# Review of parallel manipulator for various applications

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*Presented in International Conference on Advancements and Futuristic Trends in Mechanical and Materials Engineering held at Indian Institute of Technology Ropar (IITR), Rupnagar, during December 5-7, 2019.*

ABSTRACT

*This paper highlights, various applications of parallel manipulator having multiple degrees of freedom (DOF). Parallel manipulators are used in various fields such as industry, space, medical, fusion reactor, and virtual reality. Here the focus is given to nuclear fusion applications. A review of kinematic analysis and dynamic analysis has been described. Also, there is a discussion on the use of a flexible joint to increase the performance of the system.*

KEYWORDS

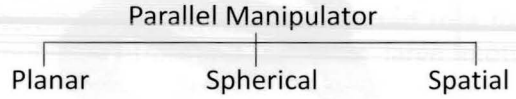
Parallel manipulator,
Delta robot,
Fusion,
Medical,
Industry.

## 1. Introduction

The parallel manipulator is a closed-loop structure used for the manipulation of end-effector. It has a fixed and mobile platform (end-effector) are connected with each other by at least two or more kinematic chains. Kinematic links are connected using universal joint, revolute joint, spherical joint or prismatic joint. These links control the position and orientation of the mobile platform. In 1954, Gough developed six DOF parallel manipulator with hydraulic jack for universal tire testing machine. In 1962 parallel mechanism was designed by Willard L.V. Pollard for automatic spray painting. The mechanism had five DOF, namely three positions and two rotations. In 1965, a paper was published by Steward on six DOF parallel platform for flight simulator (Merlet, 1993).

## 2. Classification of Parallel Manipulator

The parallel manipulator is categorized according to their nature of motion in three categories.




1. Planar parallel manipulator: The parallel manipulator in which kinematic links are on the same plane is defined as a planar parallel manipulator. It has a maximum of three degrees of freedom.
2. Spherical parallel manipulator: In spherical parallel manipulator, kinematic links are in the curve shape and motion of the mobile platform is controlled spherically. It has three degrees of freedom.
3. Spatial parallel manipulator: In spatial parallel manipulator, the mobile platform is moved in space with respect to the fixed platform. The spatial manipulator has more than three degrees of freedom, therefore, it has many applications.

## 3. Kinematic Analysis

The kinematic analysis deals with only the motion of the manipulator without considering the torques or forces. The study of the kinematics of the parallel manipulator is made for obtaining motion of the mobile platform. Kinematic analysis for the parallel manipulator is divided into two categories, forward kinematics and inverse kinematics (Peidong Wu, 2008). In forward kinematics, the joint variable is known, and the position of end-effector is obtained, while in the inverse kinematic position of end-effector is known and the value of the joint variable is obtained. Inverse kinematics for the parallel manipulator is easy but forward kinematics for the parallel manipulator is quite difficult because of multiple positions occurring for the same joint variable.

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conditions of constraints for Cable Driven robot are

- When n+1>m then it is in under constrained condition.
- When n+1=m then it is in fully constrained condition.
- When n+1<m then it is in redundantly constrained condition (Qian, Zi, Shang, & Xu, 2018)

### 7.2. Space application

The parallel mechanism is used in a satellite tracker system and simulation of the space vehicle. Katsuyoshi Tsujita et al. developed a test system where a parallel robot is used for gravity compensation of a space-craft (Tsujita, Shigematsu, & Kishimoto, 2014). The vibration caused due to Omni wheel of the parallel robot is isolated by the parallel robot itself as shown in Fig. 6.

### 7.3. Medical application

The parallel manipulator can be used in neurosurgery, spine surgery, ophthalmology, orthopaedic for total knee and hip replacement surgery. As shown in Fig. 7, Parallel manipulators are also used for surgical operations. It can manipulate the needle in six DOF. Due to high accuracy and precision, it provides minimum pain and higher efficiency by reducing the surgery time (Zhang,, Huang,, & Li, 2018).

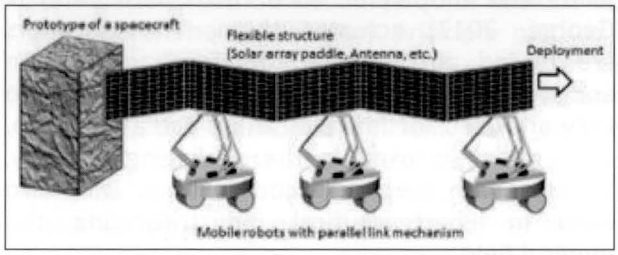


**Fig. 6.** System architecture (Tsujita, Shigematsu, & Kishimoto, 2014).

### 7.4. Virtual reality application

Dongsu Wu et al. developed a parallel manipulator for assisting head and neck motion by using a head-mounted device for virtual reality. As shown in Fig. 8, Dongsu Wu used 6-3 Universal-Prismatic-Spherical (UPS) Steward Platform. It consists of six powered legs, an upper platform, and a lower platform. Lower platform is attached with helmet (Wu,, Wang, & Li, 2016). The position and orientation of lower platform is controlled with the help of six legs.

### 7.5. Parallel manipulator in fusion application

Huapeng Wu et al. developed a Penta- WH parallel robot as shown in Fig. 9, for assembly or repair inside the tokamak vacuum vessel. It is used to perform welding, cutting, edge machining, smoothing and NDT control. This parallel robot can handle a weight of welding device up to 200kg for e-beam welding and for cutting, it can handle dynamic force up to 3 kN. The design of parallel robot Penta-WH consists of two parallel mechanisms, first for positioning in three axes and second for orientation in two axes. The third mechanism is for driving a robot on the carriage. Thus, Penta-WH parallel robot has six degree of freedom (Wu, Handroos, Pessi, Kilkki, & Jones, 2005).

Stanislao Grazioso et al., developed a hybrid kinematic mechanism. It is the combination of

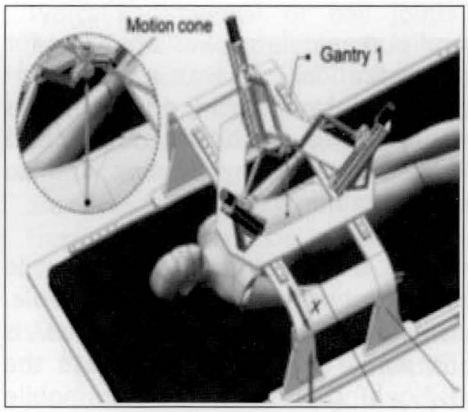


**Fig. 7.** Surgical robot for needle insertion (Zhang,, Huang,, & Li, 2018).

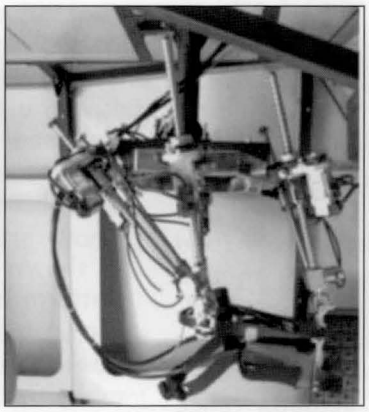

**Fig. 8.** Six DOF exoskeleton (Wu,, Wang, & Li, 2016).

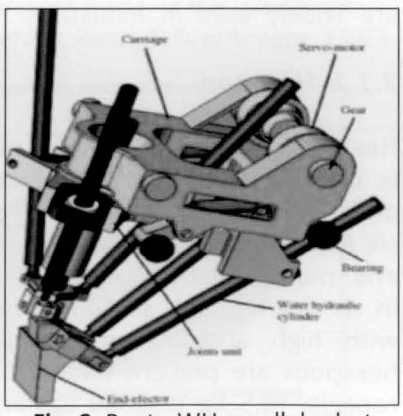


**Fig. 9.** Penta-WH parallel robot (Wu, Handroos, Pessi, Kilkki, & Jones, 2005).

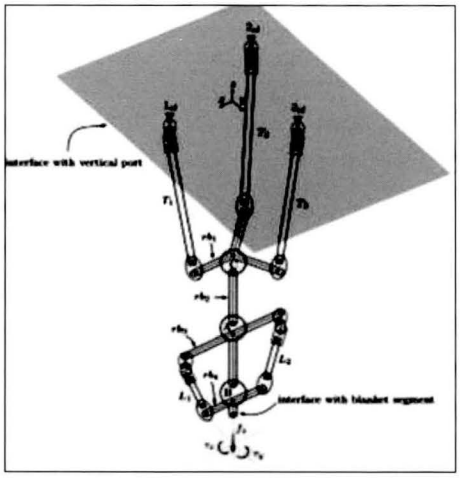


**Fig. 10.** Model of the hybrid kinematic mechanism (Graziosoa, Gironimoa, Iglesiasb, & Sicilianoa, 2019).

parallel and serial manipulator as shown in Fig. 10. The parallel section is used for positioning in space. At the end of the parallel manipulator, the serial manipulator is connected for providing rotation about the three axes. For the dynamics of hybrid kinematic mechanism, screw based formulation is used to prepare a dynamic model for simulation. It used as overhead cranes for the ex-vessel operations (Graziosoa, Gironimoa, Iglesiasb, & Sicilianoa, 2019).

## 8. Conclusion

This review work showcases different areas of applications of a parallel manipulator. It is used for gravity compensation in space and medical applications. In space, it is also used to create zero gravity condition and for vibration isolation in deployment of solar array panels. In medical field, it is used to counter balance manipulator's self-weight in gravity field for any configuration to the ease of operation on a patient by surgeons. Hexapods are used in flight and on-road vehicle simulators to give an immersive feeling to the user along with actual vibrations and jerks experienced in driving the same in real conditions. In the air force, it is used to train the newly recruited pilots, before handling the real fighter jets. Cable driven parallel robots are used in processing machinery, port cargo handling, bridge construction, welding and also used to control the cameras in stadiums. Penta-WH parallel robot is used for heavy payload handling and manipulation in fusion application. Hybrid combination of serial-parallel manipulator is used in which parallel manipulator is used for proper position in space and serial manipulator for providing rotation about the three axes. It also helps in understanding the different methods to solve the kinematics and dynamics of a parallel manipulator. This work is useful in further design and development of a parallel manipulator for heavy payload handling.

## Acknowledgement

Thanks to Institute for Plasma Research, Gandhinagar for allowing me to carry out review work and Remote Handling and Robotics Technology Division Members for their full-hearted co-operation in providing all the necessary data and detailed guidance during this review work.

## Disclaimer

The views and opinions expressed herein do not necessarily reflect those of Institute for Plasma Research, Gandhinagar.

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