

SUMMARY

The diploma projet comprises: 60 pages, 30 figures and graphical part on 3 pages A1.

The purpose of the work is to create a model of delta-manipulator and explore its capabilities.

During the work, an analytical review of existing types of parallel delta robot designs, their features and area of use was conducted. On the basis of the analysis of the devices under consideration, a manipulator with three closed kinematic chains and three degrees of freedom was selected. The calculation of the kinematics of the manipulator is carried out. The system of different trajectories was worked out and charts were displayed.

DELTA-MANIPULATOR, KINEMATICS, KINEMATIK CHAIN, MODEL, MATLAB SIMULINK, SOLIDWORKS, SIMMECHANICS.

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| | | | | | 6.050702.4211.018.BW | | | | | |
| Зм. | Лист | № докум. | Підп. | Дата | Summary Control system of DELTA robot | | | L. | Page | Pages |
| Developed | Lysenko M.S. | | | | | | | 7 | 60 | |
| Checked | Dymko S.S. | | | | | | | | | |
| T. control | | | | | | | | | | |
| N. control | | | | | | | | | | |
| Approved | Peresada S.M. | | | | | | | NTUU "Igor Sikorsky Kyiv Politechnic Institute", FEA, AEMS-EP,EP-42 group | | |