

From Kinematic Constraints to Singularities, Operation- and Working Modes of Parallel Manipulators

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Implicit algebraic constraint polynomials determine the overall kinematic behaviour of parallel kinematic structures. They provide insight in the global kinematics of many kinds of platform manipulators. In this talk we will present and discuss

- Methods to establish the sets of polynomial constraint equations.
- Forward and inverse kinematic map.
- Singularities of forward and inverse map.
- Operation and working modes of parallel manipulators.
- Some examples.