List of Contents

Introduction **4**

1 Getting Started **5**

1.1 Minimum System Configuration 5

1.2 Installation 5

1.3 Starting the Program 5

2 User Interface **6**

2.1 Project Window 6

2.1.1 Worksheet 7

2.1.2 Tools Palette 7

2.2 Graphical Representation of Structural and Control Elements 10

2.3 Defining Parameters of Structural and Control Elements 11

2.3.1 Input Boxes of Revolute, Prismatic, Helical, Cylindrical and Global Joints 11

2.3.2 Input Box of User Defined Joints 13

2.3.3 Input Box of Bodies 14

2.3.4 Input Box of Control Elements 16

2.3.5 Input Dialog Box of Global-Global Constraint Elements 17

2.3.6 Input Dialog Box of Eben-Global Constraint Elements 18

2.3.7 Input Dialog Box of C-R-C Global Constraint Elements 19

2.3.8 Input Dialog Box of Global-Cylindrical Constraint Elements 20

2.4 Math Editor 21

2.5 Diagram 26

2.5.1 Function of the Point Picker tool and Markers 26

2.5.2 Configuring a Diagram 26

2.6 The Menus 28

2.6.1 The *File* Menu 29

2.6.2 The *Edit* Menu 30

2.6.3 The *Object* Menu 30

2.6.4 The *Chain* Menu 31

2.6.5 The *Computation* Menu 32

2.7 Exporting Data 34

2.7.1 Naming Conventions for the Exported Data 34
2.7.2 The *Export Interface* *35*

3 Theoretical Background 39

3.1 Kinematic Systems 39

3.2 Elements of Kinematic Systems 40

3.2.1 Rigid Body 40
3.2.2 Joints (Kinematic Pairs) 40
3.2.3 Constraint Elements 46
3.2.4 Control Elements 48
3.2.5 Denavit-Hartenberg Parameters (DH Parameters) 49

4 Examples 51

4.1 Single Loop Mechanisms 52

4.1.1 RPHC2R Linkage 52

4.2 3RC2R Linkage 53

4.3 Stewart Platform 54

4.4 Examples with User Defined Joints 55

4.4.1 An Example of a Manipulator of the Type PUMA. 55
4.4.2 Stewart Platform with Prescribed Motion 57

4.5 Multiple Loop Mechanisms 59

4.5.1 The Cage-Cube Mechanism 59
4.5.2 Spatial Straight- Line Linkage 60

5 Literature 62