

CK 2017, PROGRAM OVERVIEW

7th International Workshop on Computational Kinematics (CK2017)						
Program						
	Sunday	Monday	Tuesday	Wednesday		
Time	21/05/2017	22/05/2017	23/05/2017	24/05/2017		
8:10		Registration				
9:00		Opening	S-4 Parallel Robots/ Optimization	S-7 Cable Robots		
9:30		Keynote Lecture	Keynote Lecture			
10:20	Coffee-break					
10:50		S-1.1 Theoretical Kinematics I	S-1.2 Path Planning	S-5.1 Theoretical Kinematics II	S-5.2 Application III	S-8.1 Theoretical Kinematics III
12:30					S-8.2 Planar Robots	
14:00	Lunch					
16:00		S-2.1 Parallel Robots I	S-2.2 Application I	S-6.1 Parallel Robots II	S-6.2 Dynamics	Social tour
16:30		Coffee-break				
17:30	Registration	S-3 Application II	Visit to the futuroscope			
18:10		Meeting of the IFToMM CK Committee	Gala dinner & Futuroscope night show			
		Welcome reception				

- ROOM A S-1.1: THEORETICAL KINEMATICS I
- ROOM B S-1.2: PATH PLANNING
- ROOM A S-2.1: PARALLEL ROBOTS I
- ROOM B S-2.2: APPLICATION I
- ROOM A S-3: APPLICATION II
- ROOM A S-4: PARALLEL ROBOTS/ OPTIMIZATION
- ROOM A S-5.1: THEORETICAL KINEMATICS II
- ROOM B S-5.2: APPLICATION III
- ROOM: A S-6.1: PARALLEL ROBOTS II
- ROOM: B S-6.2: DYNAMICS
- ROOM: A S-7: CABLE ROBOTS
- ROOM: A S-8.1: THEORETICAL KINEMATICS III
- ROOM: B S-8.2: PLANAR ROBOTS

CK 2017, DETAILED PROGRAM

MONDAY 22.05.2017

10:50 – 12:30, ROOM A ■ SESSION S-1.1: THEORETICAL KINEMATICS I

CHAIR BY: PHILIPPE WENGER

A NOVEL GEOMETRIC ANALYSIS OF THE KINEMATICS OF THE 3-RPS MANIPULATOR

MAMIDI TEJA KRISHNA, BASKAR ARAVIND, BANDYOPADHYAY SANDIPAN

CONSTRAINT EQUATIONS OF INVERTED KINEMATIC CHAINS

HUSTY MANFRED, STIGGER THOMAS

INTRUSION, PROXIMITY & STATIONARY DISTANCE

ZSOMBOR-MURRAY PAUL

LOCAL AND FULL-CYCLE MOBILITY ANALYSIS OF A 3-RPS-3-SPR SERIES-PARALLEL MANIPULATOR

NAYAK ABHILASH, CARO STÉPHANE, WENGER PHILIPPE

TOPOLOGY OPTIMIZATION OF A REACTIONLESS FOUR-BAR LINKAGE

BRIOT SÉBASTIEN, GOLDSZTEJN ALEXANDRE

10:50 – 12:30, ROOM B ■ SESSION S-1.2: PATH PLANNING

CHAIR BY: MANFRED HUSTY

MODEL REDUCTION METHODS FOR OPTIMAL FOLLOW-THE-LEADER MOVEMENTS OF BINARY ACTUATED, HYPER-REDUNDANT ROBOTS

TAPPE SVENJA, YU DAIRONG, KOTLARSKI JENS, ORTMAIER TOBIAS

MODELING AND KINEMATIC NONLINEAR CONTROL OF AERIAL MOBILE MANIPULATORS

ANDALUZ VICTOR, ORTIZ JESSICA, SILVA FRANKLIN, PROANO LUIS, PEREZ JOSE, ERAZO ALEX, CARVAJAL CHRISTIAN

PATH PLANNING BASED ON VISUAL FEEDBACK BETWEEN TERRESTRIAL AND AERIAL ROBOTS COOPERATION

ORTIZ JESSICA, ANDALUZ VICTOR, ZAPATA CRISTHIAN, VEGA ALEX

ADAPTATION OF THE GEOMETRIC MODEL OF A 6 DOF SERIAL ROBOT TO THE TASK SPACE

GUTIERREZ TAPIA JOSE, CHANAL HÉLÈNE, DURIEUX SÉVERINE, DUC EMMANUEL

OPTIMUM WALKING OF THE BIOLOID HUMANOID ROBOT ON A RECTILINEAR PATH

PAMANES ALFONSO, REYES GABRIELA, FIERRO JESUS, NUNEZ VICTOR

14:00 – 16:00, ROOM A ■ SESSION S-2.1: PARALLEL ROBOTS I

CHAIR BY: BRIOT SÉBASTIEN

AN APPROACH FOR TYPE SYNTHESIS OF OVERCONSTRAINED 1T2R PARALLEL MECHANISMS

DONG CHENGLIN, LIU HAITAO, LIU QI, SUN TAO, HUANG TIAN, CHETWYND DEREK

TRANSMISSION QUALITY EVALUATION FOR A CLASS OF FOUR-LIMB PARALLEL SCHOENFLIES-MOTION GENERATORS WITH ARTICULATED PLATFORMS

WU GUANGLEI, BAI SHAOPING, CARO STÉPHANE

FORWARD KINEMATICS OF THE GENERAL TRIPLE-ARM ROBOT USING A DISTANCE-BASED FORMULATION

THOMAS FEDERICO, ROJAS NICOLAS

STUDY OF REDUNDANTLY ACTUATED DELTA-TYPE PARALLEL KINEMATIC MECHANISMS

CORVES BURKHARD, SHAHIDI SEYED AMIRREZA, LORENZ MICHAEL, CHARAF EDDINE SAMI, HÜSING MATHIAS

3-RRR SPHERICAL PARALLEL ROBOT OPTIMIZATION WITH MINIMUM OF SINGULARITIES

CHAKER ABDELBADIA, JLASSI ASMA, MLIKA ABDELFAH

PARALLEL MANIPULATORS IN TERMS OF DUAL CAYLEY-KLEIN PARAMETERS

NAWRATIL GEORG

14:00 – 16:00, ROOM B ■ SESSION S-2.2: APPLICATIONS I

CHAIR BY: MARTIN PFURNER

KINEMATIC ANALYSIS FOR A PROSTATE BIOPSY PARALLEL ROBOT USING STUDY PARAMETERS

PISLA DOINA, BIRLESCU IOSIF, GHERMAN BOGDAN, TUCAN PAUL, VAIDA CALIN, PLITEA NICOLAE, CRISAN NICOLAE, RADU CORINA

KINEMATIC ANALYSIS OF ACTIVE ANKLE USING COMPUTATIONAL ALGEBRAIC GEOMETRY

KUMAR SHIVESH, NAYAK ABHILASH, BONGARDT BERTOLD, MUELLER ANDREAS, KIRCHNER FRANK

ROBUST DESIGN METHODOLOGY OF TOPOLOGICALLY OPTIMIZED COMPONENTS UNDER THE EFFECT OF UNCERTAINTIES

AMRITH RAJ JOSHUA, JAVED ARSHAD

CONTROL BASED ON LINEAR ALGEBRA FOR MOBILE MANIPULATORS

ANDALUZ VICTOR, VELASCO PAOLA, SASIG EDISON, CHICAIZA WILLIAM

OPTIMIZATION OF A REDUNDANT SERIAL SPHERICAL MECHANISM FOR ROBOTIC MINIMALLY INVASIVE SURGERY

NELSON CARL, LARIBI MED AMINE, ZEGHLOUL SAID

TOWARDS AN AUTONOMOUS AIRBORNE ROBOTIC AGENT

SOTO-GUERRERO DANIEL, RAMIREZ TORRES GABRIEL, GAZEAU JEAN-PIERRE

16:30 – 18:10, ROOM A ■ SESSION S-3: APPLICATIONS II

CHAired BY: SANDIPAN BANDYOPADHYAY

ERROR MODELLING AND SENSITIVITY ANALYSIS OF A PLANAR 3-PRP PARALLEL MANIPULATOR

MOHANTA JAYANT, MOHAN SANTHAKUMAR, HÜSING MATHIAS, CORVES BURKHARD

KINEMATICS AND BIFURCATION OF A TWOFOLD-SYMMETRIC 8-BAR LINKAGE

TANG ZHAO, ZLATANOV DIMITER, DAI JIAN SHENG

EVALUATING THE KNOT VECTOR TO SYNTHESIZE THE CAM MOTION USING NURBS

NGUYEN THI THANH NGA, KURTENBACH STEFAN, HÜSING MATHIAS, CORVES BURKHARD

KINEMATICS OF BIPLANETARY EPICYCLIC GEARS

ZAWISLAK STANISLAW

3D REVOLUTE JOINT WITH CLEARANCE IN MULTIBODY SYSTEMS

AKHADKAR NARENDRA, ACARY VINCENT, BROGLIATO BERNARD

TUESDAY 23.05.2017

8:10 – 9:30, ROOM A ■ SESSION S-4: PARALLEL ROBOTS -OPTIMIZATION

CHAired BY: FLORES PAULO

ROBUST OPTIMIZATION OF THE RAF PARALLEL ROBOT FOR A PRESCRIBED WORKSPACE

LARIBI MED AMINE, MIKA ABDELFAH, ROMDHANE LOTFI, ZEGHLOUL SAID

OPTIMAL DESIGN OF N-UU PARALLEL MECHANISMS

WU YUANQING, CARRICATO MARCO

ROBUST MULTI-OBJECTIVE DESIGN OPTIMIZATION OF THE 3-UPU TPM BASED ON THE GA-KRAWCZYK METHOD

EL HRAIECH SAFA, CHEBBI AHMED, AFFI ZOUHAIER, ROMDHANE LOTFI

MULTI-OBJECTIVE OPTIMIZATION OF A TRIPOD PARALLEL MECHANISM FOR A ROBOTIC LEG

RUSSO MATTEO, HERRERO SAIOA, CECCARELLI MARCO, ALTUZARRA OSCAR

10:50 – 12:30, ROOM A ■ SESSION S-5.1: THEORETICAL KINEMATICS II

CHAired BY: DAMIEN CHABLAT

APPLICATION OF INTERSECTION THEORY TO SINGULARITY AND MOTION MODE ANALYSIS OF MECHANISMS

PIIPPONEN SAMULI, MUELLER ANDREAS, HYRY EERO, TUOMELA JUKKA

RATIONAL PARAMETRIZATION OF LINEAR PENTAPOD'S SINGULARITY VARIETY AND THE DISTANCE TO IT

RASOULZADEH ARVIN, NAWRATIL GEORG

INVERSE KINEMATICS OF ANTHROPOMORPHIC ARMS YIELDING EIGHT COINCIDING CIRCLES

BONGARDT BERTOLD

OPTIMAL SYNTHESIS OF OVERCONSTRAINED 6R LINKAGES BY CURVE EVOLUTION

RAD TUDOR-DAN, SCHRÖCKER HANS-PETER

THE INSTANTANEOUS SCREW AXIS OF MOTIONS IN THE KINEMATIC IMAGE SPACE

PFURNER MARTIN, SCHADLBAUER JOSEF

10:50 – 12:30, ROOM B ■ SESSION S-5.2: APPLICATION III

CHAired BY: YUKIO TAKEDA

A NOVEL KINEMATIC MODEL OF SPATIAL FOUR-BAR LINKAGE RSPS FOR TESTING ACCURACY OF ACTUAL R-PAIRS WITH BALL-BAR

WANG ZHI, WANG DELUN, LI XIAOPENG, DONG HUIMIN, YU SHUDONG

4HAPTIC : A DEXTEROUS 4 D.O.FS HAPTIC DEVICE BASED ON DELTA ARCHITECTURE

PREAULT CELESTIN, SAAFI HOUSSEM, LARIBI MED AMINE, ZEGHLOUL SAID

KINEMATIC DESIGN OF A LIGHTING ROBOTIC ARM FOR OPERATING ROOM

SANDOVAL AREVALO JUAN SEBASTIAN, NOUAILLE LAURENCE, POISSON GERARD, PARMANTIER YVES

AUTONOMOUS MARCH CONTROL FOR HUMANOID ROBOT ANIMATION IN A VIRTUAL REALITY ENVIRONMENT

ANDALUZ VICTOR, GUAMAN SANTIAGO, SÁNCHEZ JORGE

ELASTOSTATIC MODELLING OF A WOODEN PARALLEL ROBOT

KACI LILA, BOUDAUD CLEMENT, BRIOT SEBASTIEN, MARTINET PHILIPPE

14:00 – 16:00, ROOM A ■ SESSION S-6.1: PARALLEL ROBOTS II

CHAIRER BY: CARL NELSON

DETERMINATION OF WORKSPACE VOLUME OF PARALLEL MANIPULATORS USING MONTE CARLO METHOD

CHAUDHURY ARKADEEP NARAYAN, GHOSAL ASHITAVA

KINEMATICS OF A 6-RUU PARALLEL ROBOTS WITH RECONFIGURABLE PLATFORMS

WU GUANGLEI, DONG HUIMIN

ON THE MOTION/FORCE TRANSMISSIBILITY AND CONSTRAINABILITY OF DELTA PARALLEL ROBOTS

BRINKER JAN, CORVES BURKHARD, TAKEDA YUKIO

A GEOMETRICAL APPROACH FOR THE SINGULARITY ANALYSIS OF A 3-RRS PARALLEL MANIPULATOR

TETIK HALIL, KIPER GOKHAN

THE COLLISION-FREE WORKSPACE OF THE TRIPTERON PARALLEL ROBOT BASED ON A GEOMETRICAL APPROACH

ATAEI PARNYAN, TALE MASOULEH MEHDI, ANVARI ZOLFA

A NOVEL 3T1R PARALLEL MANIPULATOR 2PARSS AND ITS KINEMATICS

SHEN HUIPING, SHAO GUOWEI, DENG JIAMING, YANG TING-LI

14:00 – 16:00, ROOM B ■ SESSION S-6.2: DYNAMICS

CHAIRER BY: ANDREAS POTT

A STUDY ON CONSTRAINTS VIOLATION IN DYNAMIC ANALYSIS OF SPATIAL MECHANISMS

PAULO FLORES

MOTION INTERPOLATION IN LIE SUBGROUPS AND SYMMETRIC SUBSPACES

SELIG JON, WU YUANQING, CARRICATO MARCO

KINEMATIC AND DYNAMIC MODELING AND BASE INERTIAL PARAMETERS DETERMINATION OF THE QUADRUPTERON PARALLEL MANIPULATOR

DANAEI BEHZAD DANAEI, ARIAN ALALEH, MASOULEH MEHDI TALE, KALHOR AHMAD

DYNAMIC ANALYSIS AND CONTROL OF A HYBRID SERIAL/CABLE DRIVEN ROBOT FOR LOWER-LIMB REHABILITATION.

ISMAIL MOURAD, LAHOUE SAMIR, ROMDHANE LOTFI

DYNAMIC SYNTHESIS OF A MULTIBODY SYSTEM: A COMPARATIVE STUDY BETWEEN GENETIC ALGORITHM AND PARTICLE SWARM OPTIMIZATION TECHNIQUES

BEN ABDALLAH MOHAMED AMINE, KEMILI IMED, LARIBI MED AMINE, AIFA OUI NIZAR

INHERENTLY BALANCED DOUBLE BENNETT LINKAGE

VAN DER WIJK VOLKERT

WEDNESDAY 24.05.2017

9:00 – 10:20, ROOM A ■ SESSION S-7: CABLE ROBOTS

CHAIRER BY: ERIKA OTTAVIANO

COMPUTING CROSS-SECTIONS OF THE WORKSPACE OF CABLE-DRIVEN PARALLEL ROBOTS WITH 6 SAGGING CABLES

MERLET JEAN-PIERRE

EFFICIENT COMPUTATION OF THE WORKSPACE BOUNDARY, ITS PROPERTIES AND DERIVATIVES FOR CABLE-DRIVEN PARALLEL ROBOTS

POTT ANDREAS

A CABLE-DRIVEN ROBOT FOR UPPER LIMB REHABILITATION INSPIRED BY THE MIRROR THERAPY

TAPPEINER LUKAS, OTTAVIANO ERIKA, HUSTY MANFRED

APPLICATION OF THE RIGID FINITE ELEMENT METHOD TO THE SIMULATION OF CABLE-DRIVEN PARALLEL ROBOTS

TEMPEL PHILIPP, SCHMIDT ANDREAS, HAASDONK BERNARD, POTT ANDREAS

10:50 – 12:30, ROOM A ■ SESSION S-8.1: THEORETICAL KINEMATICS III

CHAIRER BY: GEORG NAWRATIL

A NEW INSIGHT INTO THE COUPLER CURVES OF THE RCCC FOUR-BAR LINKAGE

THOMAS FEDERICO, PEREZ-GRACIA ALBA

A FORWARD KINEMATICS DATA STRUCTURE FOR EFFICIENT EVOLUTIONARY INVERSE KINEMATICS

STARKE SEBASTIAN, HENDRICH NORMAN, ZHANG JIANWEI

DIFFERENTIATION-FREE TAYLOR APPROXIMATION OF FINITE MOTION IN CLOSED LOOP KINEMATICS

DE JONG JAN, MUELLER ANDREAS, VAN DIJK JOHANNES, HERDER JUS

A NEW DIRECT POSITION ANALYSIS SOLUTION FOR AN OVER-CONSTRAINED GOUGH-STEWART PLATFORM

LUZI LUCA, SANCISI NICOLA, PARENTI CASTELLI VINCENZO

A GENERALIZED AND ANALYTICAL METHOD TO SOLVE INVERSE KINEMATICS OF SERIAL AND PARALLEL MECHANISMS USING FINITE SCREW THEORY

SUN TAO, YANG SHUOFEI, HUANG TIAN, DAI JIAN SHENG

10:50 – 12:30, ROOM B ■ SESSION S-8.2: PLANAR ROBOTS

CHAired BY: ABDELFAH MLIKA

KINETOSTATIC ANALYSIS AND SOLUTION CLASSIFICATION OF A PLANAR TENSEGRITY MECHANISM

WENGER PHILIPPE, CHABLAT DAMIEN

DESIGN OPTIMIZATION AND ACCURACY ANALYSIS OF A PLANAR 2PRP-PRR PARALLEL MANIPULATOR

SANTHAKUMAR MOHAN, CORVES BURKHARD, WENGER PHILIPPE

OPERATION MODES OF THE PLANAR 3-RRR MANIPULATOR

BASKAR ARAVIND, BANDYOPADHYAY SANDIPAN

THE IMPACT OF KINEMATIC REDUNDANCIES ON THE CONDITIONING OF A PLANAR PARALLEL MANIPULATOR

VITOR FONTES JOAO, VIEIRA HIPARCO, DA SILVA MAÍRA

HOLISTIC MODULAR MULTILAYER SYNTHESIS OF PLANAR LINKAGES USING PARAMETERIZED MASS PROPERTIES

HEINRICH STEFAN, BERGER MAIK

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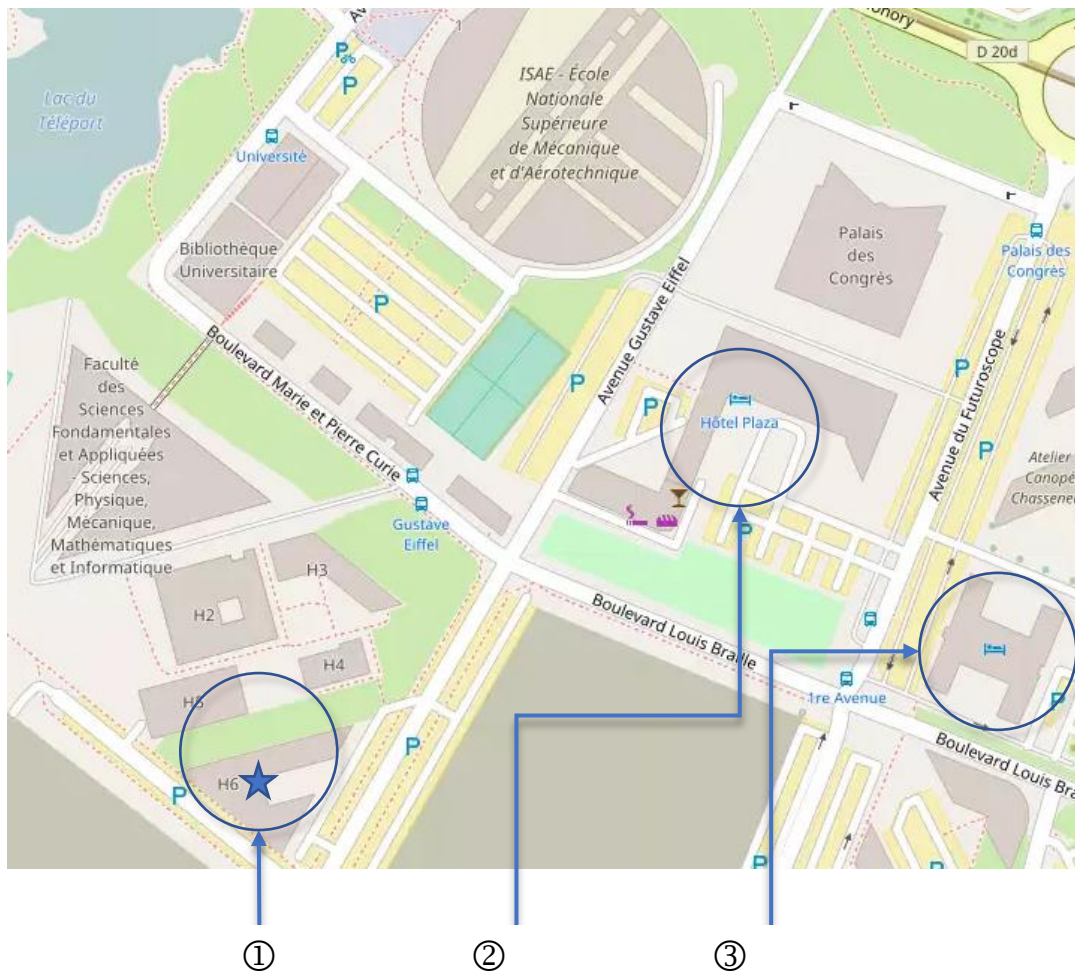
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Conference location



- ① : Localization of CK2017
- ② : Hotel Plaza
- ③ : Hotel Alteora

