http://dx.doi.org/10.1080/14686996.2019.1610668
[2] Zhang, F., Cai, L., Li, W., Huang, F. (2016). Design of automatic labeling system on the end surfaces of bundles of round steels. Journal of Hebei University of Science and Technology, 37(6): 601-608. http://doi.org/10.7535/hbkd.2016yx06012
[3] Li, Y., Sato, H. (2018). Insect-computer hybrid robot. Molecular Frontiers Journal, 2(1): 30-42. http://dx.doi.org/10.1142/S2529732518500025
[4] Petko, M., Gac, K., Góra, G., Karpiel, G., Ochoński, J., Kobus, K. (2016). CNC system of the 5-axis hybrid robot for milling. Mechatronics, 37: 89-99. http://dx.doi.org/10.1016/j.mechatronics.2016.03.001
[5] Wen, K., Gosselin, C. (2019). Kinematically redundant hybrid robots with simple singularity conditions and analytical inverse kinematic solutions. IEEE Robotics and Automation Letters, 4(4): 3828-3835. http://dx.doi.org/10.1109/LRA.2019.2928756
[6] Fajardo-Pruna, M., López-Estrada, L., Pérez, H., Diez, E., Vizán, A. (2019). Analysis of a single-edge micro cutting process in a hybrid parallel-serial machine tool. International Journal of Mechanical Sciences, 151: 222-235. http://dx.doi.org/10.1016/j.ijmecsci.2018.11.023
[7] Moosavian, A., Zhu John Sun, C., Inman, D.J. (2017). Dimensional synthesis of a multiloop linkage with single input using parameterized curves. Journal of Mechanisms and Robotics, 9(2): 1-25. http://dx.doi.org/10.1115/1.4035799
[8] Martínez, S., Rueda, M., Martínez, H., Arcos, A. (2017). Optimal dimension and optimal auxiliary vector to construct calibration estimators of the distribution function. Journal of Computational and Applied Mathematics, 318: 444-459. https://doi.org/10.1016/j.cam.2016.02.002
[9] Petko, M., Karpiel, G., Gac, K., Góra, G., Kobus, K., Ochoński, J. (2016). Trajectory tracking controller of the hybrid robot for milling. Mechatronics, 37: 100-111. http://dx.doi.org/10.1016/j.mechatronics.2016.03.012
[10] Mariolo, A.V., Casiraghi, M., Galetta, D., Spaggiari, L. (2018). Robotic hybrid approach for an anterior pancoast tumor in a severely obese patient. The Annals of Thoracic Surgery, 106(3): e115-e116. https://doi.org/10.1016/j.mechatronics.2016.03.012
[11] Préault, C., Saafi, H., Laribi, M.A., Zeghloul, S. (2019). Optimal design and evaluation of a dexterous 4 DoFs haptic device based on delta architecture. Robotica, 37(7): 1267-1288. https://doi.org/10.1017/S0263574718000929
[12] Ilyushin, Y.V., Pervukhin, D.A., Afanasieva, O.V., Afanasyev, M.P., Kolesnichenko, S.V. (2015). The methods of the synthesis of the nonlinear regulators for the distributed one-dimension control objects. Modern Applied Science, 9(2): 54-67. http://dx.doi.org/10.5539/mas.v9n2p42
[13] Saadatzi, M.H., Masouleh, M.T., Taghirad, H.D. (2012). Workspace analysis of 5-PRUR parallel mechanisms (3T2R). Robotics and Computer-Integrated Manufacturing, 28(3): 437-448. http://dx.doi.org/10.1016/j.rcim.2011.12.002
[14] Schappler, M., Tappe, S., Ortmaier, T. (2019). Modeling Parallel robot kinematics for 3T2R and 3T3R tasks using reciprocal sets of Euler angles. Robotics, 8(3): 68-92. http://dx.doi.org/10.3390/robotics8030068
[15] Schappler, M., Tappe, S., Ortmaier, T. (2019). Resolution of functional redundancy for 3T2R robot tasks using two sets of reciprocal Euler angles. In IFToMM World Congress on Mechanism and Machine Science, 1701-1710. http://dx.doi.org/10.1007/978-3-030-20131-9_168
[16] Amine, S., Masouleh, M.T., Caro, S., Wenger, P., Gosselin, C. (2012). Singularity analysis of 3T2R parallel mechanisms using Grassmann-Cayley algebra and Grassmann geometry. Mechanism and Machine Theory, 52: 326-340. http://dx.doi.org/10.1016/j.mechmachtheory.2011.11.015
[17] Chang, T.H., Chen, S.L., Kang, C.A., Inasaki, I. (2002). Design optimization of the linkage dimension for a hybrid-type parallel kinematic machine tool. Proceedings of the Institution of Mechanical Engineers, Part K: Journal of Multi-body Dynamics, 216(2): 143-156. http://dx.doi.org/10.1243/14644190260070385
[18] Chen, D., Zhang, Y., Li, S. (2017). Tracking control of robot manipulators with unknown models: A Jacobian-matrix-adaption method. IEEE Transactions on Industrial Informatics, 14(7): 3044-3053. http://dx.doi.org/10.1109/TII.2017.2766455
[19] Crisan, A., Negrean, I. (2019). The Jacobian matrix based on the transfer matrices. ACTA Technica Napocensis-Series: Applied Mathematics, Mechanics, and Engineering, 62(1): 135-140.
[20] Wu, L., Crawford, R., Roberts, J. (2017). An analytic approach to converting POE parameters into D-H parameters for serial-link robots. IEEE Robotics and Automation Letters, 2(4): 2174-2179. http://dx.doi.org/10.1109/LRA.2017.2723470
[21] Singh, A., Singla, A., Soni, S. (2015). Extension of DH parameter method to hybrid manipulators used in robot-assisted surgery. Proceedings of the Institution of Mechanical Engineers, Part H: Journal of Engineering in Medicine, 229(10): 703-712. https://doi.org/10.1177/0954411915602289
[22] Safeea, M., Neto, P., Bearee, R. (2019). Robot dynamics: A recursive algorithm for efficient calculation of Christoffel symbols. Mechanism and Machine Theory, 142: 103589. https://doi.org/10.1016/j.mechmachtheory.2019.103589
[23] Xie, B., Maciejewski, A.A. (2017). Structure and performance analysis of the 7! robots generated from an optimally fault tolerant Jacobian. IEEE Robotics and Automation Letters, 2(4): 1956-1963. http://dx.doi.org/10.1109/LRA.2017.2715879
[24] Vieira, H.L., Fontes, J.V., Beck, A.T., da Silva, M.M. (2019). Reliable and failure-free workspaces for motion planning algorithms for parallel manipulators under geometrical uncertainties. Journal of Computational and Nonlinear Dynamics, 14(2): 021005. http://dx.doi.org/10.1115/1.4042015
[25] Gouttefarde, M., Collard, J.F., Riehl, N., Baradat, C. (2015). Geometry selection of a redundantly actuated cable-suspended parallel robot. IEEE Transactions on Robotics, 31(2): 501-510. http://dx.doi.org/10.1109/TRO.2015.2400253
[26] Choe, Y., Kang, C.H., Kim, S., Park, C.G. (2018). INS/GPS deep integration using frobenius norm based adaptive filter with two adaptation parameters. Journal of Institute of Control, Robotics and Systems, 24(8): 716-721. http://doi.org/10.5302/J.ICROS.2018.0090