mechanisms (3T2R) with identical limb structure. *Mechanism and Machine Theory*, 46(7):945–959, July 2011.
- [talemasouleh2011-1] Tale Masouleh M. and others . Kinematic analysis of 5-RPUR (3T2R) parallel mechanisms. Meccanica, 46:131-146, 2011.
- [talke2018] Talke K.A., De Oiveira M., and Bewley T. Catenary tether shape analysis for a UAV USV team. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Madrid, October, 1-5, 2018.
- [tan2013] Tan D-P., Ji S-M., and M-S. Jin. Intelligent computer-aided instruction modeling and a method to optimize study strategies for parallel robot instruction. *IEEE Trans. on Education*, 56(3), August 2013.
- [tanaka-w2002] Tanaka W. and others . Simplified kinematic calibration for a class of parallel mechanism. In *IEEE Int. Conf. on Robotics and Automation*, pages 483–488, Washington, May, 11-15, 2002.

- [tanaka-w2003] Tanaka W. and others . Calibration method by simplified measurement for parallel mechanism. In 11th ICAR, pages 1781–1786, Coimbra, June 30- July 3, 2003.
- [tanaka-w2006] Tanaka W. and others . Calibration method for parallel mechanism using micro-grid pattern. In *IEEE Int. Conf. on Robotics and Automation*, pages 763–768, Orlando, May, 16-18, 2006.
- [tanaka88] Tanaka M. Motion and dynamics of flexible arm of a mast-type statically determinate truss. In *Proc. Computational Mechanics '88, Theory and Applications*, pages 42.iii.1–42.iii.4, Atlanta, GA, USA, April, 10-14, 1988.
- [tanaka90] Tanaka M. and others . Motion/configuration control of a truss-type parallel manipulator with redundancy. In *Japan-USA Symposium on Flexible Automation*, pages 329–336, ISCIE, Kyoto, 1990.
- [tanaka90-1] Tanaka M., Seguchi Y., and others . Kinematics of adaptive truss permitting nodal offset (configuration and workspace reach). In *First Joint USA/Japan Conf. on adaptive structure*, pages 691–714, Maui, Hawaii, November, 13-15, 1990.
- [tanaka92] Tanaka M. and Hanahara K. Simulation study of dynamic properties and nodal offset of truss-type parallel mechanism. In *IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems*, pages 445–450, Kobe, September, 16-20, 1992.
- [tanaka94] Tanaka M. Large-scaled framed structure as parallel mechanism with hyper-redundancy. *Advanced Robotics*, 8(6):573–587, December 1994.
- [tanaka94-1] Tanaka M. Truss-type mechanism. Advanced Robotics, 8(6):599, December 1994.
- [tanase2012] Tanase I. and others . Workspace identification with neural network for an optimal designed 2-dof orientation parallel device. In 4th European Conf. on Mechanism Science (Eucomes), pages 159–167, Santander, September, 19-21, 2012.
- [tancredi94] Tancredi L. and Merlet J-P. Evaluation of the errors when solving the direct kinematics of parallel manipulators with extra sensors. In Lenarčič J. and Ravani B., editors, ARK, pages 439–448, Ljubljana, July, 4-6, 1994. Springer Verlag.
- [tancredi95] Tancredi L., Teillaud M., and Merlet J-P. Extra sensors data for solving the forward kinematics problem of parallel manipulators. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 2122–2126, Milan, August 30- September 2, 1995.
- [tancredi95-1] Tancredi L., Teillaud M., and Merlet J-P. Forward kinematics of a parallel manipulator with additional rotary sensors measuring the position of platform joints. In J-P. Merlet B. Ravani, editor, *Computational Kinematics*, pages 261–270. Kluwer, September, 4-6, 1995.
- [tancredi95-phd] Tancredi L. De la simplification et la résolution du modèle géométrique direct des robots parallèles. Ph.D. Thesis, École des Mines de Paris, Sophia, December, 20, 1995. **Keywords:** kinematics,forward kinematics with redundant sensors.
- [tancredi96] Tancredi L., Teillaud M., and Devillers O. Symbolic elimination for parallel manipulators. Research Report 2809, INRIA, February 1996.
- [tancredi99] Tancredi L. and Teillaud M. Application de la géométrie synthétique au problème de modélisation géométrique directe des robots parallèles. *Mechanism and Machine Theory*, 34(2):255–269, February 1999.
- [tanev98] Tanev T.K. Forward displacement analysis of a three legged four-degree-of-freedom parallel manipulator. In ARK, pages 147–154, Strobl, June 29- July 4, 1998.
- [tanev2002] Tanev T.K. and Rooney J. Rotation symmetry axes and the quality index in a 3D octahedral parallel robot manipulator system. In ARK, pages 29–38, Caldes de Malavalla, June 29- July 2, 2002.
- [tanev2006] Tanev T.K. Singularity analysis of a 4-dof parallel manipulator using geometric algebra. In ARK, pages 275–284, Ljubljana, June, 26-29, 2006.
- [tanev2008] Tanev T.K. Geometric algebra approach to singularity of parallel manipulators with limited mobility. In ARK, pages 39–48, Batz/mer, June, 23-26, 2008.

- [tang-l2014] Tang L. and others . Dynamic trajectory planning of planar two-dof redundantly actuated cable-suspended parallel robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Chicago, September, 14-18, 2014.
- [tang-l2020] Tang L. and others . Singularity analysis on a special class of cable-suspended parallel mechanisms with pairwise cable arrangement and actuation redundancy. ASME J. of Mechanical Design, 142, February 2020.
- [tang-t2020] Tang T., Fang H., and Zhang J. Hierarchical design, laboratory prototype fabrication and machining tests of a novel 5-axis hybrid serial-parallel kinematic machine tool. *Robotics and Computer-Integrated Manufacturing*, 64, 2020.
- [tang-t2021] Tang T. and others. Chebyshev inclusion function based interval kinetostatic modeling and parameter sensitivity analysis for Exechon-like parallel kinematic machines with parameter uncertainties. *Mechanism and Machine Theory*, 157, 2021.
- [tang-t2021-1] Tang T. and others. Type synthesis, unified kinematic analysis and prototype validation of a family of Exechon inspired parallel mechanisms for 5-axis hybrid kinematic machine tools. *Robotics and Computer-Integrated Manufacturing*, 72, 2021.
- [tang2002] Tang X., Yin W., and Wang J. A study of the accuracy of a novel 4-dof hybrid machine tool. In 3rd Chemnitzer Parallelkinematik Seminar, pages 509–523, Chemnitz, April, 23-25, 2002.
- [tang2011] Tang X. and Yao R. Dimensional design of the six-cable driven parallel manipulator of FAST. ASME J. of Mechanical Design, 133(11):111012–1/11, November 2011.
- [tang2014] Tang X. and othrs . Accuracy synthesis of a multi-level hybrid positioning mechanism for the feed support system in FAST. Robotics and Computer-Integrated Manufacturing, 30(5):565–575, October 2014.
- [tangxq2008] Tang X.Q. and Huang P. Parallel manipulators, Towards new applications, chapter The analysis and application of parallel manipulator for active reflector of FAST, pages 321–346. ITECH, April 2008. **Keywords:** 3 dof robot, applications.
- [tanikawa99] Tanikawa T. and Arai T. Development of a micro-manipulation system having a two-fingered micro-hand. *IEEE Trans. on Robotics and Automation*, 15(1):152–162, February 1999.
- [tannous 2014] Tannous M., Caro S., and Goldsztejn A. Sensitivity analysis of parallel manipulators using an interval linearization method. *Mechanism and Machine Theory*, 71:93–114, January 2014.
- [taosun2016] Tao-Sun G.M. and others . Mobility analysis and kinematic synthesis of a novel 4-dof parallel manipulator. *Robotica*, 34(5):1010–1025, May 2016.
- [tarao2000] Tarao S., Inohira E., and Uchiyama M. Motion simulation using a high-speed parallel link mechanism. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Takamatsu, Japan, October 30- November 5, 2000.
- [tari2012] Tari H., Su H-J., and Hauenstein D. Classification and complete solution of the kinetostatics of a compliant Stewart–Gough platform. *Mechanism and Machine Theory*, 49:177=186, March 2012.
- [tavolieri2008] Tavolieri C., Ceccarelli M., and Merlet J-P. A workspace analysis of a fully constrained cable-based parallel manipulator by using interval analysis. In *Musme*, San Juan, Argentina, April, 8-12, 2008.
- [tavolieri2008-phd] Tavolieri C. Design of a cable-based parallel manipulator for rehabilitation applications. Ph.D. Thesis, University of Cassino, Cassino, October, 20, 2008. **Keywords:** wire robot, applications.
- [tchon2012] Tchoń K. and ohers . Motion planning for parallel robots with non-holonomic joints. In ARK, pages 115–122, Innsbruck, June, 25-28, 2012.
- [tchon2014] Tchoń K. and Jakubiak J. Motion planning of non-holonomic parallel orienting platform: a jacobian approach. In ARK, pages 95–103, Ljulbjana, June 29- July 3, 2014.
- [teague95] Teague E.C. 1/n Feynman machines as a path to ultraminiaturisation? In *Proc. of the SPIE Conf. Microlitography and Metrology in MicroMachining*, pages 82–88, Austin, October, 23-24, 1995.

- [tempel2015] Tempel P., Schnelle F., Pott A., and Eberhard P. Design and programming for cable-driven parallel robots in the german pavilion at the expo 2015. *Machines*, 3(3):223–241, 2015.
- [tempel2017] Tempel P. and others. Estimating inertial parameters of suspended cable-driven parallel robots; use case on CoGiRo. In *IEEE Int. Conf. on Robotics and Automation*, pages 6093–6098, Singapore, 2017.
- [tempel2018] Tempel P., Trautwein F., and Pott A. Experimental identification of stress-strain material models of UHMWPE fiber cables for improving cable tension control strategies. In ARK, Bologna, July, 1-5, 2018.
- [tengfei2019] Tengfei T. and Jun Z. Conceptual design and kinetostatic analysis of a modular parallel kinematic machine-based hybrid machine tool for large aeronautic components. *Robotics and Computer-Integrated Manufacturing*, 57:1–16, 2019.
- [tesar89] Tesar D. and Butler M.S. A generalized modular architecture for robot structures. *Manufacturing review*, 2(2), June 1989.
- [thanh2012] Thanh D., T and others. Dynamics identification of kinematically redudnant parallel robot using the direct search method. *Mechanism and Machine Theory*, 55:104–121, September 2012.
- [thayer98] Thayer D. and Vagners J. A look at the pole/zero structure of a Stewart platform using special coordinate basis. In *American Control Conference*, pages 1165–1169, Philadelphia, June, 24-26, 1998.
- [theingi2007] Theingi and others . Management of parallel-manipulator singularities using joint-coupling. Advanced Robotics, 21(5-6):583-600, 2007.
- [thomas-u2002] Thomas U., Maciuszek I., and Wahl F.M. A unified notation for serial, parallel, and hybrid kinematic structures. In *IEEE Int. Conf. on Robotics and Automation*, pages 2868–2873, Washington, May, 11-15, 2002.
- [thomas 2002] Thomas F. and others. Uncertainty model and singularities of 3-2-1 wire-based tracking systems. In ARK, pages 107–116, Caldes de Malavalla, June 29- July 2, 2002.
- [thomas 2004] Thomas F. Solving geometric constraints by iterative projections and backprojections. In *IEEE Int. Conf. on Robotics and Automation*, pages 1789–1794, New Orleans, April, 28-30, 2004.
- [thomas 2020-mv] Thomas M. J., Joy M. L., and Sudheer A. P. Kinematic and dynamic analysis of a 3-PRUS spatial parallel manipulator. *Chinese J. of Mechanical Engineering*, 33(1):13, February 2020.
- [thompson96] Thompson C.J. and Campbell P.D. Tendon suspended platform robot, December, 17, 1996. United States Patent n° 5,585,707, McDonnel Douglas Corporation. **Keywords:** wire robot,applications,simulator,patent.
- [thornton88] Thornton G.S. The GEC Tetrabot-a new serial-parallel assembly robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 437–439, Philadelphia, April, 24-29, 1988.
- [thurneysen2002] Thurneysen M. and others . A new parallel kinematics for high-speed machine tools Hita STT. In 3rd Chemnitzer Parallelkinematik Seminar, pages 553–562, Chemnitz, April, 23-25, 2002.
- [tian-c2019] Tian C., Fang Y., and Ge Q.J. Design and analysis of a partially decoupled generalized parallel mechanism for 3T1R motion. *Mechanism and Machine Theory*, 140:211–232, 2019.
- [tian-c2020] Tian C. and Zhang D. A new family of generalized parallel manipulators with configurable moving platforms. *Mechanism and Machine Theory*, 153:211–232, 2020.
- [tian-c2021] Tian C. and others . Structure synthesis of reconfigurable generalized parallel mechanisms with configurable platforms. *Mechanism and Machine Theory*, 160, 2021.
- [tian-h2017] Tian H. and others . A 6-dof parallel bone-grinding robot for cervical disc replacment surgery. *Med Biol Eng Comput*, 55:2107–2121, 2017.
- [tian-hb2019] Tian H-B. and others . Stiffness analysis of a metamorphic parallel mechanism with three configurations. Mechanism and Machine Theory, 142, 2019.
- [tian2016] Tian W. and others . Kinematic calibration of a 3-DOF spindle head using a double ball bar. *Mechanism and Machine Theory*, 102:167–178, 2016.

- [tian2017] Tian Y. and others . A reconfigurable multi-mode mobile parallel robot. *Mechanism and Machine Theory*, 111:39–65, 2017.
- [tian2020] Tian W. and others . A systematic approach for accuracy design of lower-mobility parallel mechanism. *Robotica*, pages 2173–2188, 2020.
- [ting-y93] Ting Y., Tosunoglu S., and Freeman R. Actuator saturation avoidance for fault tolerant robot. In 32nd Conf. on Decision and Control, pages 2125–2130, San Antonio, December, 15-17, 1993.
- [ting-y2004] Ting Y. and others . Modeling and control for a Gough-Stewart platform CNC machine. In *IEEE Int. Conf. on Robotics and Automation*, New Orleans, April, 28-30, 2004.
- [ting85] Ting K.L. and Tsai G.H. Mobility and synthesis of five-bar programmable linkages. In 9th Applied Mechanisms Conf., pages III.1–III.8, Kansas City, October 1985.
- [tischler98] Tischler C.R. and Samuel A.E. Predicting the slop of in-series/parallel manipulators caused by joint clearances. In ARK, pages 227–236, Strobl, June 29- July 4, 1998.
- [tischler2001] Tischler C.R., Andrew S., and Hunt K.H. Selecting multi-freedom multi-loop kinematic chain to suit a given task. *Mechanism and Machine Theory*, 36(8):925–938, August 2001.
- [titus2017] Titus A.B., Narayanan T., and Das G.P. Vision system for coconut farm cable robot. In *International Conference on Smart Technologies and Management for Computing, Communication, Controls, Energy and Materials (ICSTM)*, 2017.
- [tognon2018-phd] Tognon M. Theory and Applications for Control and Motion Planning of Aerial Robots in Physical Interaction with particular focus on Tethered Aerial Vehicles. Ph.D. Thesis, Université de Toulouse, Toulouse, July 2018. **Keywords:** applications, wire robot, aerial.
- [tol2002] Tol U.A., Clerc J-P., and Wiens G.J. Micro-macro approach for dexterity enhancement of PKM's. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, pages 34–39, Québec, October, 3-4, 2002.
- [tonai90] Tonai S. and Matsushita S. Parallel link robot arm, September, 7, 1990. United States Patent n° 4,946,337. **Keywords:** planar robot, patent, mechanical architecture, 2 dof robot.
- [tong2018] Tong Y. and He J. Dynamics and force regulation of fully constrained cable-driven parallel mechanism as a marine salvage device. In *Int. Conf. of Intelligent Robotic and Control Engineering (IRCE)*, 2018.
- [tong2020] Tong Y., Gosselin C., and Jiang H. Dynamic decoupling analysis and experiment based on a class of modified Gough-Stewart parallel manipulators with line orthogonality. *Mechanism and Machine Theory*, 143, 2020.
- [tonshoff98] Tönshoff K., Grendel H., and Kaak R. A hybrid manipulator for laser machining. In First European-American Forum on Parallel Kinematic Machines, Milan, August 31- September 1, 1998.
- [tonshoff98-1] Tönshoff K., Grendel H., and Schmidt A. A hybrid manipulator structure for laser machining. In 12th RoManSy, pages 343–350, Paris, July, 6-9, 1998.
- [tonshoff98-2] Tönshoff K., Günther G., and Grendel H. Vergleiche betrachtung paralleler und hybrider Strukturen. In New machine concepts for handling and manufacturing devices on the basis of parallel structures, pages 249–270, Braunschweig, November, 10-11, 1998.
- [tonshoff2002] Tönshoff K., Grendel H., and Grotjahn M. Modelling and control of linear direct driven hexapod. In 3rd Chemnitzer Parallelkinematik Seminar, pages 335–350, Chemnitz, April, 23-25, 2002.
- [tonshoff2002-1] Tönshoff K. and others . Modelling of error effects on the new hybrid kinematic DUMBO structure. In 3rd Chemnitzer Parallelkinematik Seminar, pages 639–653, Chemnitz, April, 23-25, 2002.
- [tooyama2000] Tooyama T. and others . Development of parallel mechanism based milling machine HexaM. In 2nd Chemnitzer Parallelkinematik Seminar, pages 331–341, Chemnitz, April, 12-13, 2000.
- [torras2006] Torras C., Thomas F., and Alberich-Carraminana M. Stratifying the singularity loci of a class of parallel manipulators. *IEEE Trans. on Robotics*, 22(1), February 2006.

- [torresmendez2017] Torres-Medez S.J. and others. Analytical workspace delineation of a translational underconstrained cable-based robot. In *International Conference on Electronics, Communications and Computers (CONIELECOMP)*, 2017.
- [tosi2010] Tosi D. and others . Cheope: A new reconfigurable redundant manipulator. Mechanism and Machine Theory, 45(4):611-626, 2010.
- [tourajizadeh2016] Tourajizadeh H. and Manteghi S. Design and optimal control of dual-stage Stewart platform using feedback-linearized quadratic regulator. *Advanced Robotics*, 30:1305–1321, 2016.
- [tourajizadeh2016-1] Tourajizadeh H. and Korayem M.H. Optimal regulation of a cable suspended robot equipped with cable interfering avoidance controller. *Advanced Robotics*, 30:1273–1287, 2016.
- [tourajizadeh2020] Tourajizadeh H. and Gholami O. Optimal control and path planning of a 3PRS robot using indirect variation algorithm. *Robotica*, 38:903–924, 2020.
- [toyama93] Toyama O., Uchiyama M., and Pierrot F. Parallel robot, March, 26, 1993. United States Patent n° 5,333,514, Toyoda. **Keywords:** mechanical architecture,patent.
- [toyoda2000] Kaisha Toyoda Kokikabushiki, Pierrot F., and Company O. Four degree of freedom parallel robot, September, 18, 2000. European Patent n° EP 1 084 802 A2. **Keywords:** patent,4 dof robot.
- [toz2013] Toz M. and Kucuc S. Dextrous workspace optimization of an asymmetric six-degree-of-freedom Stewart-Gough platform type manipulator. *Robotics and Autonomous Systems*, 12(12):1516–1528, December 2013.
- [toz2014] Toz M. and Kucuc S. Dimensional optimization of 6-dof 3-CCC type asymmetric parallel manipulator. Advanced Robotics, 28:625–637, 2014.
- [toz2015] Toz M. and Kucuc S. Parallel manipulator software tool for design, analysis, and simulation of 195 GSP mechanisms. *Computer applications in Engineering Education*, 23(6):931–946, November 2015.
- [traslosheros 2007] Traslosheros A. and others . Visual servoing using a parallel robot: preliminary results. In IEEE/ASME international conference on advanced intelligent mechatronics, Zurich, 2007.
- [traslosheros2007-1] Traslosheros A. and others . Visual servoing of a parallel robot system. In *IEEE International Symposium on Intelligent Signal Processing*, Alcala de Henares, 2007.
- [traslosheros2010] Traslosheros A. and others . One camera in hand for kinematic calibration of a parallel robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Taipei, October, 18-22, 2010.
- [traslosheros 2011] Traslosheros A. and others . Visual servoing for the Robotenis system: a strategy for a 3 dof parallel robot to hit a ping-pong ball. In *IEEE Conference on Decision and Control and European Control Conference*, Orlando, 2011.
- [trautwein2018] Trautwein F., Tempel P., and Pott A. A symbolic-numeric method to capture the impact of varied geometrical parameters on the translational workspace of a planar cable-driven parallel robot. In *ReMAR*, Delft, June, 20-22, 2018.
- [trawny2009] Trawny N. and others . 3D relative poste estimation from six distances. In *Robotics: Science and Systems*, Seattle, June 2009.
- [treib98] Treib T., Meier P., and Hebsacker M. Wachstumgesetzmässigkeiten und einstazpotentiale parallel-kinematischer manipulatoren. In *New machine concepts for handling and manufacturing devices on the basis of parallel structures*, pages 81–94, Braunschweig, November, 10-11, 1998.
- [treib2002] Treib T. Parallel kinematic machines in practice. In 3rd Chemnitzer Parallelkinematik Seminar, pages 63–66, Chemnitz, April, 23-25, 2002.
- [trevisani2006] Trevisani A., Gallina P., and Williams II R.L. Cable-direct-driven robot (CDDR) with passive SCARA support: Theory and simulation. *J. of Intelligent and Robotic Systems*, 46:73–94, 2006.
- [trevisani2012] Trevisani A. Experimental validation of a trajectory planning approach avoiding cable slackness and excessive tension in underconstrained translational planar cable-driven robots. In 1st Int. Conf. on cable-driven parallel robots (CableCon), pages 23–40, Stuttgart, September, 3-4, 2012.

- [trinkle2002] Trinkle J.C. and R.J. Milgram. Complete path planning for closed kinematic chains with spherical joints. *Int. J. of Robotics Research*, 21(9):773–789, September 2002.
- [tsai-ky2003] Tsai K-Y. and Huang K.D. The design of isotropic 6-DOF parallel manipulators using isotropy generators. *Mechanism and Machine Theory*, 38(11):1199–1214, November 2003.
- [tsai-ky2006] Tsai K-Y. and Lin J.C. Determining the compatible orientation workspace of Stewart-Gough parallel manipulators. *Mechanism and Machine Theory*, 41(10):1168–1184, October 2006.
- [tsai-ky2007] Tsai K-Y. and Lee T.K. 6-dof isotropic parallel manipulators with three PPSR or PRPS chains. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [tsai-ky2008] Tsai K-Y., Lin P.Y., and Lee T.K. 4R and 5R parallel manipulators that can reach maximum number of isotropic positions. *Mechanism and Machine Theory*, 43(1):68–79, January 2008.
- [tsai-ky2009] Tsai K-Y. and Lee T.K. 6-dof parallel manipulators with better dexterity, rotability, or singularity-free workspace. *Robotica*, 27(4):599–606, July 2009.
- [tsai-ky2014] Tsai K-Y., Lin J.C., and Lo Y. Six-dof parallel manipulators with maximal singularity-free joint space or workspace. *Robotica*, 32(3):401–411, May 2014.
- [tsai-ky2014-1] Tsai K-Y., Lo I-T., and Lin P.J. Compatible reachable workspaces of symmetrical Stewart-Gough parallel manipulators. *Mechanism and Machine Theory*, 77:111–121, 2014.
- [tsai-ms2003] Tsai M-S. and others . Direct kinematic analysis of a 3-PRS parallel mechanism. *Mechanism and Machine Theory*, 38(1):71–83, January 2003.
- [tsai-ms2010] Tsai M-S. and Yuan W-H. Inverse dynamics analysis for a 3-PRS parallel mechanism based on a special decomposition of the reaction forces. *Mechanism and Machine Theory*, 45(11):1491–1508, November 2010.
- [tsai-tc2004] Tsai T-C. and Hsu Y-L. Development of a parallel surgical robot with automatic bone drilling carriage for stereotactic neurosurgery. In *Int. Conf. on Systems, Man and Cybernetics*, The Hague, October, 10-13, 2004.
- [tsai93] Tsai L-W. and Tahmasebi F. Synthesis and analysis of a new class of six-degree-of-freedom parallel minimanipulators. *J. of Robotic Systems*, 10(5):561–580, July 1993.
- [tsai96] Tsai L-W., Walsh G.C., and Stamper R.E. Kinematics of a novel three dof translational platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 3446–3451, Minneapolis, April, 24-26, 1996.
- [tsai96-1] Tsai L-W. Kinematics of a three-dof platform with three extensible limbs. In ARK, pages 401–410, Portoroz-Bernadin, June, 22-26, 1996.
- [tsai98] Tsai L-W. The jacobian analysis of a parallel manipulator using reciprocal screws. In ARK, pages 327–336, Strobl, June 29- July 4, 1998.
- [tsai98-1] Tsai L-W. The jacobian analysis of a parallel manipulator using reciprocal screws. Research Report 98-34, ISR, University of Maryland, 1998.
- [tsai2000] Tsai L-W. Solving the inverse dynamics of a Stewart-Gough manipulator by the principle of virtual work. ASME J. of Mechanical Design, 122(1):3–9, March 2000.
- [tsai2000-1] Tsai L-W. and Joshi S. Kinematics and optimization of a spatial 3-UPU parallel manipulator.  $ASME\ J.$  of  $Mechanical\ Design,\ 112(4):439-446$ , December 2000.
- [tsai2001] Tsai L-W. and Joshi S. Comparison study of architectures of four 3 degree-of-freedom translational parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1283–1288, Seoul, May, 23-25, 2001.
- [tsai2002] Tsai L-W. and Joshi S. Kinematic analysis of 3-dof position mechanisms for use in hybrid kinematic machines. ASME J. of Mechanical Design, 124(2):245–253, June 2002.
- [tsumaki2012] Tsumaki Y., Ono F., and Tsukuda T. The 20-dof miniature humanoid MH-2, a wearable communication system. In *IEEE Int. Conf. on Robotics and Automation*, pages 3930–3935, Saint Paul, May, 14-18, 2012.

- [tsumaki2012-1] Tsumaki Y., Eguchi H., and Tsukuda T. A novel Delta-type parallel mechanism with wire-pulley. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1567–1572, Vilamoura, October, 7-12, 2012.
- [tsumaki2014] Tsumaki Y. and others . Ultra-light forearm with a parallel wrist mechanism. In *IEEE/ASME Int. Conf. on Advanced Intelligent Mechatronics*, pages 1419–1423, Besancon, July, 8-11, 2014.
- [tu2018] Tu Y. and others. Optimal design of SINS's Stewart platform bumper for restoration accuracy based on genetic algorithm. *Mechanism and Machine Theory*, 124:42–54, 2018.
- [tucan2017] Tucan P. and others . Development of a control system for an innovative parallel robot used in prostate biopsy. In *IInt. Conf. on Control Systems and Computer Science*, 2017.
- [tunc2016] Tunc L.T. and Shaw J. Investigation of the effects of Stewart platform-type industrial robot on stability of robotic milling. The International Journal of Advanced Manufacturing Technology, pages 189–199, 2016.
- [tzafestas2002] Tzafestas S., Kostis M., and Pimenides T. Observer-based optimal control of flexible Stewart parallel robots. J. of Intelligent and Robotic Systems, 34(2):489–503, August 2002.
- [uchida2011] Uchida T. and McPhee J. Triangularizing kinematic constraint equations using gröbner bases for real-time dynamic simulation. *Multibody System Dynamics*, 25:335–356, 2011.
- [uchiyama92] Uchiyama M. and others . Design and control of a very fast 6 d.o.f. parallel robot. In *IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems*, pages 473–478, Kobe, September, 16-20, 1992.
- [uchiyama94] Uchiyama M. Structures and characteristics of parallel manipulators. *Advanced Robotics*, 8(6):545–557, December 1994.
- [uchiyama94-1] Uchiyama M. A 6 d.o.f. parallel robot HEXA. Advanced Robotics, 8(6):601, December 1994.
- [uchiyama96] Uchiyama M., Miwa T., and Nenchev D.N. A very fast parallel robot to be applied to dextrous motion. In *World Automation Congress*, volume 3, pages 753–758, Montpellier, May, 28-30, 1996.
- [uchiyama2003] Uchiyama M. and Sato D. Dexterous motion design for DD parallel robot. In *ISRR*, Sienna, October, 19-22, 2003.
- [uchiyama2005] Uchiyama M., Tsumaki Y., and Yoon W-K. Design of a compact 6-dof haptic device to use parallel mechanisms. In *ISRR*, San-Francisco, October, 12-15, 2005.
- [ueland2021] Ueland E., T. Sauder., and Skjetne R. Optimal force allocation for overconstrained cable-driven parallel robots: continuously differentiable solutions with assessment of computational efficiency. *IEEE Trans. on Robotics*, 37(2):659–666, April 2021.
- [uhlar2008] Uhlar S. and Betsch P. Parallel manipulators, New Developments, chapter Conserving integrators for parallel manipulators, pages 75–107. ITECH, April 2008. **Keywords:** dynamics, planar robot.
- [ukidve2006] Ukidve C.S., McInroy J.E., and Jafari F. Orthogonal gough-stewart platforms with optimal fault tolerant manipulability. In *IEEE Int. Conf. on Robotics and Automation*, pages 3801–3806, Orlando, May, 16-18, 2006.
- [ukidve2008] Ukidve C.S., McInroy J.E., and Jafari F. *Parallel manipulators, Towards new applications*, chapter Quantifying and optimizing failure tolerance of a class of parallel manipulators, pages 45–68. ITECH, April 2008. **Keywords:** jacobian,safety.
- [unger88] Unger D. and others . Optimum stiffness study for a parallel link robot crane under horizontal force. In 2nd Int. Symp. on Robotics and Manufacturing, Research, Education, Applications, pages 1037–1046, Albuquerque, 1988
- [ur-rehman2009] Ur-Rehman R. and others. Kinematic and dynamic analysis of the 2-dof spherical wrist of Orthoglide 5-axis. In 3eme Congrès International Conception et Modélisation des Systèmes Mécaniques CMSM, Hammamet, March, 16-18, 2009.

- [ur-rehman2010] Ur-Rehman R., Caro S., Chablat D., and Wenger P. Multi-objective path placement of parallel kinematics machines based on energy consumption, shaking forces and maximum actuator torques: application to the Orthoglide. *Mechanism and Machine Theory*, 45(8):1125–1141, August 2010.
- [ur-rehman2010-1] Ur-Rehman R. and others . Multiobjective design optimization of 3-PRR planar parallel manipulators. In 20th CIRP Design Conference, Nantes, April 2010.
- [urizar2009] Urizar M. and others . Computing the configuration space for motion planning between assembly modes. In *Computational Kinematics*, pages 35–42, Duisburg, May, 6-8, 2009.
- [urizar2010] Urizar M. and others . Researching into non-singular transitions in the joint space. In ARK, pages 45–52, Piran, June 28- July 1, 2010.
- [urizar2012] Urizar M. and others . Assembly mode changing in the cuspidal analytic 3-R $\underline{P}$ R. *IEEE Trans. on Robotics*, 28(2):506–513, April 2012.
- [urizar2015] Urizar M. and others. Non singular transitions based design methodology for parallel manipulators. Mechanism and Machine Theory, 91:168–196, 2015.
- [vaca2012] Vaca R., Aranda J., and Thomas F. Simpified Voronoi diagrams for motion planning of quadratically-solvable Gough-Stewart platforms. In ARK, pages 157–164, Innsbruck, June, 25-28, 2012.
- [vafaiei2010] Vafaei A., Aref M.M., and Taghirad H.D. Integrated controller for an over-constrained cable driven parallel manipulator: KNTU CDRPM. In *IEEE Int. Conf. on Robotics and Automation*, pages 650–655, Anchorage, May, 3-8, 2010.
- [vafaiei2011] Vafaei A., Khosravi M.A., and Taghirad H.D. Modeling and control of cable driven parallel manipulators with elastic cables: singular perturbation theory. In *Intelligent Robotics and Applications*, pages 455–464, 2011.
- [vaida2015] Vaida C. and others . Kinematic analysis of an innovative medical parallel robot using Study parameters. In 4th Workshop on Medical and Service Robotics, Nantes, July, 8-10, 2015.
- [vaida2016] Vaida C. and others . Development of a control system for a HEXA parallel robot. In *IEEE Int. Conf.* on Automation, Quality and Testing, Robotics (AQTR), 2016.
- [valasek2002] Valasek M., Sulamanidze D., and Bauma V. Spherical joint with increased mobility for hexapod. In 3rd Chemnitzer Parallelkinematik Seminar, pages 285–294, Chemnitz, April, 23-25, 2002.
- [valasek2002-1] Valasek M., Belda K., and Florian M. Control and calibration of redundantly actuated parallel robot. In 3rd Chemnitzer Parallelkinematik Seminar, pages 411–427, Chemnitz, April, 23-25, 2002.
- [valasek2002-2] Valasek M. and others . Redundantly actuated parallel structures: principle, examples, advantages. In 3rd Chemnitzer Parallelkinematik Seminar, pages 993–1009, Chemnitz, April, 23-25, 2002.
- [valasek2002-3] Valasek M. Laser interferometer based calibration technique for multi-pods parallel structures. In 6th World Multiconference on Systemics, Cybernetics and Informatics, pages 269–272, Orlando, July, 14-18, 2002.
- [valasek2005] Valasek M. and others . Design-by-optimization and control of redundantly actuated parallel kinematics Sliding Star. *Multibody System Dynamics*, 14:251–267, 2005.
- [valasek2005-1] Valasek M. and others . Tractable treatment of design by multiobjective optimization parallel kinematics case study. *Multibody System Dynamics*, 13:143–174, 2005.
- [valasek2007] Valasek M., Sika Z., and Hamrle V. From dexterity to calibrability of parallel kinematical structures. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [vallery2013] Vallery H. and others . Multidirectional transparent support for overground gait training. In *IEEE Int. Conf. Rehabilitation Robotics*, Seattle, June, 24-26, 2013.
- [valles2017] Vallés M. and others . A 3-prs parallel manipulator for ankle rehabilitation: towards a low-cost robotic rehabilitation. *Robotica*, 35:1939–1957, 2017.
- [vanderwijk2009] Van der Wijk V. and Herder J.L. Dynamic balancing of Clavel's Delta robot. In *Computational Kinematics*, Duisburg, May, 6-8, 2009.

- [vanderwijk2013] Van der Wijk V. and others . Design and experimental evaluation of a dynamically balanced redundant planer 4-RRR parallel manipulator. *Int. J. of Robotics Research*, 32(6):744–759, May 2013.
- [vanneste2020] Vanneste F. and others . Anisotropic soft robots based on 3d printed meso-structured materials: design, modeling by homogenization and simulation. *IEEE Robotics and Automation Letters*, 5(2)::2380–2386, 2020.
- [vansilfhout99] Van Silfhout R.G. High precision hydraulic Stewart platform. Review of Scientific Instruments, 70(8):3488–3494, August 1999.
- [varcmin2002] Varcmin J.U., Beckmann G., and Kohn N. Architecture of a realtime communication network for parallel robots. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 183–198, Braunschweig, May, 29-30, 2002.
- [varedi2017] Varedi-Koulaei S.M., Daniali H.M., and Farajtaba M. The effects of joint clearance on the dynamics of the 3RRR planar parallel manipulator. *Robotica*, 35:1223–1242, 2017.
- [vareilles2002] Vareilles E. and others . Modelling and simulating the dynamic behaviour of a high speed machine tool. In 2nd NCG Application Conf. on Parallel Kinematics Machine, pages 785–805, Chemnitz, April, 23-25, 2002.
- [vartholomeos 2005] Vartholomeos P. and Papadopoulos E. Analysis and design of a novel mini-platform employing vibration micro-motors. In *IEEE Int. Conf. on Robotics and Automation*, pages 3638–3643, Barcelona, April, 19-22, 2005.
- [varziri2007] Varziri M.S and Notash L. Kinematic calibration of a wire-actuated parallel robot. *Mechanism and Machine Theory*, 42(8):960–976, August 2007.
- [vashista2014] Vashista V., Jin X., and Agrawal S.K. Active tethered pelvic assist device (A-TPAD) to study force adaptation in human walking. In *IEEE Int. Conf. on Robotics and Automation*, Hong-Kong, 7 August 31- June , 2014.
- [ventura2002] Ventura Assuncao J.M. and Schumacher W. Position and force control of parallel robots. In 1st Int. Colloquium, Collaborative Research Centre 562, pages 213–228, Braunschweig, May, 29-30, 2002.
- [verhoeven 98] Verhoeven R., Hiller M., and Tadoroko S. Workspace, stiffness, singularities and classification of tendon driven Stewart platforms. In *ARK*, pages 105–114, Strobl, June 29- July 4, 1998.
- [verhoeven 2000] Verhoeven R. and Miller M. Estimating the controllable workspace of tendon-based Stewart platforms. In ARK, pages 277–284, Piran, June, 25-29, 2000.
- [verhoeven 2002] Verhoeven R. and Miller M. Tension distribution in tendon-based Stewart platform. In ARK, pages 117–124, Caldes de Malavalla, June 29- July 2, 2002.
- [verhoeven2004] Verhoeven R. Analysis of the workspace of tendon-based Stewart platforms. Ph.D. Thesis, University of Duisburg-Essen, Duisburg, 2004. **Keywords:** wire robot, workspace.
- [vermeiren2012] Vermeiren L. and others . Motion control of planar parallel robot using the fuzzy descriptor system approach. ISA Transactions, 51:596–608, 2012.
- [verner2005] Verner M., Xi F., and Mechefske C. Optimal calibration of parallel kinematic machines. ASME J. of Mechanical Design, 125(1):62–69, January 2005.
- [vertechy2002] Vertechy R., Dunlop G.R., and Parenti-Castelli V. An accurate algorithm for the real-time solution of the direct kinematics of 6-3 Stewart platform manipulators. In *ARK*, pages 369–378, Caldes de Malavalla, June 29- July 2, 2002.
- [vertechy2005] Vertechy R. and Parenti-Castelli V. Real-time direct position analysis of parallel spherical wrists by using extra sensors. ASME J. of Mechanical Design, 128(1):288–294, January 2006.
- [vertechy2006] Vertechy R. and Parenti-Castelli V. Synthesis of 2-dof spherical fully parallel mechanisms. In ARK, pages 385–394, Ljubljana, June, 26-29, 2006.

- [vertechy2007] Vertechy R. and Parenti-Castelli V. Static and stiffness analyses of a class of over-constrained parallel manipulators with legs of type US and UPS. In *IEEE Int. Conf. on Robotics and Automation*, pages 561–567, Roma, April, 10-14, 2007.
- [vertechy2008] Vertechy R. and Parenti-Castelli V. Parallel manipulators, Towards new applications, chapter Robust, fast and accurate solution of the direct position analysis of parallel manipulators by using extra-sensors, pages 133–154. ITECH, April 2008. **Keywords:** forward kinematics with redundant sensors.
- [vertechy2009] Vertechy R. and Parenti-Castelli V. Kinematic analysis of partially decoupled fully parallel manipulators of type 5-5 and 4-5. *Robotica*, 27(2):235–240, March 2009.
- [vertechy2010] Vertechy R. and others . Parallel robot with antagonistic dielectric elastomer actuation for human-machine interaction. In ARK, pages 127–136, Piran, June 28- July 1, 2010.
- [viegas2017] Viegas C., Tavakoli M., and T. de Almeida A. A novel grid-based reconfigurable spatial parallel mechanism with large workspace. *Mechanism and Machine Theory*, 115:149–167, September 2017.
- [viegas2017-2] Viegas C., Daney D., Tavakoli M., and T. de Almeida A. Performance analysis and design of parallel kinematic machines using interval analysis. *Mechanism and Machine Theory*, 117:218–236, September 2017.
- [villarreal2013] Villarreal-Cervantes M.G. and others. Robust structure-control design approach for mechatronic systems. *IEEE/ASME Trans. on Mechatronics*, 18(5), October 2013.
- [villarreal2016] Villarreal-Cervantes M.G. and Alvarez-Gallegos J. Off-line PID control tuning for a planar parallel robot using DE variants. *Expert Systems With Applications*, 64, 2016.
- [villgrattner2008] Villgrattner T. and Ulbrich H. Piezo-driven two-degree-of-freedom camera orientation system. In *IEEE Int. Conf. on Industrial Technology*, Chengdu, April, 21-24, 2008.
- [villgrattner2009] Villgrattner T., Thümmel T., and Ulbrich H. Light-weight high dynamic camera orientation system. In *Computational Kinematics*, pages 307–314, Duisburg, May, 6-8, 2009.
- [villgrattner2010] Villgrattner T. and Ulbrich H. Optimization and dynamic simulation of a parallel three degrees-of-freedom camera orientation system. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2829–2836, Taipei, October, 18-22, 2010.
- [villgrattner2011] Villgrattner T. and Ulbrich H. Design and control of a compact high dynamic camera orientation system. *IEEE/ASME Trans. on Mechatronics*, 16(2):221–231, April 2011.
- [vischer95] Vischer P. Argos: a novel parallel spherical structure. Research Report 95-03, EPFL, Lausanne, Suisse, March, 25, 1995.
- [vischer96-phd] Vischer P. Improving the accuracy of parallel robots. Ph.D. Thesis, EPFL, Lausanne, 1996. **Keywords:** calibration.
- [vischer98] Vischer P. and Clavel R. Kinematic calibration of the parallel Delta robot. *Robotica*, 16(2):207–218, March April , 1998.
- [vischer2000] Vischer P. and Clavel R. Argos: a novel 3-dof parallel wrist mechanism. *Int. J. of Robotics Research*, 19(1):5–11, January 2000.
- [vischer2000-1] Vischer P. and Clavel R. Kinematic calibration of the parallel Argos mechanism. *Robotica*, 18(6):589–599, November 2000.
- [viscomi94] Viscomi B.V., Michalerya W.D., and Lu L-W. Automated construction in the ATLSS integrated building systems. *Automation in Construction*, 3(1):35–43, May 1994.
- [vissiere2019] Vissière A. and others . Resolution evaluation of 6-degree-of-freedom precision positioning systems: Definitions and apparatus. *Measurement*, 152, February 2019.
- [vitzewitz2009] V. Zitzewitz J. and others . A versatile wire robot concept as a haptic interface for sport simulation. In *IEEE Int. Conf. on Robotics and Automation*, pages 313–318, Kobe, May, 14-16, 2009.

- [vivas2003] Vivas A., Poignet P., and Pierrot F. Predictive functional control for a parallel robot. In *IEEE Int. Conf.* on *Intelligent Robots and Systems (IROS)*, Las Vegas, October 2003.
- [vivas2003-1] Vivas A. and others . Experimental dynamic identification of a fully parallel robot. In *IEEE Int. Conf.* on Robotics and Automation, Taipei, September, 14-19, 2003.
- [vivas2005] Vivas A. and Poignet P. Predictive functional control of a parallel robot. Control Eng. Practice, 13(7):863–874, July 2005.
- [vlachos 2010] Vlachos K. and Papadopoulos E. Control design and allocation of an over-actuated triangular floating platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 3739–3744, Anchorage, May, 3-8, 2010.
- [voglewede2002] Voglewede P.A. and Ebert-Uphoff I. Two viewpoints on the unconstrained motion of parallel manipulators at or near singular configurations. In *IEEE Int. Conf. on Robotics and Automation*, pages 503–510, Washington, May, 11-15, 2002.
- [voglewede2004] Voglewede P.A. and Ebert-Uphoff I. Measuring "closeness" to singularities for parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 4539–4544, New Orleans, April, 28-30, 2004.
- [voglewede2004-1] Voglewede P.A. and Ebert-Uphoff I. Application of workspace generation techniques to determine the unconstrained motion of parallel manipulators. ASME J. of Mechanical Design, 126(2):283–290, March 2004.
- [voglewede2005] Voglewede P.A. and Ebert-Uphoff I. Application of the antipodal grasp theorem to cable-driven robots. *IEEE Trans. on Robotics*, 21(4):713–718, August 2005.
- [vonasek2013] Vonásek V.and Saska M. and Pfeucil L. Motion planning for a cable driven parallel multiple manipulator emulating a swarm of MAVs. In 9th International Workshop on Robot Motion and Control, Wasowo, July, 13-15, 2013.
- [vose2013] Vose T.H. and others . Modeling, design and control of 6 dof flexure-based parallel mechanism for vibratory manipulation. *Mechanism and Machine Theory*, 64:111–130, June 2013.
- [voss2012] Voss K.H.J., Van Der Wijkv V., and Herder J.L. Investigation of a cable-driven parallel mechanism for interaction with a variety of surfaces, applied to the cleaning of free-form buildings. In *ARK*, pages 261–268, Innsbruck, June, 25-28, 2012.
- [voss2012-1] Voss K.H.J., Van Der Wijkv V., and Herder J.L. A cable-driven mechanism for the interaction with hemispherical surfaces. In 4th European Conf. on Mechanism Science (Eucomes), pages 409–417, Santander, September, 19-21, 2012.
- [vu2017] Vu.D-S. and others . On the design of a three-dof cable-suspended parallel robot based on a parallelogram arrangement of the cables. In 3rd Int. Conf. on cable-driven parallel robots (Cable Con), Québec, 2017.
- [vulliez2018] Vulliez M., Zeghloul S., and Khatib O. Design strategy and issues of the Delthaptic, a new 6-DOF parallel haptic device. *Mechanism and Machine Theory*, 128, 2018.
- [vulliez2018-phd] Vulliez M. Le Delthaptic, un nouveau dispositif haptique parallèle polyvalent à six degrés de liberté actifs. Ph.D. Thesis, Université de Poitiers, Poitiers, July 2018. **Keywords:** mechanical architecture, haptic device.
- [vzitzewitz2010] V. Zitzewitz J. and others . Forward kinematics of redundantly actuated, tendon-based robots. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2289–2294, Taipei, October, 18-22, 2010.
- [vzitzewitz2012] V. Zitzewitz J. and others . Use of passively guided deflection units and energy storing elements to increase the application range of wire robots. In 1st Int. Conf. on cable-driven parallel robots (CableCon), pages 167–184, Stuttgart, September, 3-4, 2012.
- [vzitzewitz2013] V. Zitzewitz J. and others . A reconfigurable, tendon-based haptic interface for research into human-environment interactions. *Robotica*, 31(3):441–453, 2013.
- [wada96] Wada B.K. and others . Vibration isolation, suppression and steering (VISS). In 6th Int. Conf. on Adaptive Structures, pages 527–535, Lancaster, 1996.

- [waldron87] Waldron K.J. and Hunt K.H. Series-parallel dualities in actively coordinated mechanisms. In 4th ISRR, pages 175–182, Cambridge, August, 9-14, 1987. MIT Press.
- [waldron89] Waldron K.J., Raghavan M., and Roth B. Kinematics of a hybrid series-parallel manipulation system. *J. of Mechanisms, Transmissions and Automation in Design*, 111(2):211–221, June 1989.
- [waldron91] Waldron K.J. and Hunt K.H. Series-parallel dualities in actively coordinated mechanisms. *Int. J. of Robotics Research*, 10(2):473–480, April 1991.
- [wampler92] Wampler C. and Arai T. Calibration of robots having kinematic closed-loops using non-linear least squares estimator. In *IFToMM-jc Conf.*, pages 153–158, Nagoya, September, 24-26, 1992.
- [wampler94] Wampler C.W. Forward displacement analysis of general six-in-parallel (Stewart) platform manipulators using soma coordinates. Research Report 8179, GM, May 1994.
- [wampler95] Wampler C.W., Hollerbach J.M., and Arai T. An implicit loop method for kinematic calibration and its application to closed-chain mechanisms. *IEEE Trans. on Robotics and Automation*, 11(5):710–724, October 1995.
- [wampler96] Wampler C.W. Forward displacement analysis of general six-in-parallel SPS (Stewart) platform manipulators using soma coordinates. *Mechanism and Machine Theory*, 31(3):331–337, April 1996.
- [wampler2004] Wampler C.W. Displacement analysis of spherical mechanism having three or fewer loops.  $ASME\ J.$  of  $Mechanical\ Design,\ 126(1):93-100,\ January\ 2004.$
- [wan2016] Wan S. and Xu Q. Design and analysis of a new compliant XY micropositioning stage based on Roberts mechanism. *Mechanism and Machine Theory*, 95:125–139, 2016.
- [wang-b2022] Wang B., Cardou P., and Caro S. An approach for predicting the calibration accuracy in planar cable-driven parallel robots. In *ARK*, Bilbao, June, 26-30, 2022.
- [wang-b2023] Wang B., Cardou P., and Caro S. An approach for predicting the calibration accuracy in planar cable-driven parallel robots and experiment validation. *Meccanica*, 58:2177–2196, 2023.
- [wang-c2013] Wang C. and others . Design and kinematical performance analysis of a 3- R US/ R RR redundantly actuated parallel mechanism for ankle rehabilitation. *J. of Mechanisms and Robotics*, 5(4), November 2013.
- [wang-c2015] Wang C. and others . Design and kinematic analysis of redundantly actuated parallel mechanisms for ankle rehabilitation. *Robotica*, 33(2):366–384, February 2015.
- [wang-c2016] Wang C. and others . Investigation on active vibration isolation of a Stewart platform with piezoelectric actuators. *Journal of Sound and Vibration*, 383:1–19, 2016.
- [wang-c2017] Wang C. and others . Novel 2R3T and 2R2T parallel mechanisms with high rotational capability. Robotica, 35:401-418, 2017.
- [wang-c2021] Wang C. and others . A novel index to evaluate the mapping of parallel mechanisms from internal to external wrenches. *Mechanism and Machine Theory*, 155, 2021.
- [wang-d2014] Wang D., Fan R., and Chen W. Performance enhancement of a three-degree-of-freedom parallel tool head via actuation redundancy. *Mechanism and Machine Theory*, 71:142–162, January 2014.
- [wang-d2018] Wang D., Wu J., and Wang L. Research on the error transfer characteristics of a 3-dof parallel tool head. *Robotics and Computer-Integrated Manufacturing*, 50:266–275, 2018.
- [wang-fy94] Wang F-Y. and Lever P.J.A. A mobile vehicle for ressource prospecting and site certification. In *ISRAM*, pages 81–86, Hawai, August, 15-17, 1994.
- [wang-h2009] Wang H. and others . Configuration and isotropy study of a novel fully pre-stressed and double-layer six-component force/torque sensor. In *IEEE Int. Conf on Mechatronics and Automation*, pages 3693–3698, Changchun, August, 9-12, 2009.
- [wang-h2010] Wang H. and others . Output error bound prediction of parallel manipulators based on the level set method. *Mechanism and Machine Theory*, 45(8):1153–1170, August 2010.

- [wang-h2017] Wang H. and others. Parameter optimization of heavy-load parallel manipulator by introducing stiffness distribution evaluation index. *Mechanism and Machine Theory*, 108:244–259, 2017.
- [wang-h2017-1] Wang H. and others . Finding measurement configuration for accurate calibration: verification with a cable-driven parallel robot. *IEEE Trans. on Robotics*, 33(5):1156–1189, October 2017.
- [wang-h2019] Wang H. and others . Conceptual design and dimensional synthesis of a novel parallel mechanism for lower-limb rehabilitation. *Robotica*, 37:469–480, 2019.
- [wang-h2019-1] Wang H. and others. Exact kinematic modeling and identification of reconfigurable cable-driven robots with dual-pulley cable guiding mechanisms. *IEEE/ASME Trans. on Mechatronics*, 24(2), April 2019.
- [wang-js2007] Wang J.S. and others. Error analysis on a tripod parallel machine tool based on D-H parameters differential transform. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [wang-k2022] Wang K. and others . A repelling-screw-based approach for the construction of generalized jacobian matrices for nonredundant parallel manipulators. *Mechanism and Machine Theory*, 176, 2022.
- [wang-l2017] Wang L., Xu H., and Guan L. Optimal design of a 3-PUU parallel mechanism with 2R1T dofs. *Mechanism and Machine Theory*, 114:190–203, 2017.
- [wang-l2019] Wang L. and others . Analysis and optimization of a novel planar 5R parallel mechanism with variable actuation modes. *Robotics and Computer-Integrated Manufacturing*, 56:178–190, 2019.
- [wang-l2019-1] Wang L. and others. Worskapce analysis of cable parallel manipulator for side net cleaning of deep sea fishing ground. In 4th Int. Conf. on cable-driven parallel robots (CableCon), Cracow, June 30- July 4, 2019.
- [wang-l2020] Wang L., Chang Y., and Zhu H. Internal model control and experimental study of ankle rehabilitation robot. *Robotica*, 38:940–956, 2020.
- [wang-l2020-1] Wang L. and others . Velocity planning for astronaut virtual training robot with high-order dynamic constraints. *Robotica*, 38:2121–2137, 2020.
- [wang-l2020-2] Wang L. and others . Design and analysis of novel 2R1T generalized parallel mechanisms with large rotational angles. *Mechanism and Machine Theory*, 150, 2020.
- [wang-l2023] Wang L., Fang Y., and Zhang D. Design of 4-dof hybrid parallel robots with an integrated three-fingered robot end effector. *Mechanism and Machine Theory*, 189, 2023.
- [wang-lct93] Wang L.C.T. and Chen C.C. On the numerical kinematic analysis of general parallel robotic manipulators. *IEEE Trans. on Robotics and Automation*, 9(3):272–285, June 1993.
- [wang-lct94] Wang L.C.T. and Chen C.C. On the dynamic analysis of a general parallel robotic manipulators. *Int. J. of Robotics and Automation*, 9(2):81–87, 1994.
- [wang-lct98] Wang L-C.T. and Hsieh J-H. Extreme reaches and reachable workspace analysis of general parallel robotic manipulator. *J. of Robotic Systems*, 5(3):145–159, 1998.
- [wang-lct2007] Wang L.C.T. and Ohen K-T. Local rolling abd tilting capability analysis of fully parallel linear actuated platform-type manipulators. *Advanced Robotics*, 21(8):931–960, 2007.
- [wang-lp2011] Wang L-P. and others . Kinematic calibration of the 3-dof parallel module of a 5 axis hybrid milling machine. *Robotica*, 29(4):535–546, July 2011.
- [wang-m2015] Wang M. and Ceccarelli M. Topology search of 3-dof translation parallel manipulators. *Chinese J. of Mechanical Engineering*, 28(4), 2015.
- [wang-m2021] Wang M. and others . Evaluation of the kinematic performance of a  $3-\underline{R}RRS$  parallel mechanism. Robotica, 39(606-617), 2021.
- [wang-qm2003] Wang Q-M., Wang J., Liu X-J, and Zhang H. Kinematic and dynamic analysis of a new cylindrical 3-dof parallel manipulator. In *ASME Design Engineering Technical Conference*, Montréal, September 29-October 2, 2002.

- [wang-qwd-2001] Wang Q.W.D. and Tan M. Characterization of the analytical boundary of the workspace for 3-6 SPS parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3755–3759, Seoul, May, 23-25, 2001.
- [wang-r-2017] Wang R. and Zhang X. Optimal design of a planar parallel 3-DOF nanopositioner with multi-objective. Mechanism and Machine Theory, 112:61–83, 2017.
- [wang-s98] Wang S. and others . Kinematics and force analysis of a 6 d.o.f. parallel mechanism with elastic joints. In ARK, pages 87–96, Strobl, June 29- July 4, 1998.
- [wang-sc2003] Wang S-C. and others. Kinematics and dynamics of a 6 degree-of-freedom fully parallel manipulator with elastic joints. *Mechanism and Machine Theory*, 38(5):439–461, May 2003.
- [wang-sm-2002] Wang S.M. and Ehmann K.F. Error model and accuracy analysis of a six-dof Stewart platform. ASME Journal of Manufacturing Science and Engineering, 124(2):286–295, May 2002.
- [wang-x-2005] Wang X. and Mills J.K. Active control of configuration-dependent linkage vibration with application to a planar parallel platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 4338–4343, Barcelona, April, 19-22, 2005.
- [wang-x-2006] Wang X. and Mills J.K. Dynamic modeling of a flexible-link planar parallel platform using a substructuring approach. *Mechanism and Machine Theory*, 41(6):671–687, June 2006.
- [wang-x-2006-1] Wang X. and Mills J.K. Dual-modal control of configuration-dependent linkage vibration in a smart parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3544–3549, Orlando, May, 16-18, 2006.
- [wang-x-2006-2] Wang X. and Mills J.K. Modal control design of configuration-dependent linkage vibration in a parallel robot through experimental identification. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 3225–3230, Beijing, October, 9-15, 2006.
- [wang-x-2008] Wang X., Baron L., and Cloutier G. Topology of serial and parallel manipulators and topological diagrams. *Mechanism and Machine Theory*, 43(6):754–770, June 2008.
- [wang-x-2008-1] Wang X., Baron L., and Cloutier G. Topological and geometrical synthesis of three-degree-of-freedom fully parallel manipulators by intantaneous kinematics. ASME J. of Mechanical Design, 130(3):032301–1/8, March 2008.
- [wang-x-2008-2] Wang X. and Baron L. Parallel manipulators, New Developments, chapter Topology and geometry of serial and parallel manipulators, pages 57–74. ITECH, April 2008. **Keywords:** mechanical architecture, structural synthesis.
- [wang-x-2018] Wang X., Cao G., and Van Horssen W.T. Dynamic simulation of multi-cable driven parallel suspension platform with slack cables. *Mechanism and Machine Theory*, 126:329–343, 2018.
- [wang-x-2021] Wang X., Wu J., and Wang Y. Dynamics evaluation of 2UPU/SP parallel mechanism for a 5-dof hybrid robot considering gravity. *Robotics and Autonomous Systems*, 135, 2021.
- [wang-y99] Wang Y. Workspace analysis of a novel closed-chain manipulator. Master's thesis, Case Western Reserve University, 1999. **Keywords:** workspace,6 dof robot,trajectory planning.
- [wang-y2000] Wang Y., Newman W.S., and Stoughton R.S. Workspace analysis of the Paradex robot-a novel, closed-chain kinematically redundant manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 2392–2397, San Francisco, April, 24-28, 2000.
- [wang-y2002] Wang Y. and G.S. Chirikjian. A divide-and-conquer method for inverse kinematics of hyper-redundant manipulators. In ARK, pages 407–414, Caldes de Malavalla, June 29- July 2, 2002.
- [wang-y2006] Wang Y. and G.S. Chirikjian. Propagation of errors in hybrid manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1848–1853, Orlando, May, 16-18, 2006.
- [wang-y2012] Wang Y. and others . Hyperstatic analysis of a fully pre-stressed six-axis force/torque sensor. *Mechanism and Machine Theory*, 57:84–94, November 2012.

- [wang-y2019] Wang Y. and others . Kinematic analysis and optimum design of a novel 2PUR-2RPU parallel robot. Mechanism and Machine Theory, 139, 2019.
- [wang-y2020] Wang Y. and others . Sliding mode robust control of a wire-driven parallel robot based on HJI theory and a disturbance observer. *IEEE Access*, 2020.
- [wang-yx2005] Wang Y-X. and Wang Y-M. Configuration bifurcations analysis of six degree-of-freedom symmetrical Stewart parallel mechanism. ASME J. of Mechanical Design, 127(1):70–77, January 2005.
- [wang-yx2008] Wang Y-X. and Li Y-T. Disturbed configuration characteristics of Gough-Stewart parallel manipulators at singular points. ASME J. of Mechanical Design, 130(2):022304–1/9, February 2008.
- [wang-yx2008-1] Wang Y-X., Li Y-T., and Pan S-X. Modified disturbance function method for a 6-6 Gough-Stewart parallel manipulator to traverse the singularity hypersurface. ASME J. of Mechanical Design, 130(5):052305—1/8, May 2008.
- [wang-yy2007] Wang Y.Y., Huang T., and Chetwynd D.G. Semi-analytical approach for stiffness estimation of PKM having complex machine frames. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [wang-zhe2001] Wang Z. and others . A study on workspace, boundary workspace analysis and workpiece positioning for parallel machine tools. *Mechanism and Machine Theory*, 36(6):605–622, June 2001.
- [wang-zhe2009] Wang Z. and others . Forward kinematics analysis of six-dof Stewart platform using PCA and PNM algorithm. *Industrial Robot*, 36(5):448–460, 2009.
- [wang-zhi2006] Wang Z. and Ghorbel F.H. Control of closed kinematic chains using a singularly perturbed dynamics model. ASME J. of Mechanical Design, 128(1):142–151, March 2006.
- [wang-zhi2020] Wang Z., Zhang W., and Ding X. Design and analysis of a novel mechanism with a two-dof remote centre of motion. *Mechanism and Machine Theory*, 153, 2020.
- [wang-zho2010] Wang Z. and others. A unified algorithm to determine the reachable and dexterous workspace of parallel manipulators. *Robotics and Computer-Integrated Manufacturing*, 26(5):454–460, October 2010.
- [wang93] Wang J. and Masory O. On the accuracy of a Stewart platform-part I: The effect of manufacturing tolerances. In *IEEE Int. Conf. on Robotics and Automation*, pages 114–120, Atlanta, May, 2-6, 1993.
- [wang98] Wang J. and Gosselin C.M. Static balancing of spatial six-degree-of-freedom parallel mechanisms with revolute actuators. In ASME Design Engineering Technical Conference, Atlanta, September, 13-16, 1998.
- [wang98-1] Wang J. and Gosselin C.M. A new approach for the dynamic analysis of parallel manipulators. *Multibody System Dynamics*, 2(3):317–334, September 1998.
- [wang98-2] Wang J. and Gosselin C.M. Kinematic analysis and singularity loci of spatial four-degree-of-freedom parallel manipulators using a vector formulation. ASME J. of Mechanical Design, 120(4):555–558, December 1998.
- [wang99] Wang J. and Gosselin C.M. Static balancing of spatial three-degree-of-freedom parallel mechanisms. *Mechanism and Machine Theory*, 34(3):437–452, April 1999.
- [wang2002] Wang J. and Gosselin C.M. Singularity analysis and design of kinematically redundant parallel mechanism. In ASME Design Engineering Technical Conference, Montréal, September 29- October 2, 2002.
- [wang2004] Wang J. and Gosselin C.M. Singularity loci of a special class of spherical 3-dof parallel mechanisms with prismatic actuators. ASME J. of Mechanical Design, 126(2):319–326, March 2004.
- [wang2004-1] Wang J. and Gosselin C.M. Kinematic analysis and design of kinematically redundant parallel mechanisms. ASME J. of Mechanical Design, 126(1):109–118, January 2004.
- [wang2007] Wang J. and others . Simplified strategy of the dynamic model of a 6-UPS parallel kinematic machine for real-time control. *Mechanism and Machine Theory*, 42(9):1119–1140, September 2007.

- [wang2007-1] Wang J., Liu X-J., and Wu C. Industrial Robotics, Theory, Modelling and Control, chapter On the analysis and kinematic design of a novel 2-dof translational parallel robot, pages 265–300. pro literatur Verlag, January 2007. **Keywords:** 2 dof robot, mechanical architecture.
- [wang2009] Wang J. and others. Workspace and singularity analysis of a 3-dof planar parallel manipulator with actuation redundancy. *Robotica*, 27(1):51–57, January 2009.
- [wang2009-1] Wang J., Liu X., and Wu C. Optimal design of a new spatial 3-dof parallel robot with respect to a frame-free index. *Science in China, Series E: Technological Sciences*, 52(4):986–999, April 2009.
- [wang 2009-2] Wang J. and others . Dynamic feed-forward control of a parallel kinematic machine. Mechatronics, 19:313-324, 2009.
- [wang2010] Wang J., Wu C., and Liu X-J. Performance evaluation of parallel manipulators: motion/force transmissibility and its index. *Mechanism and Machine Theory*, 45(10):1462–1476, October 2010.
- [wang2013] Wang J., Han W., and H. Lin. Femoral fracture reduction with a parallel manipulator robot on a traction table. Int J Med Robotics Comput Assist Surg, 9:464–471, 2013.
- [wangj-2003] Wang J. and Liu X-J. Analysis of a novel cylindrical 3-dof parallel robot. *Robotics and Autonomous Systems*, 42(1):31–46, January 2003.
- [wangl-2006] Wang L., Xi F., and Zhang D. A parallel robotic attachment and its remote manipulation. *Robotics and Computer-Integrated Manufacturing*, 22(5-6):515–525, December 2006.
- [wangl-2010] Wang L., Wu J., and Wang J. Dynamic formulation of a planar 3-dof parallel manipulator with actuation redundancy. *Robotics and Computer-Integrated Manufacturing*, 26(1):67–73, February 2010.
- [wanglc-2002] Wang L-C. and Oen K-T. Numerical direct kinematic analysis of fully parallel linearly actuated platform type manipulator. J. of Robotic Systems, 19(18):391–400, 2002.
- [wapler98] Wapler M. and Neugebauer J-G. Erfahrungen mit einem Hexapod-Roboter für die Mikrochirurgie. In New machine concepts for handling and manufacturing devices on the basis of parallel structures, pages 243–248, Braunschweig, November, 10-11, 1998.
- [wapler2003] Wapler M. and others . A Stewart platform for precision surgery. Trans. of the Institute of Measurement and Control, 25(4):329–334, 2003.
- [warnaar95] Warnaar D.B. and Chew M. Kinematic synthesis of deployable-foldable truss structures using graph theory, Part 1: graph generation. ASME J. of Mechanical Design, 117(1):112–116, March 1995.
- [warnaar95-1] Warnaar D.B. and Chew M. Kinematic synthesis of deployable-foldable truss structures using graph theory, Part 2: generation of deployable truss module using design concepts. ASME J. of Mechanical Design, 117(1):117–122, March 1995.
- [watson84] Watson P. Fligth simulators-the grand illusion. Electron. Aust., 46(4):12–17, 1984.
- [webb2002] Webb P., Geldart M., and Gindy N. An evaluation of the machining performance of the Giddings and Lewis Variax for hard and difficult material. In 2nd NCG Application Conf. on Parallel Kinematics Machine, pages 817–831, Chemnitz, April, 23-25, 2002.
- [weber2014] Weber X., Cuvillon L., and Gangloff J. Active vibration canceling of a cable-driven parallel robot using reaction wheels. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1724–1729, 2014.
- [weber2015] Weber X., Cuvillon L., and Gangloff J. Active vibration canceling of a cable-driven parallel robot in modal space. In *IEEE Int. Conf. on Robotics and Automation*, Seattle, May, 26-30, 2015.
- [weber2016-phd] Weber X. Commande modale de robots parallèles à câbles flexibles. Ph.D. Thesis, Université de Strasbourg, Strasbourg, July, 11, 2016. **Keywords:** wire robot, control, vibration.
- [weck2000] Weck M. and Staimer D. On the accuracy of parallel kinematic machine tools: design compensation and calibration. In 2nd Chemnitzer Parallelkinematik Seminar, pages 73–83, Chemnitz, April, 12-13, 2000.

- [weck2002] Weck M. and Giesler M. Task oriented multi-objective-optimization of parallel kinematics for machine-tools. In 3rd Chemnitzer Parallelkinematik Seminar, pages 187–211, Chemnitz, April, 23-25, 2002.
- [weck2002-1] Weck M. and Stainer D. Application experience with a hexapode machine-tool for machining complex aerospace parts. In 2nd NCG Application Conf. on Parallel Kinematics Machine, pages 808–815, Chemnitz, April, 23-25, 2002.
- [wehbeh2020] Wehbeh J., Rahman S., and Sharf I. Distributed model predictive control for usus collaborative payload transport. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Las Vegas, October, 25-29, 2020.
- [wei-j2019] Wei J. and Dai J.S. Reconfiguration-aimed and manifold-operation based type synthesis of metamorphic parallel mechanisms with motion between 1R2T and 2R1T. *Mechanism and Machine Theory*, 139:66–80, 2019.
- [wei-l2017] Wei L., Limin T., and Zhengnan J. Research on anti-swing characteristic of redundancy cable-driven parallel robot. In 2nd Advanced Information Technology, Electronic and Automation Control Conference (IAEAC), 2017.
- [wei-l2018] Wei L. and Angeles J. Full-mobility 3-CCC parallel-kinematics machines: Forward kinematics, singularity, workspace and dexterity analyses. *Mechanism and Machine Theory*, 126:312–328, 2018.
- [wei2019] Wei H., Qiu Y., and Sheng Y. On the cable pseudo-drag problem of cable-driven parallel camera robots at high speeds. *Robotica*, 37:1695–1709, 2019.
- [weikert2002] Weikert S. and Knapp W. Application of the grid-bar device on the Hexaglide. In 3rd Chemnitzer Parallelkinematik Seminar, pages 295–310, Chemnitz, April, 23-25, 2002.
- [weiss2009] Weill A., Langlois R.G., and Hayes M.J.D. The effect of dual row omnidirectional wheels on the kinematics of the Atlas spherical motion platform. *Mechanism and Machine Theory*, 44(2):349–358, January 2009.
- [weiss2012] Weiss J.C., Ernst B., and Wehking K-H. Use of high strength fibre ropes in multi-rope kinematic robot systems. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [wen-h2015] Wen H., Xu W., and Cong M. Kinematic model and analysis of an actuation redundant parallel robot with higher kinematic pairs for jaw movement. *IEEE Trans. on Industrial Electronics*, 62(3), March 2015.
- [wen-j-t-2003] Wen J.T. and O'Brien J.F. Singularities in three-legged platform type parallel mechanisms. *IEEE Trans. on Robotics and Automation*, 19(4):720–726, August 2003.
- [wen-jia2002] Wen-Jia C., Ming-Yang Z., and Ling Y. A six-leg, four d.o.f. parallel manipulator. In 3rd Chemnitzer Parallelkinematik Seminar, pages 227–240, Chemnitz, April, 23-25, 2002.
- [wen-k2017] Wen K., Seo T., and Lee J.W. A geometric approach for singularity analysis of 3-dof planar parallel manipulators using Grassmann–Cayley algebra. *Robotica*, 35:511–520, 2017.
- [wen-s-2016] Wen S. and others . The study of model predictive control algorithm based on the force/position control scheme of the 5-dof redundant actuation parallel robot. *Robotics and Autonomous Systems*, 79:12–25, 2016.
- [wen-s-2017] Wen S. and others . Fuzzy identification and delay compensation based on the force/ position control scheme of the 5-dof redundantly actuated parallel robot. *Int. J. Fuzzy Syst.*, 19(1):124–140, 2017.
- [wen-s-2020] Wen S. and others . Fractional-order internal model control algorithm based on the force/position control structure of redundant actuation parallel robot. *International Journal of Advanced Robotic Systems*, 2020.
- [wen94] Wen F. and Liang C. Displacement analysis of the 6-6 platform mechanisms. *Mechanism and Machine Theory*, 29(4):547–557, May 1994.
- [wendlandt94] Wendlandt J.M. and Sastry S.S. Design and control of a simplified Stewart platform for endoscopy. In 33nd Conf. on Decision and Control, pages 357–362, Lake Buena Vista, December, 14-16, 1994.
- [weng87] Weng T-C., Sandor G.N., and Xu Y. On the workspace of closed-loop manipulators with ground mounted rotary-linear actuators and finite size platform. In *ASME Design and Automation Conf.*, pages 55–61, Boston, September, 27-30, 1987.

- [weng88] Weng T.C. Kinematics of parallel manipulators with ground-mounted actuators. Ph.D. Thesis, University of Florida, Gainesville, 1988. **Keywords:** kinematics.
- [wenger98] Wenger P. and Chablat D. Workspace and assembly modes in fully parallel manipulators: a descriptive study. In ARK, pages 117–126, Strobl, June 29- July 4, 1998.
- [wenger2000] Wenger P. and Chablat D. Kinematic analysis of a new parallel machine-tool: the Orthoglide. In ARK, pages 305–314, Piran, June, 25-29, 2000.
- [wenger2001] Wenger P., Gosselin C., and Chablat D. A comparative study of parallel kinematic architecture for machining applications. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 249–258. EJCK, May, 20-22, 2001. **Keywords:** planar robot,2 dof robot,workspace,machine-tool.
- [wenger2002] Wenger P. and Chablat D. Design of a three-axis isotropic parallel manipulator for machining applications: the Orthoglide. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, pages 16–23, Québec, October, 3-4, 2002.
- [wenger2007] Wenger P., Chablat D., and Zein M. Degeneracy study of the forward kinematics of planar 3 RPR parallel manipulators. ASME J. of Mechanical Design, 129(12):1265–1268, December 2007.
- [wenger2009] Wenger P. and Chablat D. Kinematic analysis of a class of analytic planar  $3-R\underline{P}R$  parallel manipulators. In Computational Kinematics, pages 43–50, Duisburg, May, 6-8, 2009.
- [wenjie2019] Wenjie T. and others . Kinematic calibration of a 5-DOF hybrid kinematic machine tool by considering the ill-posed identification problem using regularisation method. *Robotics and Computer-Integrated Manufacturing*, 60:49–62, 2019.
- [weule2002] Weule H. and others . Computer-aided optimization of the static and dynamic properties of parallel kinematics. In 3rd Chemnitzer Parallelkinematik Seminar, pages 527–546, Chemnitz, April, 23-25, 2002.
- [wieland98] Wieland F. and others. Erfahrungen mit einer Hexapod-Werkzeugmaschine in der Produktiontechnik. In New machine concepts for handling and manufacturing devices on the basis of parallel structures, pages 271–285, Braunschweig, November, 10-11, 1998.
- [wiens98] Wiens G.J. and Hardage D. Dynamics and controls of hexapod machine-tools. In *First European-American Forum on Parallel Kinematic Machines*, pages 217–225, Milan, August 31- September 1, 1998.
- [wiens2002] Wiens G.J., Shamblin S.A., and Oh Y.H. Characterization of PKM dynamics in terms of system identification. *Proc. Instn Mech Engrs, Part K: J. Multi-body dynamics*, 216(1):59–72, March 2002.
- [wiitala98] Wiitala J.M. and Stanisic M.M. Kinematics of a split-equator symmetrically actuated double pointing systems used in a robotic wrist. In *ARK*, pages 237–246, Strobl, June 29- July 4, 1998.
- [wiitala2000] Wiitala J.M. and Stanisic M.M. Design of an overconstrained and dextrous spherical wrist. ASME J. of Mechanical Design, 122(3):347–353, September 2000.
- [wildenberg 2000] Wildenberg F. Calibration for hexapod CMW. In 2nd Chemnitzer Parallelkinematik Seminar, pages 101–112, Chemnitz, April, 12-13, 2000.
- [williams-i2006] Williams I., Hovland G., and Brogardh T. Kinematic error calibration of the Gantry-Tau parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 4199–4204, Orlando, May, 16-18, 2006.
- [williams88] Williams II R.L. and Reinholtz C.F. Closed-form workspace determination and optimization for parallel robot mechanisms. In ASME Proc. of the the 20th Biennial Mechanisms Conf., pages 341–351, Kissimmee, Orlando, September, 25-27, 1988.
- [williams98] Williams II R.L. and Hexter E.R. Maximizing kinematic motion for a 3-dof VGT module. ASME J. of Mechanical Design, 120(2):333–336, June 1998.
- [williams98-1] Williams II R.L. Cable-suspended haptic interface. International Journal of Virtual Reality, 3(33), 1998.
- [williams2000] Williams II R.L. and Poling D.B. Spherically-actuated platform manipulator. In ASME Proc. of the the 26th Biennial Mechanisms Conf., Baltimore, September, 10-13, 2000.

- [williams2001] Williams II R.L. and Gallina P. Planar cable-direct-driven robots, Part 1: kinematics and statics. In ASME Proc. of the the 27th Biennial Mechanisms Conf., Pittsburgh, September, 9-12, 2001.
- [williams2002] Williams II R.L. and Gallina P. Planar translational cable-direct-driven robots:design of wrench exertion. J. of Intelligent and Robotic Systems, 35(2):203–219, 2002.
- [williams2003] Williams II R.L., Gallina P., and Vadia J. Planar translational cable-direct-driven robots. *J. of Robotic Systems*, 20(3):107–120, 2003.
- [williams2004] Williams II R.L., Albus J., and Bostelman R. 3D cable-based cartesian metrology system. *J. of Robotic Systems*, 21(5):237–257, 2004.
- [williams2004-1] Williams II R.L., Snyder B., Albus J., and Bostelman R. Seven-dof cable- suspended robot with independent metrology. In ASME Proc. of the the 30th Biennial Mechanisms Conf., Salt Lake City, 2004.
- [williams2005] Williams II R.L. Novel cable-suspended Robotcrane support. *Industrial Robot*, 32(4):326–333, 2005.
- [williams2006] Williams II R.L., Chadaram V., and Giacometti F. Three-cable haptic interface. In ASME Proc. of the the 32th Biennial Mechanisms Conf., Philadelphia, September, 10-13, 2006.
- [wilson1997] Wilson D.R. and O'Connor J.J. A three-dimensional geometric model of the knee for the study of joint forces in gait. *Gait & Posture*, 5(2):108–115, 1997.
- [wilson1998] Wilson D.R., Feikes J.D., and O'Connor J.J. Ligaments and articular contact guide passive knee flexion. J. of Biomechanics, 31(12):1127–1136, 1998.
- [wingert2002] Wingert A., M.D. Lichtel, and Dubowsky S. On the kinematics of parallel mechanisms with bi-stable polymer actuators. In ARK, pages 303–310, Caldes de Malavalla, June 29- July 2, 2002.
- [wischnitzer2008] Y. Wischnitzer, Shvalb N., and Shoham M. Wire-driven parallel robot: permitting collisions between wires. *Int. J. of Robotics Research*, 27(9):1007–1026, September 2008.
- [wang-w-2008] Wang W. and others . Parallel manipulators, Towards new applications, chapter A reconfigurable mobile robot system based on a parallel mechanism, pages 347–362. ITECH, April 2008. **Keywords:** 2 dof robot, applications.
- [wobbe2010] Wobbe F., Nguyen D.H., and Schumacher W. Anti-windup design for trajectory tracking of a parallel robot an holistic approach. In *IEEE Int. Conf. on Robotics and Automation*, pages 4001–4008, Anchorage, May, 3-8, 2010.
- [woernle2012] Woernle C. Trajectory tracking for a three-cable suspension manipulator by nonlinear feedforward and linear feedback control. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [wohlhart94] Wohlhart K. Displacement analysis of the general spherical Stewart platform. *Mechanism and Machine Theory*, 29(4):581–589, May 1994.
- [wohlhart96] Wohlhart K. Kinematotropic linkages. In ARK, pages 359–368, Portoroz-Bernadin, June, 22-26, 1996.
- [wohlhart99] Wohlhart K. Degrees of shakiness. Mechanism and Machine Theory, 34(7):1103–1126, October 1999.
- [wohlhart2000] Wohlhart K. Architectural shakiness or architectural mobility of platforms. In ARK, pages 365–374, Piran, June, 25-29, 2000.
- [wohlhart2002] Wohlhart K. Synthesis of architecturally mobile double-planar platforms. In ARK, pages 473–482, Caldes de Malavalla, June 29- July 2, 2002.
- [wohlhart 2003] Wohlhart K. Mobile 6-SPS parallel manipulators. J. of Robotic Systems, 20(8):509–516, 2003.
- [wolf2002] Wolf A., Shoham M., and Park F.C. Investigation of singularities and self-motions of the 3-UPU robot. In ARK, pages 165–174, Caldes de Malavalla, June 29- July 2, 2002.
- [wolf2003] Wolf A. and Shoham M. Investigation of parallel manipulators using linear complex approximation. ASME J. of Mechanical Design, 125(3):564–572, September 2003.

- [wolf2004] Wolf A. and others . Application of line geometry and linear complex approximation to singularity analysis of the 3-dof CaPaMan manipulator. *Mechanism and Machine Theory*, 39(1):75–95, January 2004.
- [wolf2006] Wolf A. and Shoham M. Screw theory for the synthesis of the geometry of a parallel robot for a given instantaneous task. *Mechanism and Machine Theory*, 41(6):656–670, June 2006.
- [wu-c2011] Wu C. and others . New measure for 'closeness' to singularities of parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 5135–5140, Shangai, May, 9-13, 2011.
- [wu-g-2014] Wu G., Bai S., and Kepler J. Mobile platform center shift in spherical parallel manipulators with flexible limbs. *Mechanism and Machine Theory*, 75:12–26, May 2014.
- [wu-g-2014-1] Wu G., Caro S., Bai S., and Kepler J. Dynamic modeling and design optimization of a 3-dof spherical parallel manipulator. *Robotics and Autonomous Systems*, 62(10):1377–1386, October 2014.
- [wu-g-2015] Wu G., Caro S., and Wang J. Design and transmission analysis of an asymmetrical spherical parallel manipulator. *Mechanism and Machine Theory*, 94, 2015.
- [wu-g-2015-1] Wu G., Bai S., and Hjornet P. Parametric optimal design of a parallel Schönflies-motion robot under pick-and-place trajectory constraints. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Hamburg, Germany, September 28- October 2, 2015.
- [wu-g-2016] Wu G. and Zou P. Comparison of 3-dof asymmetrical spherical parallel manipulators with respect to motion/force transmission and stiffness. *Mechanism and Machine Theory*, 105:369–387, 2016.
- [wu-g-2020] Wu G. and others . A four-limb parallel Schönflies motion generator with full-circle end-effector rotation. Mechanism and Machine Theory, 146, 2020.
- [wu-g-2022] Wu G. and others . Trajectory tracking by fuzzy-based super-twist sliding mode control of a parallel PnP robot. In ARK, Bilbao, June, 26-30, 2022.
- [wu-g2017] Wu G., Bai S., and Caro S. Transmission quality evaluation for a class of four-limb parallel Schönflies-motion generators with articulated platforms. In *Computational Kinematics*, Poitiers, May 2017.
- [wu-g2017-1] Wu G. and Zou P. Stiffness analysis and comparison of a Biglide parallel grinder with alternative spatial modular parallelograms. *Robotica*, 35(6):1310–1326, 2017.
- [wu-g2018] Wu G. and Niu B. Dynamic stability of a tripod parallel robotic wrist featuring continuous end-effector rotation used for drill point grinder. *Mechanism and Machine Theory*, 129:36–50, 2018.
- [wu-g2018-1] Wu G. Workspace, transmissibility and dynamics of a new 3T3R parallel pick-and-place robot with high rotational capability. In *IEEE Int. Conf. on Robotics and Automation*, Brisbane, May, 21-25, 2018.
- [wu-g2018-2] Wu H., G. ans Shen. Lateral stability of a 3-dof asymmetrical spherical parallel manipulator with a universal joint featuring infinite torsional mouvement. In ARK, pages 233–241, Bologna, July, 1-5, 2018.
- [wu-g2019] Wu G. and Bai S. Design and kinematic analysis of a 3-RRR spherical parallel manipulator reconfigured with four-bar linkages. *Robotics and Computer-Integrated Manufacturing*, 56:55–65, 2019.
- [wu-h-2003] Wu H. and others . Design of parallel intersector weld/cut robot for machining processes in ITER vacuum vessel. Fusion Engineering and Design, 69(1-4):327–331, September 2003.
- [wu-h-2005] Wu H. and others . Development and control towards a parallel water hydraulic weld/cut robot for machining processes in ITER vacuum vessel. Fusion Engineering and Design, 75-79:625–631, November 2005.
- [wu-h-2006] Wu H., Pessi P., Handroos H., and Jones L. Kinematics and control of a mobile parallel robot machine. In 5th Chemnitzer Parallelkinematik Seminar, pages 399–412, Chemnitz, April, 25-26, 2006.
- [wu-h-2008] Wu H., Handroos H., and Pessi P. Parallel manipulators, Towards new applications, chapter Hybrid parallel robot for the assembling of ITER, pages 363–378. ITECH, April 2008. **Keywords:** hybrid robot, applications, hydraulics.
- [wu-h-2024] Wu H. and others . Kinetostatics modeling and elasto-geometrical calibration of overconstrained parallel manipulators. *Mechanism and Machine Theory*, 191, 2024.

- [wu-j2007] Wu J., Wang J-S., L-P. Wang, and Li T-M. Dexterity and stiffness analysis of a three-degree-of-freedom planar parallel manipulator with actuation redundancy. *Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science*, 221(8):961–969, 2007.
- [wu-j2007-1] Wu J., Wang J-S., Li T-M., and L-P. Wang. Analysis and application of a 2-dof planar parallel mechanism. *ASME J. of Mechanical Design*, 129(4):434–437, April 2007.
- [wu-j2008] Wu J., Wang J., and Wang L. Optimal kinematic design and application of a redundantly actuated 3dof planar parallel manipulator. ASME J. of Mechanical Design, 130(5):054503-1/5, May 2008.
- [wu-j2008-1] Wu J. and Yin Z. Parallel manipulators, Towards new applications, chapter A novel 4-dof parallel manipulator H4, pages 405–448. ITECH, April 2008. **Keywords:** 4 dof robot,mechanical architecture,performance analysis.
- [wu-j2009] Wu J., Wang J., Wang L., and Li T. Dynamics and control of a planar 3-dof parallel manipulator with actuation redundancy. *Mechanism and Machine Theory*, 44(4):835–849, April 2009.
- [wu-j2009-1] Wu J. and others . Study on the stiffness of a 5-dof hybrid machine-tool with actuation redundancy. Mechanism and Machine Theory, 44(2):289–305, February 2009.
- [wu-j2009-2] Wu J. and others . Dynamic model and force control of the redudantly actuated parallel manipulator of a 5-dof hybrid machine-tool. *Robotica*, 27(1):59–65, January 2009.
- [wu-j2010] Wu J., Wang J., and Wang L. A comparison study of two planar 2-dof parallel mechanisms one with 2-RRR and the other with 3-RRR structures. *Robotica*, 28(6):937–942, October 2010.
- [wu-j2010-1] Wu J. and Wang J. Motion control of the 2-dof parallel manipulator of a hybrid machine tool. *Robotica*, 28(6):861–868, October 2010.
- [wu-j2011] Wu J., Wang J., and You Z. A comparison study on the dynamics of planar 3-dof 4-RRR, 3-RRR and 2-RRR parellel manipulators. *Robotics and Computer-Integrated Manufacturing*, 27(1):150–156, February 2011.
- [wu-j2013] Wu J. and others . Optimal design of a 2-DOF parallel manipulator with actuation redundancy considering kinematics and natural frequency. *Robotics and Computer-Integrated Manufacturing*, 29(1):80–85, February 2013.
- [wu-j2013-1] Wu J. and others . Performance analysis and comparison of planar 3-dof parallel manipulators with one and two additional branches. J. of Intelligent and Robotic Systems, 29(1):73–82, October 2013.
- [wu-j2013-2] Wu J. and others . Stiffness and natural frequency of a 3-dof parallel manipulator with consideration of additional leg candidates. *Robotics and Autonomous Systems*, 61:868–875, 2013.
- [wu-j2017] Wu J. and others . A 3-dof quick-action parallel manipulator based on four linkage mechanisms with high-speed cam. *Mechanism and Machine Theory*, 115:168–196, September 2017.
- [wu-j2017-1] Wu J. and others . Workspace and dynamic performance evaluation of the parallel manipulators in a spray-painting equipment. *Robotics and Computer-Integrated Manufacturing*, 44:199–207, 2017.
- [wu-j2017-2] Wu J. and others . A parametric model of 3-PPR planar parallel manipulators for optimum shape design of platforms. *Mechanism and Machine Theory*, 118(5), December 2017.
- [wu-j2018] Wu J. and others . Mechatronics modeling and vibration analysis of a 2-dof parallel manipulator in a 5-dof hybrid machine tool. *Mechanism and Machine Theory*, 121:430–445, 2018.
- [wu-j2019] Wu J. and others . Kinematics solving of under-constrained cable-driven parallel robots based on intelligent algorithm. In 4th Int. Conf. on Control and Robotics Engineering, 2019.
- [wu-l2018] Wu L. and others . An approach for elastodynamic modeling of hybrid robots based on substructure synthesis technique. *Mechanism and Machine Theory*, 123:124–136, 2018.
- [wu-m2011] Wu M. and others . A cable-driven locomotor training system for restoration of gait in human SCI. *Gait & Posture*, 33(2):256–260, February 2011.

- [wu-m2011-1] Wu M. and others . A novel cable-driven robotic training improves locomotor function in individuals post-stroke. In 33rd Annual International Conference of the IEEE EMBS, Boston, 2011.
- [wu-m2020] Wu M. and others . Vibration reduction of delta robot based on trajectory planning. *Mechanism and Machine Theory*, 153, 2020.
- [wu-tl2007] Wu T-L. and Chang S-H. Mechanism design of multi-degrees of freedom nano-positioner. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [wu-wd-96] Wu W.D. and Huang Y.Z. The direct kinematic solution of the planar Stewart platform with coplanar ground points. *J. of Computational Mathematics*, 14(3):263–272, 1996.
- [wu-x2020] Wu X. and Bai S. Analytical determination of shape singularities for three types of parallel manipulators. Mechanism and Machine Theory, 149, 2020.
- [wu-y2002] Wu Y. and Gosselin C.M. Kinematic analysis of spatial 3-dof parallelepiped mechanisms. In ARK, pages 423–432, Caldes de Malavalla, June 29- July 2, 2002.
- [wu-y2002-1] Wu Y. and others . Topology analysis of closed-chain mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 2856–2860, Washington, May, 11-15, 2002.
- [wu-y2004] Wu Y. and Gosselin C.M. Synthesis of reactionless spatial 3-dof and 6-dof mechanisms without separate counter-rotations. *Int. J. of Robotics Research*, 23(6):625–642, 2004.
- [wu-y2008] Wu Y. and others . Quotient kinematics machines:concept, analysis and synthesis. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1964–1969, Nice, France, September, 22-26, 2008.
- [wu-y2010] Wu Y. and others . Quotient kinematics machines:concept, analysis and synthesis. In *IEEE Int. Conf. on Robotics and Automation*, pages 2739–2744, Anchorage, May, 3-8, 2010.
- [wu-y2017] Wu Y. and Carricato M. Synthesis and singularity analysis of  $N \mathcal{U}\mathcal{U}$  parallel wrists: a symmetric space approach. J. of Mechanisms and Robotics, 9(5), October 2017.
- [wu-y2018] Wu Y. and others . CU-brick cable-driven robot for automated construction of complex brick structures: From simulation to hardware realisation. In 2018 IEEE International Conference on Simulation, Modeling, and Programming for Autonomous Robots (SIMPAR), pages 166–173, 2018.
- [wu-y2018-1] Wu Y. and Carricato M. Line-symmetric motion generators. In ARK, Bologna, July, 1-5, 2018.
- [wu-y2019] Wu Y. and Carricato M. Workspace optimization of a class of zero-torsion parallel wrists. *Robotica*, 37:1174–1189, 2019.
- [wu-z2016] Wu Z. and others . A 6dof passive vibration isolator using x-shape supporting structures. *Journal of Sound* and *Vibration*, 380:90–111, 2016.
- [wu-z2018] Wu Z. and Xu Q. Design, optimization and testing of a compact XY parallel nanopositioning stage with stacked structure. *Mechanism and Machine Theory*, 126:171–188, 2018.
- [wu92] Wu K.C and Sutter T.R. Structural analysis of three space crane articulated truss joint concepts. Research Report TM-4373, NASA Research Center, Langley, May 1992.
- [wurst2002] Wurst K-H. and Peting U. PKM concept for reconfigurable machine-tools. In 3rd Chemnitzer Parallelkinematik Seminar, pages 683–695, Chemnitz, April, 23-25, 2002.
- [xi99] Xi F. Dynamic balancing of hexapods for high-speed applications. Robotica, 17(3):335–342, May 1999.
- [xi2001] Xi F. and others. Development of a sliding-leg tripod as an add-on device for manufacturing. *Robotica*, 19(3):285–294, May 2001.
- [xi2002] Xi F., Zhang D., and Mechefske C.M. Global kinetostatic analysis of parallel kinematic machines. In 3rd Chemnitzer Parallelkinematik Seminar, pages 907–922, Chemnitz, April, 23-25, 2002.
- [xi2002-1] Xi F. and others . A comparison study on tripod units for machine tools. In 3rd Chemnitzer Parallelkine-matik Seminar, pages 923–939, Chemnitz, April, 23-25, 2002.

- [xi2004] Xi F. and others . Global kinetostatic modelling of tripod-based parallel kinematic machine. *Mechanism and Machine Theory*, 39(4):357–377, April 2004.
- [xi2005] Xi F., Angelico O., and Sinatra R. Tripod dynamics and its inertia effect. ASME J. of Mechanical Design, 127(1):144–149, January 2005.
- [xi2006] Xi F., Xu Y., and Xiong G. Design and analysis of a re-configurable parallel robot. *Mechanism and Machine Theory*, 41(2):191–211, February 2006.
- [xi2020] Xi F. and others. Analysis and control of an actuation-redundant parallel mechanism requiring synchronization. *J. of Mechanisms and Robotics*, 12, August 2020.
- [xia2022] Xia Z. and others. A novel 6 dofs generalized parallel manipulator design and analysis based on humanoid leg. *Mechanism and Machine Theory*, 176, 2022.
- [xiang-y2021] Xiang Y., Li Q., and Jiang X. Dynamic rotational trajectory planning of a cable-driven parallel robot for passing through singular orientations. *Mechanism and Machine Theory*, 158, 2021.
- [xiang2020] Xiang S., Gao Z., H.and Liu, and Gosselin C. Dynamic transition trajectory planning of three-DOF cable-suspended parallel robots via linear time-varying MPC. *Mechanism and Machine Theory*, 146, 2020.
- [xiang2020-1] Xiang S., Gao Z., H.and Liu, and Gosselin C. Trajectory optimization for a six-dof cable-suspended parallel robot with dynamic motions beyond the static workspace. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [xiao-h2018] Xiao H., Lu S., and Ding X. Tension cable distribution of a membrane antenna frame based on stiffness analysis of the equivalent 4-SPS-S parallel mechanism. *Mechanism and Machine Theory*, 124:133–149, 2018.
- [xiao2014] Xiao S. and Li Y. Model-based sliding mode control for a 3-dof translational micro parallel positioning stage. In *IEEE Int. Conf. on Robotics and Automation*, Hong-Kong, 7 August 31- June, 2014.
- [xiaoguang2016] Xiaoguang W., Shaoyu M., and Qi L. Hybrid pose/tension control based on stiffness optimization of cable-driven parallel mechanism in wind tunnel test. In 2nd International Conference on Control, Automation and Robotics, 2016.
- [xie-c-2021] Xie C. and others . Deep reinforcement learning based cable tension distribution optimization for cable-driven rehabilitation robot. In *IEEE Int. Conf. on Advanced Robotics and Mechatronics*, Chongqing, July, 3-5, 2021.
- [xie-s2020] Xie S. and others . Dynamic modeling and performance analysis of a new redundant parallel rehabilitation robot. *IEEE Access*, 2020.
- [xie-z2021] Xie Z. and others . Global  $G^3$  continuity toolpath smoothing for a 5-dof machining robot with parallel kinematics. Robotics and Computer-Integrated Manufacturing, 67, 2021.
- [xie2003] Xie D. and Anamato N.M. A kinematics-based probabilistic roadmap method for high dof closed chain systems. Research Report TR03-007, Departement of Computer Science, Texas A&M University, November, 14, 2003.
- [xie2004] Xie D. and Anamato N.M. A kinematics-based probabilistic roadmap method for high dof closed chain systems. In *IEEE Int. Conf. on Robotics and Automation*, New Orleans, April, 28-30, 2004.
- [xing2022] Xing S. and others. Component calibration and configuration planning in assembly automation with a parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 77, October 2022.
- [xiong2020] Xiong H. and others. Comparison of end-to-end and hybrid deep reinforcement learning strategies for controlling cable-driven parallel robots. *Neurocomputing*, 377:73–84, 2020.
- [xu-k2018] Xu K. and others . Design of 3-dof zero coupling degree planar parallel manipulator based on coupling-reducing and its kinematic performance improvement. In *EUCOMES*, pages 400–408, Aachen, September, 4-6, 2018.
- [xu-l-2017] Xu L. and others . Kinematic analysis and design of a novel  $3T1R2 (PRR)^2RH$  hybrid manipulator. Mechanism and Machine Theory, 112:105–122, 2017.

- [xu-l2018] Xu L. and others. Tex3: An 2R1T parallel manipulator with minimum dof of joints and fixed linear actuators. *International Journal of Precision Engineering and Manufacturing*, 19(2), 2018.
- [xu-l2019] Xu L. and others . Design, analysis and optimization of Hex4, a new 2R1T overconstrained parallel manipulator with actuation redundancy. *Robotica*, 37(2), 2019.
- [xu-lj-2001] Xu L.J., Fan S-W., and Li H. Analytical model method for dynamics of N-celled tetrahedron variable geometry truss manipulators. *Mechanism and Machine Theory*, 36(11-12):1271–1279, November 2001.
- [xu-p-2017] Xu P. and others . Kinematics analysis of a hybrid manipulator for computer controlled ultra-precision freeform polishing. *Robotics and Computer-Integrated Manufacturing*, 44:44–56, 2017.
- [xu-q-2006] Xu Q. and Li Y. A novel design of a 3-PRC compliant parallel micromanipulator for nanomanipulation. *Robotica*, 24(4):527–528, July 2006.
- [xu-q-2007] Xu Q. and Li Y. Design and analysis of a new three-prismatic-revolute-cylindrical translational parallel manipulator. *Proc. Instn Mech Engrs, Part C: J. Mechanical Engineering Science*, 221(5):565–576, 2007.
- [xu-q-2007-1] Xu Q. and Li Y. Influences of constraint errors on the mobility of a 3-dof translational parallel manipulator. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [xu-q-2009] Xu Q. and Li Y. Error analysis and optimal design of a class of translational parallel kinematic machine using particle swarm optimization. *Robotica*, 27(1):67–78, 2007.
- [xu-q-2010] Xu Q. and Li Y. Dahl model-based hysteresis compensation and precise positioning control of an XY parallel micromanipulator with piezoelectric actuation. ASME J. of Dynamic Systems, Measurement and Control, 132(4):041011–1/15, July 2010.
- [xu-wl2008] Xu W.L., Pap J-S., and Bronlund J. Design of a biologically inspired parallel robot for foods chewing. *IEEE Trans. on Industrial Electronics*, 55(2), February 2008.
- [xu-y-2015] Xu Y. and others . A method for force analysis of the overconstrained lower mobility parallel mechanism. *Mechanism and Machine Theory*, 88:31–48, June 2015.
- [xu-y-2017] Xu Y. and others. Type synthesis of the 2R1T parallel mechanisms with two continuous rotational axes and study on the principle of motion decoupling. *Mechanism and Machine Theory*, 108:27–40, 2017.
- [xu-y-2020] Xu Y. and others . Type synthesis of overconstrained 2R1T parallel mechanisms with the fewest kinematic joints based on the ultimate constraint wrenches. *Mechanism and Machine Theory*, 147, 2020.
- [xu-y-2021] Xu Y. and others . Force analysis of the redundantly actuated parallel mechanism 2RPR+P considering different control methodologies. *Robotics and Autonomous Systems*, 142, 2021.
- [xu-y2019] Xu Y. and others . Principle of force analysis of overconstrained parallel mechanisms considering link weight. *Robotica*, 37:1533–1544, 2019.
- [xu92] Xu Y-X., Kohli D., and Weng T-C. Direct differential kinematics of hybrid-chain manipulators including singularities and stability analyses. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 65–73, Scottsdale, September, 13-16, 1992.
- [xu-z2020] Xu Z. and others . Dynamics analysis of a novel 3-PSS parallel robot based on linear motor. *IEEE Access*, 2020.
- [yakey2001] Yakey J.H. and others . Randomized path planning for linkages with closed kinematic chains. *IEEE Trans. on Robotics and Automation*, 17(6):951–958, December 2001.
- [yamada2004] Yamada H., Kudomi S., and Muto T. Development of a hydraulic parallel-link-type force display (investigation of basis function of the force display). *Int. J. of Robotics and Automation*, 19(1):1–5, 2004.
- [yamakawi2004] Yamakawi T., Omata T., and Mori O. 4R and 5R parallel mechanism mobile robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 3684–3689, New Orleans, April, 28-30, 2004.

- [yamamoto2000] Yamamoto M. and Mohri A. Inverse kinematic analysis for incompletely restrained parallel wire mechanisms. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Takamatsu, October 30- November 5, 2000.
- [yamamoto2004] Yamamoto M., Yanai N., and Mohri A. Trajectory control of incompletely restrained parallel-wire-suspended mechanism based on inverse dynamics. *IEEE Trans. on Robotics*, 20(5):840–850, October 2004.
- [yamamoto99] Yamamoto M., Yanai N., and Mohri A. Inverse dynamics and control of crane-type manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1222–1227, Kyongju, October, 17-21, 1999.
- [yamane98] Yamane K. and others . Parallel dynamics computation and  $H_{\infty}$  acceleration control of parallel manipulators for acceleration display. In *IEEE Int. Conf. on Robotics and Automation*, pages 2301–2306, Louvain, May, 18-20, 1998.
- [yamane 2005] Yamane K. and others . Parallel dynamics computation and  $H_{\infty}$  acceleration control of parallel manipulators for acceleration display. ASME J. of Dynamic Systems, Measurement and Control, 127(2):185–191, June 2005.
- [yan2016] Yan S.J., Ong S.K., and Nee A.Y.C. Stiffness analysis of parallelogram-type parallel manipulators using a strain energy method. *Robotics and Computer-Integrated Manufacturing*, 37:13–22, 2016.
- [yang-c2010] Yang C. and others . PD control with gravity compensation for hydraulic 6-DOF parallel manipulator. Mechanism and Machine Theory, 45(4):666-677, April 2010.
- [yang-c2012] Yang C. and others . Decoupling control for spatial six-degree-of-freedom electro-hydraulic parallel robot. Mechanism and Machine Theory, 28:14–23, 2012.
- [yang-c2014] Yang C., Qu Z., and Han J. Decoupled-space control and experimental evaluation of spatial electrohydraulic robotic manipulators using singular value decomposition algorithms. *IEEE Trans. on Industrial Electronics*, 61(7), July 2014.
- [yang-c2018] Yang C. and others . Elastostatic stiffness modeling of overconstrained parallel manipulators. *Mechanism and Machine Theory*, 122:58–74, 2018.
- [yang-c2020] Yang C., Li Q., and Q. Chen. Decoupled elastostatic stiffness modeling of parallel manipulators based on the rigidity principle. *Mechanism and Machine Theory*, 145, 2020.
- [yang-c2021] Yang C., Li Q., and Q. Chen. Natural frequency analysis of parallel manipulators using global independent generalized displacement coordinates. *Mechanism and Machine Theory*, 156, 2021.
- [yang-c2022] Yang C., Li Q., and Ye W. Dimensional synthesis method of parallel manipulators based on the principle component analysis. *Mechanism and Machine Theory*, 176, 2022.
- [yang-g99] Yang G., Chen I-M., and Yeo S.H. Design consideration and kinematic modeling for modular reconfigurable parallel robots. In 10th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1079–1084, Oulu, June, 20-24, 1999.
- [yang-g2001] Yang G. and others . Kinematic design of modular reconfigurable in-parallel robots.  $Autonomous\ Robots$ , 10(1):83-89, January 2001.
- [yang-g2001-1] Yang G. and others . Self-calibration of three-legged modular reconfigurable parallel robots based on leg-end distance errors. *Robotica*, 19(2):187–198, March 2001.
- [yang-g2001-2] Yang G. and others . Singularity analysis of three-legged parallel robots based on passive-joint velocities. In *IEEE Int. Conf. on Robotics and Automation*, pages 2407–2412, Seoul, May, 21-26, 2001.
- [yang-g2001-3] Yang G., Chen I-M., and Angeles J. Singularity analysis of three-legged parallel robots based on passive joint velocities. *IEEE Trans. on Robotics and Automation*, 17(4):413–422, August 2001.
- [yang-g2002] Yang G. and others . Simultaneous base and tool calibration for self-calibrated parallel robots. *Robotica*, 20(4):367–374, July 2002.

- [yang-g2002-1] Yang G., Chen W., and Chen I-M. A geometrical method for the singularity analysis of 3-RRR planar parallel robots with different actuation schemes. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2055–2060, Lausanne, October 2002.
- [yang-g2004] Yang G., Chen I-M., W. Chen, and Lin W. Kinematic design of a six-dof parallel-kinematics machine with decoupled-motion architecture. *IEEE Trans. on Robotics*, 20(5):876–884, October 2004.
- [yang-g2004-1] Yang G., Yeo S.H., and Pham C.B. Kinematics and singularity analysis of a planar cable-driven parallel manipulator. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Sendai, September 28- October 2, 2004.
- [yang-g2006] Yang G., Pham C.B., and Yeo S.H. Workspace performance optimization of fully restrained cable-driven parallel manipulators. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Beijing, October, 9-15, 2006.
- [yang-g2011] Yang G. and others . Analysis and design of a 3-dof flexure-based zero-torsion parallel manipulator for nano-alignment applications. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [yang-j98] Yang J. and Geng Z.J. Closed form forward kinematics solution to a class of hexapod robots. *IEEE Trans. on Robotics and Automation*, 14(7):503–508, June 1998.
- [yang-j2011] Yang J. and others . Type synthesis of parallel mechanisms having the first class  $G_F$  sets and one-dimensional rotation. Robotica, 29:895–902, 2011.
- [yang-m2019] Yang M. and others . Optimal design, modeling and control of a long stroke 3-PRR compliant parallel manipulator with variable thickness flexure pivots. *Robotics and Computer-Integrated Manufacturing*, 60:23–33, 2019.
- [yang-ph96] Yang P-H., Waldron J.K., and Orin D.E. Kinematics of a three degree-of-freedom motion platform for a low cost driving simulator. In ARK, pages 89–98, Portoroz-Bernadin, June, 22-26, 1996.
- [yang-ph2000] Yang P-H. and Waldron J.K. Coordination of parallel arrays of binary actuators. In 13th RoManSy, pages 43–50, Zakopane, July, 3-6, 2000.
- [yang-s2016] Yang S. and others . A finite screw approach to type synthesis of three-dof translational parallel mechanisms. *Mechanism and Machine Theory*, 104:405–419, 2016.
- [yang-s2017] Yang S., Sun T., and Huang T. Type synthesis of parallel mechanisms having 3T1R motion with variable rotational axis. *Mechanism and Machine Theory*, 109:220 230, 2017.
- [yang-s2020] Yang S. and Li Y. Different kinds of 3T2R serial kinematic chains and their applications in synthesis of parallel mechanisms. *Mechanism and Machine Theory*, 144, 2020.
- [yang-sy2012] Yang S.Y., Mac Lachlan R.A., and Riviere C.N. Design and analysis of 6 dof handheld micromanipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 1946–1951, Saint Paul, May, 14-18, 2012.
- [yang-t2009] Yang T. and others . Robust backstepping control of active vibration isolation using a Stewart platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 1788–1793, Kobe, May, 14-16, 2009.
- [yang-tl2018] Yang T-l. and others . Topology design of robot mechanisms. Springer, 2018. **Keywords:** structural synthesis.
- [yang-x2017] Yang X. and others . A dual quaternion solution to the forward kinematics of a class of six-dof parallel robots with full or redundant actuation.  $Mechanism\ and\ Machine\ Theory,\ 107:27-36,\ 2017.$
- [yang-x2017-1] Yang X. and others . Dynamic isotropic design and decentralized active control of a six-axis vibration isolator via Stewart platform. *Mechanism and Machine Theory*, 117:244–252, 2017.
- [yang-x2018] Yang X. and others. A dual quaternion approach to efficient determination of the maximal singularity-free joint space and workspace of six-dof parallel robots. *Mechanism and Machine Theory*, 129:279–292, 2018.
- [yang-x2019] Yang X. and others. Modified robust dynamic control for a Diamond parallel robot. *IEEE/ASME Trans. on Mechatronics*, 24(3), June 2019.

- [yang-y2008] Yang Y. and O'Brien J.F. A sequential method for the singularity free workspace design of a planar 3-arm parallel robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 1977–1982, Nice, France, September, 22-26, 2008.
- [yang-y2008-1] Yang Y. and O'Brien J.F. Finding unmanipulable singularities in parallel mechanisms using jacobian decomposition. *J. of Intelligent and Robotic Systems*, 53(1):3–19, September 2008.
- [yang-y2009] Yang Y. and O'Brien J.F. A geometric approach for the design of singularity-free parallel robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 1801–1806, Kobe, May, 14-16, 2009.
- [yang-y2009-1] Yang Y. and Zhang Y. A new cable-driven haptic device for integrating kinesthetic and cutaneous display. In ASME/IFToMM International Conference on Reconfigurable Mechanisms and Robots, pages 386–391, 2009.
- [yang-y2010] Yang Y. and O'Brien J.F. A sequential method for the singularity-free workspace design of a three legged parallel robot. *Mechanism and Machine Theory*, 45(11):1674–1706, November 2010.
- [yang-y2011] Yang Y. and O'Brien J.F. A novel composition of 2 parallel robots for 6dof workspace. In *IEEE Int. Conf. on Robotics and Automation*, Shangai, May, 9-13, 2011.
- [yang-y2018] Yang Y. and others. Design of 2-degrees-of-freedom (dof) planar translational mechanisms with parallel linear motion elements for an automatic docking device. *Mechanism and Machine Theory*, 121:398–424, 2018.
- [yang-y2021] Yang Y. and others . Kinematic stability of a 2-dof deployable translational parallel manipulator. Mechanism and Machine Theory, 160, 2021.
- [yang-z2018] Yang Z. and Zhang D. Novel design of a 3-RRUU 6-dof parallel manipulator. In 4th International Conference on Mechanical and Aeronautical Engineering, 2018.
- [yang-z2020] Yang Z., Yang L., and Zhang L. Eye-in-hand 3d visual servoing of helical swimmers using parallel mobile coils. In *IEEE Int. Conf. on Robotics and Automation*, Paris, May 31- August 31, 2020.
- [yang84] Yang D.C.H. and Lee T.W. Feasibility study of a platform type of robotic manipulator from a kinematic viewpoint. J. of Mechanisms, Transmissions and Automation in Design, 106(2):191–198, June 1984.
- [yao-r2012] Yao R., Li H., and Zhang X. A modeling method of the cable-driven parallel manipulator for FAST. In 1st Int. Conf. on cable-driven parallel robots (CableCon), Stuttgart, September, 3-4, 2012.
- [yao-s2018] Yao S. and others . Vision-based adaptive control of a 3-RRR parallel positioning system. *Science China Technology*, 61:253–1264, 2018.
- [yao-s2019] Yao S. and others . High-accuracy calibration of a visual motion measurement system for planar 3-dof robots using Gaussian process. *IEEE Sensors Journal*, 19(17):7659–7667, 2019.
- [yao2011] Yao J. and others . Spatially isotropic configuration of Stewart platform-based force sensor. *Mechanism and Machine Theory*, 46(2):142–155, February 2011.
- [yao2015] Yao J. and others . Isotropy analysis of redundant parallel six-axis force sensor. *Mechanism and Machine Theory*, 91:131–150, 2015.
- [yao2016] Yao J. and others . A 3D-printed redundant six components force sensor with eight parallel limbs. Sensors and Actuators A, 247:90–97, 2016.
- [yao2017] Yao J. and others . Dynamic analysis and driving force optimization of a 5-dof parallel manipulator with redundant actuation. *Robotics and Computer-Integrated Manufacturing*, 48:51–58, December 2017.
- [yaqing 2007] Yaqing Z., Qi L., and Xiongwei L. Initial test of a wire-driven parallel suspension system for low speed wind tunnels. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [yasir2020] A. Yasir, Kiper G., and Can Dede M.I. Kinematic design of a non-parasitic 2R1T parallel mechanism with remote center of motion to be used in minimally invasive surgery applications. *Mechanism and Machine Theory*, 153, 2020.

- [yasuda2000] Yasuda T. and others. Experiments with a parallel robot with singularity-perturbed design. In 26th Ann. Conf. of the IEEE Indus. Electronics Society, pages 217–222, Nagoya, October, 22-28, 2000.
- [yau2001] Yau C.L. Systems and methods employing a rotary track for machining and manufacturing, March, 6, 2001. United States Patent n° 6,196,081. **Keywords:** mechanical architecture,6 dof robot, patent.
- [ye-h2020] Ye H. annd others. Forward and inverse kinematics of a 5-dof hybrid robot for composite material machining. Robotics and Computer-Integrated Manufacturing, 65, 2020.
- [ye2014] Ye W. and others . A new family of reconfigurable parallel mechanisms with diamond kinematropic chain. Mechanism and Machine Theory, 74:1–9, April 2014.
- [ye2014-1] Ye W. and others . A new family of reconfigurable parallel mechanisms with diamond kinematotropic chain. Mechanism and Machine Theory, 74:1–9, April 2014.
- [ye2016] Ye W. and others. Mobility variation of a family of metamorphic parallel mechanisms with reconfigurable hybrid limbs. *Robotics and Computer-Integrated Manufacturing*, 41:145–162, 2016.
- [ye2020] Ye W., Chai X., and Zhang K. Kinematic modeling and optimization of a new reconfigurable parallel mechanism. *Mechanism and Machine Theory*, 149, October 2000.
- [ye2020-1] Ye W., Zhang B., and Li Q. Design of a 1r1t planar mechanism with remote center of motion. *Mechanism and Machine Theory*, 149, 2020.
- [yedukondalu2015] Yedukondalu G., Srinath A., and Suresh Kumar J. Mechanical chest compression with a medical parallel manipulator for cardiopulmonary resuscitation. *Int J Med Robotics Comput Assist Surg*, 11:448–457, 2015.
- [yee91] Yee C.S. and Lim K.B. Neural network for the forward kinematics problem in parallel manipulator. In *IEEE Int. Joint Conf. on Neural Network*, pages 1699–1704, Singapore, November, 18-21, 1991.
- [yee97] Yee C.S. and Lim K.B. Forward kinematics solution of Stewart platform using neural network. *Neurocomputing*, 16(4):333-349, 1997.
- [yen2013] Yen P-L. and Hung S.S. Cooperative force control of a hybrid Cartesian parallel manipulator for bone slicing. *Robotica*, 31(2):173–182, March 2013.
- [yi-l2007] Yi L. and Leinonen T. Computer simulation machining a 3D free form surface by using a 3-UPU parallel manipulator and a milling machine. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [yi-l2007-1] Yi L. and Leinonen T. Using cad variation geometric approach solving velocity/acceleration of a 4SPS &UPU parallel manipulator. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [yi-w2019] Yi W. and others. Optimal design and force control of a nine-cable-driven parallel mechanism for lunar takeoff simulation. *Chinese J. of Mechanical Engineering*, 32(73), 2019.
- [yi-y2004] Yi Y. and others . Generating classes of orthogonal Gough-Stewart platforms. In *IEEE Int. Conf. on Robotics and Automation*, pages 4969–4974, New Orleans, April, 28-30, 2004.
- [yi-y2004-1] Yi Y. and others . Optimum design of a class of fault tolerant isotropic Gough-Stewart platforms. In *IEEE Int. Conf. on Robotics and Automation*, pages 4963–4968, New Orleans, April, 28-30, 2004.
- [yi92] Yi B-J., Freeman R.A., and Tesar D. Force and stiffness transmission in redundantly actuated mechanisms: the case for a spherical shoulder mechanism. In 22nd Biennial Mechanisms Conf., pages 163–172, Scottsdale, September, 13-16, 1992.
- [yi93] Yi B-J. and Freeman R.A. Geometric characteristics of antagonistic stiffness in redundantly actuated mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 654–661, Atlanta, May, 2-6, 1993.
- [yi2001] Yi B-J., Cox D., and Tesar D. Analysis and design criteria for a redundantly actuated 4-legged six degree-of-freedom parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3286–3293, Seoul, May, 21-26, 2001.

- [yi2002] Yi B-J. and others. Design and experiment of a 3-DOF parallel micro-mechanism utilizing flexure hinges. In *IEEE Int. Conf. on Robotics and Automation*, pages 1167–1172, Washington, May, 11-15, 2002.
- [yi2003] Yi B-J. and others . Design and experiment of a 3-DOF parallel micromechanism utilizing flexure hinges. *IEEE Trans. on Robotics and Automation*, 19(4):604–612, August 2003.
- [yilmaz2018] Yilmaz N. and others . External force/torque estimation on a dexterous parallel robotic surgical instrument wrist. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Madrid, October, 1-5, 2018.
- [yin-fw2020] Yin F.W. and others. A screw theory based approach to determining the identifiable parameters for calibration of parallel manipulators:. *Mechanism and Machine Theory*, 145, 2020.
- [yin94] Yin J.P. and Liang C.G. The forward displacement analysis of a kind of special platform manipulator. *Mechanism and Machine Theory*, 29(1):1–9, January 1994.
- [yin98] J.P. Yin, Marsh D., and Duffy J. Catastrophe analysis of planar three-spring systems. In ASME Design Engineering Technical Conferences, Atlanta, September, 13-16, 1998.
- [yiu2001] Yiu Y.K. and others. On the dynamics of parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 3766–3771, Seoul, May, 23-25, 2001.
- [yiu2001-1] Yiu Y.K. and Li Z.X. Modeling configuration space and singularities of parallel mechanisms. In *Int. Conf. on Mechatronics Technology (ICMT)*, pages 298–303, Singapore, June, 6-8, 2001.
- [yiu2003] Yiu Y.K., Meng J., and Li Z.X. Auto-calibration for a parallel manipulator with sensor redundancy. In *IEEE Int. Conf. on Robotics and Automation*, pages 3660–3665, Taipei, September, 14-19, 2003.
- [yong2009] Yong Y.K. and Lu T-F. Kinetostatic modeling of 3-RRR compliant micro-motion stages with flexure hinges. *Mechanism and Machine Theory*, 44(6):1156–1175, June 2009.
- [yoon-dk2012] Yoon D-K. and others . Autonomous human tracking of mutiple robotic lamps. In *IEEE Int. Conf. on Robotics and Automation*, pages 3567–3572, Saint Paul, May, 14-18, 2012.
- [yoon-jh-2006] Yoon J.H. and others . Optimal trajectory generation of serially-linked parallel biped robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 1610–1615, Orlando, May, 16-18, 2006.
- $[yoon-wk-2004] \ \ Yoon\ W-K.\ and\ others\ .\ Stiffness\ analysis\ and\ design\ of\ a\ compact\ modified\ Delta\ parallel\ mechanism. \\ Robotica,\ 22(5):463-475,\ \ September\ \ 2004.$
- [yoon2000] Yoon J. and Ryu J. Control and evaluation of a new 6-dof haptic device using a parallel mechanism. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, Takamatsu, Japan, October 30- November 5, 2000.
- [yoon2005] Yoon J. and Ryu J. A new family of hybrid 4-dof parallel mechanisms with two platforms and its application to a footpad device. *J. of Robotic Systems*, 22(5):287–298, 2005.
- [yoon2005-1] Yoon J. and Ryu J. A novel reconfigurable ankle/foot rehabilitation robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 2301–2306, Barcelona, April, 19-22, 2005.
- [yoon2006] Yoon J. and Ryu J. A novel locomotion interface with two 6-dof parallel manipulators that allows human walking on various virtual terrains. *Int. J. of Robotics Research*, 25(7):689–708, July 2006.
- [yoon2016] Yoon J. and others . Multi-mode input shaping for vibration suppression on an overconstrained cable-driven parallel robot with cable stiffness. In 7th Int. Conf on Mechanical and Aerospace Engineering, 2016.
- [yoon2017] Yoon J. and others. Adaptive control for cable driven parallel robots. In 17th International Conference on Control, Automation and Systems (ICCAS), Jeju, October, 18-21, 2017.
- [yoshida96] Yoshida K., Mavroidis C., and Dubowsky S. Impact dynamics of space long reach manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 1909–1916, Minneapolis, April, 24-26, 1996.
- [you-w2009] You W. and others . High efficient inverse dynamic calculation approach for a haptic device with pantograph parallel platform. *Multibody System Dynamics*, 21:233–247, 2009.

- [you211] You X. and others . Dynamic control of a 3-dof cable-driven robot based on backstepping technique. In 6th IEEE Conference on Industrial Electronics and Applications, 2011.
- [youssef2020] Youssef K. and Otis M.J-D. Reconfigurable fully constrained cable driven parallel mechanism for avoiding interference between cables. *Mechanism and Machine Theory*, 148, 2020.
- [yu-a2008] Yu A., Bonev I.A., and Zsombor-Murray P. Geometric approach to the accuracy analysis of a class of 3-dof planar parallel robot. *Mechanism and Machine Theory*, 43(3):364–375, March 2008.
- [yu-g-2018] Yu G. and others . Stiffness modeling approach for a 3-dof parallel manipulator with consideration of nonlinear joint stiffness. *Mechanism and Machine Theory*, 123, 2018.
- [yu-g-2020] Yu G. and others . Optimal design of the three-degree-of-freedom parallel manipulator in a spray-painting equipment. *Robotica*, 38:1064–1081, 2020.
- [yu-h2010] Yu H. and others . Structural synthesis and variation analysis of a family of 6-dof parallel mechanisms with three limbs. *Int. J. of Robotics and Automation*, 25(2):121–131, 2010.
- [yu-h2016] Yu H. and others . Calibration and integration of B-Mode optical coherence tomography for assistive control in robotic microsurgery. *IEEE/ASME Trans. on Mechatronics*, 21(6), December 2016.
- [yu-j-2016] Ju J. and otthers . The best-approximate realization of a spatial stiffness matrix with simple springs connected in parallel. *Mechanism and Machine Theory*, 103:236–249, 2016.
- [yu-k2010] Yu K. and others. Enhanced trajectory tracking control with active lower bounded stiffness control for cable robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 669–674, Anchorage, May, 3-8, 2010.
- [yu-s2018] Yu S. and others .  $\mu$ -based theory in compliant force control for space docking. *IEEE Access*, 2018.
- [yu-s2018-1] Yu S. and others . Force and moment compensation method based on three degree-of-freedom stiffness-damping identification for manipulator docking hardware-in-the-loop simulation system. *IEEE Access*, 2018.
- [yu-w2018] Yu W. and others . Design and kinematic analysis of a 3-translational-dof spatial parallel mechanism based on polyhedra. *Mechanism and Machine Theory*, 121:92–115, 2018.
- [yu-y2009] Yu Y. and others . Fuzzy logic based adjustment control of a cable-driven auto-leveling parallel robot. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, St Louis, October, 11-15, 2009.
- [yu-y2012] Yu Y. and Liang W. Design optimization for parallel mechanism using on human hip joint power assisting based on manipulability inclusive principle. In *IEEE Int. Conf. on Robotics and Automation*, pages 2306–2312, Saint Paul, May, 14-18, 2012.
- [yu-yq2011] Yu Y-Q. and others . An experimental study on the dynamics of a 3-RRR flexible parallel robot. IEEE Trans. on Robotics, 27(5):992–997, October 2011.
- [yu2001] Yu X. and others . Measuring data based non-linear error modeling for parallel machine-tool. In *IEEE Int. Conf. on Robotics and Automation*, pages 3535–3540, Seoul, May, 23-25, 2001.
- [yuan-h2014] Huan H., Courteille E., and Deblaise D. Elastodynamic analysis of cable-driven parallel manipulators considering dynamic stiffness of sagging cables. In *IEEE Int. Conf. on Robotics and Automation*, Hong-Kong, 7 May 31- June, 2014.
- [yuan-h2015] Yuan H., Courteille E., and Deblaise D. Static and dynamic stiffness analyses of cable-driven parallel robots with non-negligible cable mass and elasticity. *Mechanism and Machine Theory*, 85:64–81, March 2015.
- [yuan-h2015phd] Yuan H. Static and Dynamic Stiffness Analysis of Cable-Driven Parallel Robots. Ph.D. Thesis, INSA Rennes, Rennes, 2015. **Keywords:** wire robot, statics, stiffness.
- [yuan-h2017] Yuan H. and others . Vibration analysis of cable-driven parallel robot based on the dynamic stiffness matrix method. *Journal of Sound and Vibration*, 394:527–544, 2017.
- [yuan-wh2014] Yuan W-H. and Tsai M-S. A novel approach for forward dynamic analysis of 3-PRS parallel manipulators with consideration of friction effect. *Robotics and Computer-Integrated Manufacturing*, 30(3):315–325, June 2014.

- [yuan-x022] Yuan X. and others . Position error modeling and accuracy evaluation of n-dof translational parallel manipulators that can be transformed into n four-bar mechanisms based on motion/force transmissibility. *Mechanism and Machine Theory*, 176, 2022.
- [yuan2002] Yuan J., Wang Z., and Liu F. The fixed point method for structure calibration of parallel kinematics machine tool. In 3rd Chemnitzer Parallelkinematik Seminar, pages 455–467, Chemnitz, April, 23-25, 2002.
- [yue-j2024] Yue J. and others. Design, analysis and optimization of a novel redundant (6+1)-degree-of-freedom parallel mechanism with configurable platform:. *Mechanism and Machine Theory*, 192, 2024.
- [yue2010] Yue Y. and others. Relationship among input-force, payload, stiffness and displacement of a 3-DOF perpendicular parallel micro-manipulator. *Mechanism and Machine Theory*, 45(5):756–771, May 2010.
- [yufeng95] Yufeng L. and Tingli Y. Structure types and characteristics of six degree-of-freedom closed-chain manipulators with all actuators on base. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1795–1799, Milan, August 30- September 2, 1995.
- [yumei2000] Yumei H. and others . R&d of living assistant serial&parallel robot. Analysis of motion and function. In *IEEE Int. Workshop on Robot and Human Interactive Communication*, pages 427–429, Osaka, September, 27-29, 2000.
- [yun2011] Yun Y. and Li Y. Optimal design of a 3-PUPU parallel robot with compliant hinges for micromanipulator in a cubic workspace. *Robotics and Computer-Integrated Manufacturing*, 27(6):977–985, December 2011.
- [yuqi2017] Yuqi W. and others . Simulation experiment of flexible parallel robot control by RBF neural network based on sliding mode robust term. In 2nd Asia-Pacific Conference on Intelligent Robot Systems, 2017.
- [zabalza2002] Zabalza I. and others. Tri-Scott. a new kinematic structure for a 6-dof decoupled parallel manipulator. In Workshop on Fundamental Issues and Future Research Directions for Parallel Mechanisms and Manipulators, pages 12–15, Québec, October, 3-4, 2002.
- [zabalza2002-1] Zabalza I. and others . A variant of a 6-RKS Hunt-type parallel manipulator to easily use insensitivity position configurations. In *ARK*, pages 291–300, Caldes de Malavalla, June 29- July 2, 2002.
- [zabalza2007] Zabalza I. and Ros J. Synthesis of a 6-RUS parallel manipulator using its stationary configurations. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [zaccaria2022] Zaccaria F., Ida E., Briot S., and Carricato M. Workspace computation of planar continuum parallel robots. *IEEE Robotics and Automation Letters*, 7(2), April 2022.
- [zago98] Zago L. and others . Extremely compact secondary mirror unit for the SOFIA telescope capable of 6-degree-of-freedom alignment plus chopping. In *SPIE Astronomical Telescopes and Instrumentation*, Kona, March, 20-28, 1998.
- [zago2000] Zago L. and others . Development and testing of a high-precision, high-stiffness linear actuator for the focus-center mechanism of the SOFIA secondary mirror. In *SPIE Astronomical Telescopes and Instrumentation*, Munchen, March, 27-31, 2000.
- [zake2019] Zake Z. and others . Vision-based control and stability analysis of a cable-driven parallel robot. IEEE Robotics and Automation Letters, 4(2), April 2019.
- [zake2021-phd] Zake Z. Design and stability analysis of visual servoing on cable-driven parallel robots for accuracy improvement. Ph.D. Thesis, LS2N, Nantes, 2021. **Keywords:** wire robot, statics, stiffness, accuracy, control.
- [zamanov84] Zamanov V.B and Sotirov Z.M. Structures and kinematics of parallel topology manipulating systems. In *Proc. Int. Symp. on Design and Synthesis*, pages 453–458, Tokyo, July, 11-13, 1984.
- [zamanov89] Zamanov V.B and Sotirov Z.M. Duality in mechanical properties of sequential and parallel robots. In 20th Int. Symp. on Industrial robots (ISIR), pages 1041–1050, Tokyo, October, 4-6, 1989.
- [zamanov91] Zamanov V.B and Sotirov Z.M. A contribution to the serial and parallel manipulator duality. In 8th IFToMM World Congress on the Theory of Machine and Mechanisms, pages 517–520, Prague, August, 26-31, 1991.

- [zamanov92] Zamanov V.B and Sotirov Z.M. Parallel manipulators in robotics. In *IMACS/SICE Int. Symp. on Robotics, Mechatronics, and Manufacturing Systems*, pages 409–418, Kobe, September, 16-20, 1992.
- [zanganeh93] Zanganeh K.E. and Angeles J. The semigraphical solution of the direct kinematics of general platform-type parallel manipulators. In J. Angeles P. Kovacs, G. Hommel, editor, *Computational Kinematics*, pages 165–173. Kluwer, 1993. **Keywords:** forward kinematics.
- [zanganeh94] Zanganeh K.E. and Angeles J. Mobility and position analysis of a novel redundant parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3049–3054, San Diego, May, 8-13, 1994.
- [zanganeh94-1] Zanganeh K.E. and Angeles J. Instantaneous kinematics and design of a novel redundant parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 3043–3048, San Diego, May, 8-13, 1994.
- [zanganeh94-2] Zanganeh K.E. and Angeles J. The direct kinematics of general parallel manipulators with minimum sensor data. In *ISRAM*, pages 333–338, Hawaï, August, 14-18, 1994.
- [zanganeh94-3] Zanganeh K.E. and Angeles J. Instantaneous kinematics of modular parallel manipulators. In ASME Design Automation Conf., pages 271–277, Minneapolis, September, 11-14, 1994.
- [zanganeh95] Zanganeh K.E. and Angeles J. On the isotropic design of general six-degree-of-freedom parallel manipulators. In J-P. Merlet B. Ravani, editor, *Computational Kinematics*, pages 213–220. Kluwer, 1995. **Keywords:** jacobian, isotropy, design.
- [zanganeh96] Zanganeh K.E. and Angeles J. Displacement analysis of a six-degree-of-freedom hand controler. In *IEEE Int. Conf. on Robotics and Automation*, pages 1281–1286, Minneapolis, April, 24-26, 1996.
- [zanganeh96-1] Zanganeh K.E., Sinatra R., and Angeles J. Dynamics of a six-degree-of-freedom parallel manipulator with revolute legs. In *World Automation Congress*, volume 3, pages 817–822, Montpellier, May, 28-30, 1996.
- [zanganeh97] Zanganeh K.E. and Angeles J. Kinematic isotropy and the optimum design of parallel manipulators. *Int. J. of Robotics Research*, 16(2):185–197, April 1997.
- [zanganeh97-1] Zanganeh K.E., Sinatra R., and Angeles J. Kinematics and dynamics of a six-degree-of-freedom parallel manipulator with revolute legs. *Robotica*, 15(4):385–394, July August , 1997.
- [zanotto2014] Zanotto D. and others . Sophia-3: a semiadaptive cable-driven rehabilitation device with a tilting working plane. *IEEE Trans. on Robotics*, 30(4):974–979, August 2014.
- [zare2020] Zare S. and others . Kinematic analysis of an under-constrained cable- driven robot using neural networks. In 28 th Iranian Conference on Electrical Engineering (ICEE), 2020.
- [zare2022] Zare S. and others . Experimental study on the control of a suspended cable-driven parallel robot for object tracking purpose. *Robotica*, 40:3863–3877, 2022.
- [zarei2018] Zarei M. Oscillation damping of non linear control systems based on the phase trajectory length concept: an experimental case study on a cable-driven parallel robot. *Mechanism and Machine Theory*, 126:377–396, 2018.
- [zarkandi2011] Zarkandi S. A new geometric method for singularity analysis of spherical mechanisms. *Robotica*, 40(7):475–504, 2022.
- [zarkandi2022] Zarkandi S. Task-based torque minimization of a 3-P $\underline{P}$ RR spherical parallel manipulator. *Robotica*, 40:475–504, March 2022.
- [zarkandi2022-1] Zarkandi S. Dynamic modeling and power optimization of a  $4R\underline{P}PSP+PS$  parallel flight simulator machine. Robotica, 40:616-671, March 2022.
- [zavatta2020] Zavatta M. and others . A vision-based referencing procedure for cable-driven parallel manipulators. J. of Mechanisms and Robotics, 12(4), August 2020.
- [zeid94] Zeid A.A., Overholt J.L., and Beck R.R. Modeling of multibody systems for control using general purpose simulation languages. *Simulation*, 67(1):7–19, January 1994.

- [zein2006] Zein M., Wenger P., and Chablat D. Singular curves and cusp points in the joint space of 3-RPR parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 777–782, Orlando, May, 16-18, 2006.
- [zein2006-1] Zein M., Wenger P., and Chablat D. An algorithm for computing cusp points in the joint space of  $3-R\underline{P}R$  parallel manipulators. In 1st European Conf. on Mechanism Science (Eucomes), Obergurgl, February, 21-26, 2006.
- [zein2007] Zein M., Wenger P., and Chablat D. Singular curves in the joint space and cusp points of 3-R<u>P</u>R parallel manipulators. *Robotica*, 25(6):712–724, November 2007.
- [zein2007-1] Zein M., Wenger P., and Chablat D. Singularity surfaces and maximal singularity-free boxes in the joint space of planar 3-RPR parallel manipulators. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [zein2008] Zein M., Wenger P., and Chablat D. Non-singular assembly-mode changing motions of a  $3 R\underline{P}R$  parallel manipulators. *Mechanism and Machine Theory*, 43(4):480–490, April 2008.
- [zeiwali2007] Zeiwali M. and Notash L. Fuzzy modelbased adaptive robust control for parallel manipulators. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [zeng-q2011] Zeng Q., Fang Y., and Ehmann K.F. Design of a novel 4-dof kinematotropic hybrid parallel manipulator. ASME J. of Mechanical Design, 133(12):121006–1/9, December 2011.
- [zeng-q2012] Zeng Q. and Fang Y. Structural synthesis and analysis of serial-parallel hybrid mechanisms with spatial multi-loop kinematic chains. *Mechanism and Machine Theory*, 49:198–215, March 2012.
- [zeng-q2014] Zeng Q. and Ehmann K.F. Design of parallel hybrid-loop manipulators with kinematotropic property and deployability. *Mechanism and Machine Theory*, 71:1–26, January 2014.
- [zeng-q2014-1] Zeng Q., Ehmann K.F., and Cao J. Tri-pyramid robot: Design and kinematic analysis of a 3-dof translational parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 30(6):648–657, December 2014.
- [zeng-q2016] Zeng Q., Ehmann K.F., and Cao J. Design of general kinematropic mechanisms. *Robotics and Computer-Integrated Manufacturing*, 38:67–81, 2016.
- [zeng-q2016-1] Zeng Q., Ehmann K.F., and Cao J. Tri-pyramid robot: stiffness modeling of a 3-dof transational parallel manipulator. *Robotica*, 34(2):383–402, February 2016.
- [zeng-x2020] Zeng-x2020 . A parallel-guided compliant mechanism with variable stiffness based on layer jamming. Mechanism and Machine Theory, 148, 2020.
- [zeng2008] Zeng D., Huang Z., and Lu W. Performance analysis and optimal design of a 3-dof 3-RUR parallel mechanism. ASME J. of Mechanical Design, 130(4):042307–1/9, April 2008.
- [zhai98] Zhai S. User performance in relation to 3D input device design. Computer Graphics, 32(4):50–54, November
- [zhan2018] Zhan Z. and others. Error modelling and motion reliability analysis of a planar parallel manipulator with multiple uncertainties. *Mechanism and Machine Theory*, 124:55–72, 2018.
- [zhan2019] Zhan Z. and others. Unified motion reliability analysis and comparison study of planar parallel manipulators with interval joint clearance variables. *Mechanism and Machine Theory*, 138:58–75, 2019.
- [zhang-b2024] Zang B. and others. Synthetic design and analysis of the new feed cabin mechanism in five-hundred-meter aperture spherical radio telescope (FAST). *Mechanism and Machine Theory*, 191, 2024.
- [zhang-c2013] Zhan C. and Zhang L. Kinematic analysis and workspace investigation of a novel 2-dof parallel manipulator applied on vehicle driving simulator. *Robotics and Computer-Integrated Manufacturing*, 29(1):113–120, February 2013.
- [zhang-d2001] Zhang D. and Gosselin C.M. Kinetostatic modeling of N-DOF parallel mechanisms with a passive constraining leg and prismatic actuators. ASME J. of Mechanical Design, 123(3):375–384, September 2001.

- [zhang-d2002] Zhang D. and others. Design optimization of parallel kinematic toolheads with genetic algorithms. In 3rd Chemnitzer Parallelkinematik Seminar, pages 941–956, Chemnitz, April, 23-25, 2002.
- [zhang-d2002-1] Zhang D. and Gosselin C.M. Kinetostatic modeling of parallel mechanims with a passive constraining leg and revolute actuators. *Mechanism and Machine Theory*, 37(6):599–617, June 2002.
- [zhang-d2002-2] Zhang D. and Gosselin C.M. Parallel kinematic machine design with kinetostatic model. *Robotica*, 20(4):429–438, July 2002.
- [zhang-d2004] Zhang D. and others . Optimum design of parallel kinematic toolheads with genetic algorithm. *Robotica*, 22(1):77–84, January 2004.
- [zhang-d2005] Zhang D. and Wang L. Web-based remote manipulation in advanced manufacturing. In *IEEE Int. Workshop on Business Service Network*, Hong-Kong, 2005.
- [zhang-d2005-1] Zhang D. and Wang L. Conceptual development of an enhanced tripod mechanism for machine tool. Robotics and Computer-Integrated Manufacturing, 21(4-5):318-327, - October 2005.
- [zhang-d2005-2] Zhang D. On stiffness improvement of the tricept machine-tool. Robotica, 23(3):377–386, May 2005.
- [zhang-d2005-3] Zhang D., Wang L., and Lang S.Y.T. Parallel kinematic machines: design, analysis and simulation in an integrated virtual environment. ASME J. of Mechanical Design, 127(4):580–588, July 2005.
- [zhang-d2007] Zhang D., Wang L., and Esmailzadeh E. *Industrial Robotics, Theory, Modelling and Control*, chapter Web-based remote manipulation of parallel robot in advanced manufacturing system, pages 659–694. pro literatur Verlag, January 2007. **Keywords:** 3 dof robot, web.
- [zhang-d2009] Zhang D., Bi Z., and Li B. Design and kinetostatic analysis of a new parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 25(4-5):782–791, August 2009.
- [zhang-d2011] Zhang D. and Zhang F. Design and analysis of a totally decoupled 3-dof spherical parallel manipultator. *Robotica*, 29(7):1093–1100, December 2011.
- [zhang-d2011-1] Zhang D. and Lei J. Kinematic analysis of a novel 3-dof actuation redundant parallel manipulator using artificial intelligence approach. *Robotics and Computer-Integrated Manufacturing*, 27(1):157–163, February 2010.
- [zhang-d2011-2] Zhang D. and others . Static balancing and dynamic modeling of a three-degree-of-freedom parallel kinematic manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 470–475, Shangai, May, 9-13, 2011.
- [zhang-d2015] Zhang D. and Gao Z. Performance analysis and optimization of a five degrees-of-freedom hybrid parallel micromanipulator. *Robotics and Computer-Integrated Manufacturing*, 34:20–29, 2015.
- [zhang-d2017] Zhang D. and others. Kinematics, dynamics and stiffness analysis of a novel 3-dof kinematically/actuation redundant planar parallel mechanism. *Mechanism and Machine Theory*, 116:203–219, 2017.
- [zhang-f2018] Zhang F., Shang W., and Cong S. Choosing measurement configurations for kinematic calibration of cable-driven parallel robots. In 3rd Int. Conf. on Advanced Robotics and Mechatronics (ICARM), 2018.
- [zhang-gf-2004] Zhang G-F. and Gao X-S. Planar generalized Stewart platforms and their direct kinematics. In 5th Automated Deduction in Geometry (ADG), pages 198–211, Gainesville, September, 16-18, 2004.
- [zhang-gf-2012] Zhang G-F. Classification of direct kinematics to planar generalized Stewart platforms. *Computational geometry; Theory and Applications*, 45:485–473, 2012.
- [zhang-h2018] Zhang H. and others . Kinematic accuracy research of 2(3HUS+S) parallel manipulator for simulation of hip joint motion. *Robotica*, 36:1386–1401, 2018.
- [zhang-h2019] Zhang H. and others. A Newton-Raphson and BP neural network hybrid algorithm for forward kinematics of parallel manipulator. In 2nd WRC Symposium on Advanced Robotics and Automation, Beijing, August, 21, 2019.

- [zhang-hx-2007] Zhang H-X. and others. Runtime reconfiguration of a modular mobile robot with serial and parallel mechanisms. In *IEEE Int. Conf. on Intelligent Robots and Systems (IROS)*, pages 2999–3004, San Diego, September, 22-26, 2007.
- [zhang-j2011] Zhang J. and others . A 6-dof heavy-load parallel manipulator with RFTA and its application. In *IEEE Int. Conf. on Robotics and Automation*, pages 470–475, Shangai, May, 9-13, 2011.
- [zhang-j2014] Zhang J. and others . Kinematic calibration of a 2-dof translational parallel manipulator. *Advanced Robotics*, 28(10):707–714, 2014.
- [zhang-j2016] Zhang J., Zhao Y., and Jin Y. Kinetostatic-model-based stiffness analysis of Exechon PKM. *Robotics and Computer-Integrated Manufacturing*, 37:208–220, 2016.
- [zhang-j2020] Zhang J. and others . Modeling and experimental study of a novel multi-dof parallel soft robot. *IEEE Access*, 2020.
- [zhang-j2020-1] Zhang J. and others . Design and implementation of novel fractional-order controllers for stabilized platforms. *IEEE Access*, 2020.
- [zhang-k2010] Zhang K. and Dai J.S. Geometry and constraint analysis of the three-spherical kinematic chain based parallel mechanism. *J. of Mechanisms and Robotics*, 2(3), August 2010.
- [zhang-k2012] Zhang K., Dai J.S., and Fang Y. Constraint analysis and bifurcated motion of the 3PUP parallel mechanism. *Mechanism and Machine Theory*, 49:256–269, March 2012.
- [zhang-l2011] Zhang L. and Song Y. Optimal design of the Delta robot based on dynamics. In *IEEE Int. Conf. on Robotics and Automation*, pages 336–341, Shangai, May, 9-13, 2011.
- [zhang-lj-2006] Zhang L-J. and others . Analysis of the workspace of 2-dof spherical 5r parallel manipulator. In *IEEE Int. Conf. on Robotics and Automation*, pages 1123–1128, Orlando, May, 16-18, 2006.
- [zhang-md94] Zhang M.D. and Song S.M. Study of three-degree-of-freedom parallel platforms for reactional compensation. In *ISRAM*, pages 373–378, Hawaï, August, 14-18, 1994.
- [zhang-n2016] Zhang N. and Shang W. Dynamic trajectory planning of a 3-dof under-constrained cable-driven parallel robot. *Mechanism and Machine Theory*, 98:21–35, April 2016.
- [zhang-n2017] Zhang N., Shang W., and Cong S. Geometry-based trajectory planning of a 3-3 cable suspended parallel robot. *IEEE Trans. on Robotics*, 33(2):484–491, April 2017.
- [zhang-n2018] Zhang N., Huang P., and LI Q. Modeling, design and experiment of a remote-center-of-motion parallel manipulator for needle insertion. *Robotics and Computer-Integrated Manufacturing*, 50:193–202, 2018.
- [zhang-x2007] Zhang X., Mills J.K., and Cleghorn W.L. Dynamic modeling and experimental validation of a 3-PRR parallel manipulator with flexible intermediate links. *J. of Intelligent and Robotic Systems*, 50(4):324–340, December 2007.
- [zhang-x2009] Zhang X., Mills J.K., and Cleghorn W.L. Coupling characteristics of rigid body motion and elastic deformation of a 3-PRR parallel manipulator with flexible links. *Multibody System Dynamics*, 21:167–192, 2009.
- [zhang-x2010] Zhang X., Mills J.K., and Cleghorn W.L. Investigation of axial forces on dynamic propoerties of a flexible 3-PRR parallel manipulator moving with high speed. *Robotica*, 28(4):607–619, July 2010.
- [zhang-q2015] Zhang Q. and others . Dynamic model and input shaping control of a flexible link parallel manipulator considering the exact boundary conditions. *Robotica*, 33(6):1201–1230, July 2015.
- [zhang-x2016] Zhang X. and Zhang X. A comparative study of planar 3-RRR and 4-RRR mechanisms with joint clearances. *Robotics and Computer-Integrated Manufacturing*, 40:24–33, August 2016.
- [zhang-q2017] Zhang Q. and others . Smooth adaptive sliding mode vibration control of a flexible parallel manipulator with multiple smart linkages in modal space. *Journal of Sound and Vibration*, 411:1–19, 2017.
- [zhang-x2018] Zhang X. and Xu Q. Design, fabrication and testing of a novel symmetrical 3-dof large-stroke parallel micro/nano-positioning stage. *Robotics and Computer-Integrated Manufacturing*, 54:162–172, 2018.

- [zhang-q2019] Zhang Q. and others . Pose detection of parallel robot based on improved Hough-K-means and SURF algorithms. In *Jiangsu Annual Conference on Automation (JACA)*, 2019.
- [zhang-y-2000] Zhang Y. and Hesselbach J. Piezoelectric rotary-linear-actuators for miniaturised or micro parallel robot. In 7th Int. Conf. on New Actuators, pages 371–374, Bremen, June, 19-20, 2000.
- [zhang-y-2007] Zhang Y., Gong J., and Gao F. Singularity elimination of parallel mechanisms by means of redundant actuation. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [zhang-y-2009] Zhang Y., Liu H., and Wu X. Kinematics analysis of a novel parallel manipulator. *Mechanism and Machine Theory*, 44(9):1648–1657, September 2009.
- [zhang-y-2009-1] Zhang Y. and others . Workspace analysis of a novel 6-dof cable-driven parallel robot. In *IEEE International Conference on Robotics and Biomimetics*, Guilin, December, 19-23, 2009.
- [zhang-y98] Zhang Y. and Duffy J. The optimum quality index for a redundant 4-4 in parallel manipulator. In 12th RoManSy, pages 289–296, Paris, July, 6-9, 1998.
- [zhang-y2000] Zhang Y., Duffy J., and Crane C. The optimum quality index for a spatial redundant 4-8 in parallel manipulator. In ARK, pages 239–248, Piran, June, 25-29, 2000.
- [zhang-y2017] Zhang Y. and others . Zeroing dynamics based motion control scheme for parallel manipulators. *Electronic Letters*, 53(2):74–75, 2017.
- [zhang-y2018] Zhang Y. and others . CGA-based approach to direct kinematics of parallel mechanisms with the 3-RS structure. *Mechanism and Machine Theory*, 124:162–178, 2018.
- [zhang-y2018-1] Zhang Y. and others . Optimal zeroing dynamics with applications to control of serial and parallel manipulators. *Optim Control Appl Meth*, 39:1393–1406, 2018.
- [zhang-yc2002] Zhang Y-C. and Liu X-W. Force transmission index based workspace analysis of a six dof wire-driven parallel manipulator. In *ASME Design Engineering Technical Conference*, Montréal, September 29- October 2, 2002.
- [zhang-z2017] Zhang Z. and others. Optimal design of a high-speed pick-and-place cable-driven parallel robot. In 3rd Int. Conf. on cable-driven parallel robots (CableCon), Québec, 2017.
- [zhang-z2018] Zhang Z., Wang L., and Shao Z. Improving the kinematic performance of a planar 3-RRR parallel manipulator through actuation mode conversion. *Mechanism and Machine Theory*, 139:86–108, 2018.
- [zhang-z2019] Zhang Z., Cheng H.H., and Lau D. Efficient wrench-closure and interference-free conditions verification for cable-driven parallel robot trajectories using a ray-based method. *IEEE Robotics and Automation Letters*, 5(1):8–15, January 2019.
- [zhang-z2020] Zhang Z., Shao Z., and Wang L. Optimization and implementation of a high-speed 3-dofs translational cable-driven parallel robot. *Mechanism and Machine Theory*, 145, 2020.
- [zhang-z2020-1] Zhang Z. and others . Workspace analysis and optimal design of a translational cable-driven parallel robot with passive springs. *J. of Mechanisms and Robotics*, 12, October 2020.
- [zhang90] Zhang C-D. and Song S.M. Kinematics of parallel manipulators with a positional subchain. In ASME Proc. of the 21th Biennial Mechanisms Conference, volume 2, pages 271–278, Chicago, September, 16-19, 1990.
- [zhang91] Zhang C-D. and Song S.M. Forward kinematics of a class of parallel (Stewart) platforms with closed-form solutions. In *IEEE Int. Conf. on Robotics and Automation*, pages 2676–2681, Sacramento, April, 11-14, 1991.
- [zhang92] Zhang C-D. and Song S.M. Forward position analysis of parallel mechanisms with 3 general open-subchains based on selection of independent joints. In *ISRAM*, pages 377–384, Santa-Fe, November, 11-13, 1992.
- [zhang92-1] Zhang C-D. and Song S.M. Forward position analysis of nearly general Stewart platforms. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 81–87, Scottsdale, September, 13-16, 1992.

- [zhang93] Zhang C-D. and Song S.M. A efficient method for inverse dynamics of manipulators based on the virtual work principle. *J. of Robotic Systems*, 10(5):605–627, July 1993.
- [zhang94] Zhang C-D. and Song S-M. Forward position analysis of nearly general Stewart platform. ASME J. of Mechanical Design, 116(1):54–60, March 1994.
- [zhao-c2020] Zhao C. and others. Stiffness modeling of n(3RRIS) reconfigurable series-parallel manipulators by combining virtual joint method and matrix structural analysis. *Mechanism and Machine Theory*, 152, 2020.
- [zhao-c2020-1] Zhao C. and others . Deformation analysis of a novel 3-dof parallel spindle head in gravitational field. Mechanism and Machine Theory, 154, 2020.
- [zhao-f2024] Zhao F. and others. In-hand manipulation using a 3-PRS-finger-based parallel dexterous hand with bidirectional pinching capability. *Mechanism and Machine Theory*, 192, 2024.
- [zhao-js-2005] Zhao J-S. and others. Analysis of the singularity of spatial parallel manipulator with terminal constraints. *Mechanism and Machine Theory*, 40(3):275–284, March 2005.
- [zhao-js-2006] Zhao J-S. and others. Mobility properties of a Schoenflies-type parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 22(1):124–133, 2006.
- [zhao-js-2008] Zhao J-S., Chu F., and Feng Z-J. Symmetrical characteristics of the workspace for spatial parallel mechanisms with symmetric structure. *Mechanism and Machine Theory*, 43(4):427–444, April 2008.
- [zhao-js-2008-1] Zhao J-S., Chu F., and Feng Z-J. Parallel manipulators, Towards new applications, chapter Mobility of spatial parallel manipulators, pages 467–496. ITECH, April 2008. **Keywords:** mobility.
- [zhao-js-2014] Zhao J-S., Chu F-L., and Feng Z-J. Kinemaics of spatial parallel manipulators with tetrahedron coordinates. *IEEE Trans. on Robotics*, 30(1):233–243, February 2014.
- [zhao-q2019] Zhao Q., Guo J., and Hong J. Closed-form error space calculation for parallel/hybrid manipulators considering joint clearance, input uncertainty, and manufacturing imperfection. Mechanism and Machine Theory, 142, 2019.
- [zhao-q2020] Zhao Q., Guo J., and Hong J. Time-dependent system kinematic reliability analysis for planar parallel manipulators. *Mechanism and Machine Theory*, 152, 2020.
- [zhao-q2020-1] Zhao Q. and others . A novel approach to kinematic reliability analysis for planar parallel manipulators.  $ASME\ J.\ of\ Mechanical\ Design,\ 142,\ August\ 2020.$
- [zhao-r2020] Zhao R., Wu L., and Chen Y-H. Robust control for nonlinear delta parallel robot with uncertainty: an online estimation approach. *IEEE Access*, 2020.
- [zhao-t2017] Zhao T. and others . Type synthesis and analysis of rotational parallel mechanisms with a virtual continuous axis. *Mechanism and Machine Theory*, 109:139–154, 2017.
- [zhao-t2018] Zhao T. and others . Design and analysis of a cable-driven parallel robot for waist rehabilitation. In *Int. Conf. on Mechatronics, Robotics and Automation*, 2018.
- [zhao-t2019] Zhao T. and others . Typical configuration analysis of a modular reconfigurable cable-driven parallel robot. *International Journal of Advanced Robotic Systems*, 2019.
- [zhao-ts2016] Zhao T-S. and others . Stiffness and singularity analysis of foldable parallel mechanisms for ship-based stabilized platform. *Robotica*, 34(4):913–924, April 2016.
- [zhao-x2000] Zhao X. and Peng S. Uncertainty configurations of parallel manipulators. *Robotica*, 18(2):209–211, March 2000.
- [zhao-x2000-1] Zhao X. and Peng S. Direct displacement analysis of parallel manipulators. *J. of Robotic Systems*, 17(6):341–345, 2000.
- [zhao-x2017] Zhao X., Zi B., and Quian L. Design, analysis, and control of a cable-driven parallel platform with a pneumatic muscle active support. *Robotica*, 35(4):744–765, April 2017.

- [zhao-x2018] Zhao X. and others . Type synthesis and analysis of parallel mechanisms with sub-closed-loops. *Mechanism and Machine Theory*, 120:140–165, 2018.
- [zhao-y2007] Zhao Y. and others. Dynamics analysis of a 5-UPS/PRPU parallel machine tool. In 12th IFToMM World Congress on the Theory of Machines and Mechanisms, Besancon, June, 18-21, 2007.
- [zhao-y2009] Zhao Y. and Gao F. Inverse dynamics of the 6-dof out-parallel manipulator by means of the principle of virtual work. *Robotica*, 27(2):259–268, March 2009.
- [zhao-y2009-1] Zhao Y. and Gao F. Dynamic formulation and performance evaluation of the redundant parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 25(4-5):770–781, August 2009.
- [zhao-y2010] Zhao Y. and others . Elastodynamic charateristics comparison of the 8-PSS redundant parallel manipulator and its non-redundant counterpart- the 6-PSS parallel manipulator. *Mechanism and Machine Theory*, 45(2):291–303, February 2010.
- [zhao-y2011] Zhao Y. and Gao F. The joint velocity, torques and power capability evaluation of a redundant parallel manipulator. *Robotica*, 29(3):483–493, May 2011.
- [zhao-y2011-1] Zhao Y., Liu J.F., and Huang Z. A force analysis of a 3-RPS parallel mechanism by using screw theory. *Robotica*, 29(7):959–965, December 2011.
- [zhao-y2013] Zhao Y. Dimensional synthesis of a three translational degrees of freedom parallel robot while considering kinematic anisotropic property. *Robotics and Computer-Integrated Manufacturing*, 29(1):169–179, February 2013.
- [zhao-y2013-1] Zhao Y. Singularity isotropy and velocity transmission evulation of a three translational degree-of-freedo parallel robot. *Robotica*, 31(2):193–202, March 2013.
- [zhao-y2013-2] Zhao Y. Dynamic optimum design of a three translational degrees of freedom parallel robot while considering anisotropic property. *Robotics and Computer-Integrated Manufacturing*, 29(1):100–112, February 2013.
- [zhao-y2015] Zhao Y. and others. Inverse kinematics and rigid-body dynamics for a three rotational degrees of freedom parallel manipulator. *Robotics and Computer-Integrated Manufacturing*, 31:40–50, February 2015.
- [zhao-y2016] Zhao Y. Dynamic optimum design of a  $3U\underline{P}PS-\underline{P}RU$  parallel robot. International Journal of Advanced Robotic Systems, 2016.
- [zhao-y2017] Zhao Y. and others . Constant motion/force transmission analysis and synthesis of a class of translational parallel mechanisms. *Mechanism and Machine Theory*, 108:57–74, 2017.
- [zhao-y2017-1] Zhao Y. and Cheng G. Dimensional synthesis of a 3UPS-PRU parallel robot. *Robotica*, 35(12):2319–2329, 2017.
- [zhao-y2018] Zhao Y. and others . The constant balancing 6UPS/(3PRRR)+S parallel mechanism and its balancing performance analysis. *Mechanism and Machine Theory*, 126:79–91, 2018.
- [zhao-y2021] Zhao Y. and others . A new hierarchical approach for the optimal design of a 5-dof hybrid serial-parallel kinematic machine. *Mechanism and Machine Theory*, 150, 2021.
- [zhao-y2021-1] Zhao Y., J. Mei., and Niu W. Vibration error-based trajectory planning of a 5-dof hybrid machine tool. *Robotics and Computer-Integrated Manufacturing*, 69, 2021.
- [zhao95] Zhao M. and others . Development of a redundant robot manipulator based on three dof parallel platform. In *IEEE Int. Conf. on Robotics and Automation*, pages 221–226, Nagoya, May, 25-27, 1995.
- [zhao98] Zhao M. and others . Development of an advanced manufacturing system based on parallel robot manipulators. In 27th Int. Symposium on Robotics, pages 96–100, Birmingham, April 24- May 1, 1998.
- [zhen85] Zhen H. Modeling formulation of six-dof multi-loop parallel manipulator. In SYROM, volume II-1, pages 155–162, Bucarest, July, 4-9, 1985.

- [zheng-y2018] Zheng Y. and others. A Stewart isolator with high-static-low-dynamic stiffness struts based on negative stiffness magnetic springs. *Journal of Sound and Vibration*, 422:390–408, 2018.
- [zheng2016] Zheng K. and Zhang Q. Comprehensive analysis of the position error and vibration characteristics of Delta robot. Advanced Robotics, 30(20):1322–1340, 2016.
- [zhiyong2012] Zhuyong Y. and others . Digital platform-based multi-domain virtual prototype simulation on a high-speed parallel manipulator. *Robotica*, 30(5):827–835, September 2012.
- [zhou-q2020] Zhou Q. and others. Enumeration and optimum design of a class of translational parallel mechanisms with prismatic and parallelogram joints. *Mechanism and Machine Theory*, 150, 2020.
- [zhou-s2020] Zhou S., Sun J., and Gao F. Influence of flexible spherical joints parameters on accuracy of the six-axis force/torque sensor with three-three orthogonal parallel mechanism. *Mechanism and Machine Theory*, 145, 2020.
- [zhou-w2015] Zhou W. and others . A new forward kinematic algorithm for a general Stewart platform. *Mechanism and Machine Theory*, 87:177–190, 2015.
- [zhou-x2012] Zhou X., Tang C.P., and Krovi V. Analysis framework for cooperating mobile cable robots. In *IEEE Int. Conf. on Robotics and Automation*, pages 3128–3133, Saint Paul, May, 14-18, 2012.
- [zhou-x2014] Zhou X., S-K. Jun, and Krovi V. Tension distribution shaping via reconfigurable attachment in planar mobile cable robots. *Robotica*, 32(2):245–256, March 2014.
- [zhou-x2014-1] Zhou X., S-K. Jun, and Krovi V. Stiffness modulation exploiting configuration redundancy in mobile cable robots. In *IEEE Int. Conf. on Robotics and Automation*, Hong-Kong, 7 March 31- June, 2014.
- [zhou-y2011] Zhou Y. A closed-form algorithm for the least-squares trilateration problem. Robotica, 29:375–389, 2011.
- [zhou-z2006] Zhou H., Xi J., and Mechefske C.K. Modeling of a fully flexible 3PRS manipulator for vibration analysis. *ASME J. of Mechanical Design*, 128(2):403–412, March 2006.
- [zhou2003] Zhou K. and others . Singularity loci research on high speed travelling type of double four-rod spatial parallel mechanism. *Mechanism and Machine Theory*, 38(3):195–221, March 2003.
- [zhu-x2020] Zhu X. and others . Computer-aided mobility analysis of parallel mechanisms. *Mechanism and Machine Theory*, 148, 2020.
- [zhu2007] Zhu S-J., Huang Z., and Zhao M-Y. Singularity analysis for a 5-dof fully-symmetrical parallel manipulator 5-<u>RRR</u>(RR). In *IEEE Int. Conf. on Robotics and Automation*, pages 1189–1194, Roma, April, 10-14, 2007.
- [zhu2008] Zhu S-J., Huang Z., and Zhao M-Y. Parallel manipulators, Towards new applications, chapter Feasible human-spine motion simulators based on parallel manipulator, pages 497–506. ITECH, April 2008. **Keywords:** 5 dof robot,medical,mechanical architecture.
- [zhu2009] Zhu S-J., Huang Z., and Zhao M-Y. Singularity analysis for six practicable 5-dof fully-symmetrical parallel manipulators. *Mechanism and Machine Theory*, 44(4):710–725, April 2009.
- [zhuang91] Zhuang H. and Roth Z.S. A method for kinematic calibration of Stewart platforms. In ASME Annual Winter Meeting, volume 29, pages 43–49, Atlanta, December 1991.
- [zhuang93] Zhuang H. and Roth Z.S. Method for kinematic calibration of Stewart platforms. *J. of Robotic Systems*, 10(3):391–405, 1993.
- [zhuang96] Zhuang H. and Liu L. Self calibration of a class of parallel manipulators. In *IEEE Int. Conf. on Robotics and Automation*, pages 994–999, Minneapolis, April, 24-26, 1996.
- [zhuang97] Zhuang H. and Wang Y. A coordinate measuring machine with parallel mechanisms. In *IEEE Int. Conf.* on Robotics and Automation, pages 3256–3261, Albuquerque, April, 21-28, 1997.
- [zhuang 97-1] Zhuang H. Self calibration of parallel mechanisms with a case study on Stewart platform. *IEEE Trans. on Robotics and Automation*, 13(3):387–397, June 1997.

- [zhuang98] Zhuang H., Yan J., and Masory O. Calibration of Stewart platforms and other parallel manipulators by minimizing inverse kinematic residuals. *J. of Robotic Systems*, 15(7):395–405, 1998.
- [zi2008] Zi B. and others . Dynamic modeling and active control of a cable-suspended parallel robot. *Mechatronics*, 18(1):1–12, January 2008.
- [zi2011] Zi B., Zhu Z-C., and Du J-L. Analysis and control of the cable-supporting system including actuator dynamics. Control Eng. Practice, 19:491–501, 2011.
- [zi2014] Zi B. and others . Integrated mechanism design and control for completely restrained hybrid-driven based cable parallel manipulators. *J. of Intelligent and Robotic Systems*, 74(3):643–661, June 2014.
- [zi2015] Zi B., Lin J., and Quian S. Localization, obstacle avoidance planning and control of a cooperative cable parallel robot for multiple mobile cranes. *Robotics and Computer-Integrated Manufacturing*, 34:105–123, August 2015.
- [zi2017] Zi B., Su H., and Zhang D. Design, analysis and control of a winding hybrid-driven cable parallel manipulator. Robotics and Computer-Integrated Manufacturing, 48:196–208, December 2017.
- [zibil2007] Zibil A. and others . An explicit method for determining the force-moment capabilities of redundantly actuated planar-parallel manipulators. ASME J. of Mechanical Design, 129(10):1046–1055, October 2007.
- [zitzewitz2009] Zitzewitz J. and others . A versatile wire robot concept as a haptic interface for sport simulation. In *IEEE Int. Conf. on Robotics and Automation*, Kobe, May, 14-16, 2009.
- [zlatanov92] Zlatanov D., Dai M.Q., Fenton R.G., and Benhabib B. Mechanical design and kinematics analysis of a three-legged six degree-of-freedom parallel manipulator. In 22nd Biennial Mechanisms Conf., volume DE-45, pages 529–536, Scottsdale, September, 13-16, 1992.
- [zlatanov95] Zlatanov D., Fenton R.G., and Benhabib B. A unifying framework for classification and interpretation of mechanism singularities. ASME J. of Mechanical Design, 117(4):566–572, December 1995.
- [zlatanov98] Zlatanov D., Fenton R.G., and Benhabib B. Identification and classification of the singular configurations of mechanisms. *Mechanism and Machine Theory*, 33(6):743–760, August 1998.
- [zlatanov2001] Zlatanov D. and Gosselin C.M. A family of new parallel architectures with four degrees of freedom. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 57–66. EJCK, May, 20-22, 2001. **Keywords:** mechanical architecture, 4 dof robot.
- [zlatanov2001-1] Zlatanov D., Bonev I.A., and Gosselin C.M. Constraint singularities as configuration space singularities. September, 6, 2001, http://www.parallemic.org/Reviews/Review008.html. **Keywords:** singularity,3 dof robot.
- [zlatanov2001-2] Zlatanov D., Bonev I.A., and Gosselin C.M. Constraint singularities. July, 5, 2001, www.parallemic.org/Reviews/Review005.html. **Keywords:** singularity,3 dof robot.
- [zlatanov2002] Zlatanov D., Bonev I.A., and Gosselin C.M. Constraint singularities as configuration space singularities. In ARK, Caldes de Malavalla, June 29- July 2, 2002.
- [zlatanov2002-1] Zlatanov D., Bonev I.A., and Gosselin C.M. Constraint singularities of parallel mechanisms. In *IEEE Int. Conf. on Robotics and Automation*, pages 496–502, Washington, May, 11-15, 2002.
- [zobel96] Zobel P.B., Di Stefano P., and Raparelli T. The design of a 3 dof parallel robot with pneumatic drives. In 27th Int. Symp. on Industrial Robots (ISIR), pages 707–710, Milan, October, 6-8, 1996.
- [zoppi2003] Zoppi M. and others . Constraint singularities of force transmission in nonredundant parallel robots with less than six degrees of freedom. ASME~J.~of~Mechanical~Design,~125(3):557-563,~September~2003.
- [zoppi2004] Zoppi M., Bruzzone L.E., and Molfino R.M. Position analysis of a class of translational parallel mechanisms. *Int. J. of Robotics and Automation*, 19(3):111–116, 2004.
- [zoppi2004-1] Zoppi M., Bruzzone L.E., and Molfino R.M. A novel 5-dof interconnected-chains PKM for manufacturing revolute surfaces. In 4th Chemnitzer Parallelkinematik Seminar, Chemnitz, April, 20-21, 2004.

- [zoppi2005] Zoppi M. and Molfino R.M. Forward kinematics equations of a 3-dof hybrid PM for underwater camera active support. In *Fifth International Workshop on Robot Motion and Control*, 2005.
- [zoppi2006] Zoppi M., Zlatanov D., and Molfino R.M. On the velocity analysis of non-parallel closed chain mechanisms. In ARK, pages 65–72, Ljubljana, June, 26-29, 2006.
- [zoppi2008] Zoppi M., Sieklicki W., and Molfino R. Design of a micro-robotic wrist for needle laparoscopic surgery. ASME J. of Mechanical Design, 130(10):102306–1/102306–8, October 2008.
- [zoso2012] Zoso N. and Gosselin C.M. Point-to-point motion planning of a parallel 3-dof underconstrained cable-suspended robot. In *IEEE Int. Conf. on Robotics and Automation*, pages 2325–2330, Saint Paul, May, 14-18, 2012.
- [zsombor95] Zsombor-Murray P., Husty M., and Hartmann D. Singular Stewart-Gough platforms with spherocylindrical and spheroconical hip joint trajectories. In 9th IFToMM World Congress on the Theory of Machines and Mechanisms, pages 1886–1890, Milan, August 30- September 2, 1995.
- [zsombor2001] Zsombor-Murray P. and Gfrerrer A. Kinematics of a two-legged manipulator with actuated spherical joints. In F.C. Park C.C. Iurascu, editor, *Computational Kinematics*, pages 11–20. EJCK, May, 20-22, 2001. **Keywords:** mechanical architecture, kinematics, 6 dof robot.
- [zsombor2002] Zsombor-Murray P.J. and Cervantes-Sanchez J. 3-legged spatial 4-bar platform kinematics. In ARK, pages 379–386, Caldes de Malavalla, June 29- July 2, 2002.
- [zsombor2014] Zsombor-Murray P.J. Direct kinematics of an orthogonal 6PRRS parallel manipulator. In ARK, pages 21–29, Ljulbjana, June 29- July 3, 2014.
- [zubizarreta2008] Zubizarreta A. and others. Control of parallel robots using passive sensor data. In *IEEE Int. Conf.* on *Intelligent Robots and Systems (IROS)*, pages 2398–2403, Nice, France, September, 22-26, 2008.
- [zubizarreta 2010] Zubizarreta A. and others . Dynamic modeling of planar parallel robots considering passive joint sensor data. Robotica, 28(5):649-661, September 2010.
- [zubizarreta2011] Zubizarreta A. and others . A procedure to evaluate extended computed torque control configurations in the Stewart–Gough platform. *Robotics and Autonomous Systems*, 59:770–781, 2011.
- [zubizarreta2012] Zubizarreta A. and others . Redundant sensor based control of the 3RRR parallel robot. *Mechanism and Machine Theory*, 54:1–17, August 2012.
- [zubizarreta 2013] Zubizarreta A. and others . A redundant dynamic model of parallel robot for model-based control.  $Robotica,\ 31(2):203-216,\ March\ 2013.$
- [zuccon2023] Zucconn G. and others . Vibrations of cable-suspended rehabilitation robots. *Robotica*, 41:3702–3723, 2023.
- [zuo2002] Zuo A., Wu Q.M.J., and Gruver W.A. Stereo vision guided control of a Stewart platform. In *Int. Symp. on Intelligent Control*, pages 125–130, Vancouver, October, 27-30, 2002.