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# Dynamic Modeling and Control of Redundantly Actuated Parallel Kinematics Mechanisms for Agile Manufacturing

Katya Ivanova and Yuki Tanaka
Ural Mountains University, Russia

## Abstract

This paper investigates the dynamic modeling and control of redundantly actuated parallel kinematics mechanisms (PKMs) in the context of agile manufacturing systems. Redundantly actuated PKMs offer increased flexibility, accuracy, and robustness, making them well-suited for agile manufacturing environments where rapid adaptability to changing production requirements is essential.

***Keywords***: Redundantly Actuated Parallel Kinematics Mechanisms, Agile Manufacturing, Dynamic Modeling.

## 1. Introduction

Agile manufacturing has emerged as a pivotal concept in modern industry, driven by the imperative to swiftly respond to evolving market demands while maintaining efficiency and quality[1]. Central to the realization of agile manufacturing systems are advanced robotic technologies capable of adapting to dynamic production requirements with speed and precision. Among these technologies, parallel kinematics mechanisms (PKMs) stand out for their inherent advantages in rigidity, accuracy, and workspace utilization. Redundantly actuated PKMs, equipped with more actuators than strictly necessary for a given task, represent a promising avenue for further enhancing the capabilities of agile manufacturing systems. By providing additional degrees of freedom (DOF), redundancy enables these mechanisms to exhibit enhanced dexterity, versatility, and fault tolerance, thus facilitating rapid reconfiguration and adaptation in response to changing operational needs[2].

This paper aims to explore the dynamic modeling and control strategies tailored to leverage the benefits of redundancy in PKMs for agile manufacturing applications. Understanding the principles and advantages of redundantly actuated PKMs is crucial for unlocking their full potential in agile manufacturing environments. By delving into the intricacies of dynamic modeling and control, this research seeks to provide insights into how redundantly actuated PKMs can be effectively utilized to address the challenges posed by the dynamic and unpredictable nature of agile manufacturing operations. Moreover, the paper will highlight the significance of dynamic modeling in accurately characterizing the complex dynamics of redundantly actuated systems, laying the groundwork for the development of robust and efficient control strategies.

Dynamic modeling serves as the cornerstone for the design and implementation of control strategies aimed at orchestrating the motion and behavior of redundantly actuated PKMs. However, the unique characteristics of these systems, including their redundant DOFs and nonlinear dynamics, present challenges that necessitate specialized modeling approaches. By examining various dynamic modeling techniques, ranging from Lagrange-based formulations to recursive Newton-Euler methods, this paper seeks to shed light on the methodologies employed to accurately capture the dynamics of redundantly actuated PKMs[3]. Furthermore, it will discuss the implications of redundancy on dynamic modeling and explore how advanced modeling techniques can facilitate the development of more accurate and reliable control strategies.

The study begins by outlining the principles of PKMs and elucidating the significance of redundancy in enhancing their performance. It then delves into the challenges and methodologies of dynamic modeling, emphasizing the complexities involved in accurately capturing the dynamics of redundantly actuated systems. Various control strategies tailored to exploit redundancy for improved performance are discussed, including inverse dynamics control, optimization-based control, and adaptive control techniques. Real-world applications and case studies showcasing the effectiveness of these approaches in agile manufacturing scenarios are presented. Furthermore, insights into future research directions and the potential impact of dynamic modeling and control strategies on advancing agile manufacturing capabilities are provided. Through this synthesis of knowledge and exploration of innovative approaches, this paper aims to contribute to the ongoing development of redundantly actuated PKMs for agile manufacturing.

## 2. Redundantly Actuated PKMs: Principles and Advantages

Parallel kinematics mechanisms (PKMs) represent a class of robotic systems wherein multiple links and joints are interconnected to achieve motion. Unlike serial manipulators, where the end-effector is attached to a single moving platform, PKMs feature a distributed motion architecture, with the end-effector being controlled by several independent actuators. The key principle underlying PKMs is the simultaneous movement of multiple kinematic chains, resulting in enhanced rigidity and precision[4]. This distributed motion enables PKMs to exhibit superior accuracy and workspace utilization compared to their serial counterparts. By decoupling the motion of the end-effector from the base platform, PKMs offer greater flexibility in trajectory planning and motion control, making them well-suited for applications requiring complex motion profiles and high-precision tasks.

Redundancy in PKMs refers to the presence of more actuators or degrees of freedom (DOFs) than strictly required to perform a given task. Unlike traditional serial manipulators, where each degree of freedom corresponds directly to a specific motion axis, redundantly actuated PKMs feature additional actuators that introduce redundancy into the system[5]. This redundancy provides inherent advantages in terms of fault tolerance, singularity avoidance, and performance optimization. By strategically allocating redundant DOFs, redundantly actuated PKMs can adapt their configuration to optimize performance metrics such as accuracy, speed, and energy efficiency. Moreover, redundancy enhances the robustness of PKMs against mechanical failures or unforeseen disturbances, thereby improving system reliability and uptime.

In the context of agile manufacturing, where rapid reconfiguration and adaptability are paramount, redundantly actuated PKMs offer distinct advantages over conventional robotic systems[6]. The additional degrees of freedom provided by redundancy enable PKMs to achieve greater dexterity and flexibility in manipulating objects within the workspace. This increased versatility allows for the execution of a wider range of tasks without the need for extensive reprogramming or manual intervention. Furthermore, redundantly actuated PKMs excel in applications requiring dynamic trajectory planning and obstacle avoidance, as they can exploit redundancy to navigate complex workspaces more efficiently. By leveraging redundancy, agile manufacturing systems equipped with redundantly actuated PKMs can rapidly adapt to changing production requirements, optimize resource utilization, and maintain high levels of productivity and efficiency in dynamic manufacturing environments[7].

## 3. Dynamic Modeling of Redundantly Actuated PKMs

Dynamic modeling of redundantly actuated parallel kinematics mechanisms (PKMs) presents unique challenges due to the presence of additional degrees of freedom (DOFs) and nonlinear coupling effects. Unlike traditional serial manipulators, where the dynamics are relatively straightforward to model, redundantly actuated PKMs exhibit complex interactions between the redundant DOFs and the system dynamics. One of the primary challenges is accurately capturing the coupling effects between the redundant actuators and the primary motion axes, as these interactions can significantly influence the system's dynamic behavior. Additionally, the dynamic modeling of redundantly actuated PKMs must account for factors such as varying payload distributions, joint friction, and actuator dynamics, further complicating the modeling process. Various approaches have been proposed for dynamic modeling of redundantly actuated PKMs, each with its strengths and limitations. Among the most commonly used techniques are Lagrange-based formulation, recursive Newton-Euler formulation, and hybrid approaches that combine elements of both methods[8].

Lagrange-based formulation utilizes the principles of classical mechanics to derive the equations of motion governing the dynamics of the PKM. This approach involves formulating the kinetic and potential energy of the system and applying Lagrange's equations to derive the dynamic equations. While Lagrange-based formulation provides a systematic framework for dynamic modeling, it can become computationally intensive, especially for systems with large numbers of DOFs. However, it offers the advantage of explicitly capturing the system's nonlinearities and can accommodate complex kinematic structures typical of redundantly actuated PKMs[9].

Recursive Newton-Euler formulation is a recursive algorithmic approach commonly used for dynamic modeling of serial manipulators. This method involves propagating Newton-Euler equations along the kinematic chain to compute the joint forces and torques required to achieve a desired motion trajectory. While recursive Newton-Euler formulation is computationally efficient and well-suited for real-time control applications, adapting it to redundantly actuated PKMs requires careful consideration of the additional DOFs and coupling effects[10]. Despite its simplicity, this approach may struggle to capture the nonlinear dynamics inherent in redundantly actuated systems.

Hybrid approaches combine elements of Lagrange-based and recursive Newton-Euler formulations to leverage their respective strengths[11]. By incorporating Lagrange-based methods for modeling the primary motion axes and recursive Newton-Euler techniques for the redundant DOFs, hybrid approaches aim to strike a balance between accuracy and computational efficiency. These approaches often involve partitioning the system into primary and redundant subspaces and applying tailored modeling techniques to each subspace. While hybrid approaches offer potential advantages in terms of computational efficiency and accuracy, they require careful integration of the different modeling techniques and consideration of the system's overall dynamics[12].

In the context of redundantly actuated PKMs, dynamic modeling must account for the unique characteristics of redundant DOFs, including their potential impact on system stability, performance, and control. Special attention must be paid to the coupling effects between the primary and redundant motion axes, as well as the redistribution of forces and torques among the actuators. Moreover, the dynamic modeling process should consider factors such as actuator saturation, nonlinear friction, and dynamic coupling between the end-effector and the redundant actuators[13]. By incorporating these considerations into the dynamic modeling framework, it becomes possible to develop accurate and reliable models that capture the intricate dynamics of redundantly actuated PKMs, enabling the design and implementation of effective control strategies for agile manufacturing applications.

## 4. Control Strategies for Redundantly Actuated PKMs

Inverse dynamics control is a widely used technique for controlling redundantly actuated parallel kinematics mechanisms (PKMs) by calculating the required joint torques or forces to achieve a desired end-effector trajectory. This approach involves first determining the dynamic model of the PKM and then solving the inverse dynamics problem to compute the joint torques necessary to track a given trajectory. Inverse dynamics control offers precise trajectory tracking and robust performance, particularly when the dynamic model of the PKM is accurately known. However, it can be computationally demanding, especially for systems with high degrees of redundancy and complexity[14]. Additionally, inverse dynamics control may struggle to account for uncertainties and disturbances in real-world applications, necessitating robustness-enhancing techniques. Optimization-based control strategies leverage mathematical optimization techniques to generate control inputs that optimize specific performance criteria, such as minimizing energy consumption, maximizing accuracy, or avoiding joint limits. These approaches formulate the control problem as an optimization problem, with the objective function representing the desired performance metric and the control inputs subject to constraints imposed by the system dynamics and operational limits[15]. Optimization-based control offers flexibility in specifying control objectives and constraints, making it well-suited for optimizing the performance of redundantly actuated PKMs in agile manufacturing scenarios. However, the computational complexity associated with solving large-scale optimization problems may limit real-time applicability, requiring efficient algorithms and approximations to achieve practical implementation. Adaptive control techniques aim to adapt the control inputs of redundantly actuated PKMs in real-time to account for uncertainties, variations in system parameters, and disturbances. These techniques utilize online parameter estimation algorithms to continuously update the control parameters based on feedback from the system's sensors. By adjusting the control strategy dynamically, adaptive control techniques can enhance the robustness and performance of redundantly actuated PKMs in the presence of changing operating conditions[16]. However, the effectiveness of adaptive control relies on the availability of accurate models and sufficient sensor feedback, as well as robust parameter estimation algorithms capable of handling nonlinearities and uncertainties.

Hybrid control strategies combine multiple control techniques, such as inverse dynamics control, optimization-based control, and adaptive control, to leverage their respective strengths and mitigate their weaknesses[17]. By integrating complementary control methods, hybrid strategies aim to achieve enhanced performance, robustness, and adaptability in controlling redundantly actuated PKMs. For example, a hybrid control approach may use inverse dynamics control for trajectory tracking while incorporating adaptive control to compensate for uncertainties and disturbances. Hybrid control strategies offer flexibility in tailoring the control strategy to specific application requirements and operating conditions, making them suitable for agile manufacturing environments where adaptability and performance are paramount. Real-time motion planning and trajectory optimization techniques enable redundantly actuated PKMs to generate optimal motion trajectories dynamically in response to changing task requirements and environmental conditions. These techniques utilize algorithms such as rapidly exploring random trees (RRTs) and model predictive control (MPC) to efficiently search the configuration space and generate collision-free trajectories that satisfy task constraints and optimization objectives. Real-time motion planning and trajectory optimization facilitate agile and adaptive behavior in redundantly actuated PKMs, enabling them to navigate complex workspaces, avoid obstacles, and optimize performance metrics such as speed, accuracy, and energy consumption. However, the computational complexity of these techniques may pose challenges for real-time implementation, necessitating efficient algorithms and hardware acceleration to achieve practical applicability in agile manufacturing systems[18].

## 6. Case Studies and Applications

One compelling application of redundantly actuated parallel kinematics mechanisms (PKMs) is in agile manufacturing cells designed for rapid reconfiguration and adaptability. These manufacturing cells typically feature a diverse range of tasks, from assembly to machining, and require robotic systems capable of efficiently handling various operations with minimal setup time. Redundantly actuated PKMs excel in such environments due to their flexibility, precision, and ability to dynamically adjust to changing production requirements. Case studies have demonstrated the use of redundantly actuated PKMs in agile manufacturing cells for tasks such as multi-axis machining, assembly of complex components, and flexible part positioning[19]. By integrating advanced control strategies and real-time motion planning, these manufacturing cells can achieve high levels of productivity, efficiency, and responsiveness, thereby enabling manufacturers to quickly respond to shifts in market demand and product specifications.

In the field of surgical robotics, redundantly actuated PKMs have emerged as promising platforms for enhancing the capabilities of minimally invasive surgical procedures. These robotic systems offer increased dexterity, precision, and stability, allowing surgeons to perform complex maneuvers with greater accuracy and control. Case studies have shown the application of redundantly actuated PKMs in surgical robotics for tasks such as robotic-assisted laparoscopic surgery, neurosurgery, and ophthalmic surgery. By leveraging advanced control strategies and haptic feedback interfaces, these systems enable surgeons to perform delicate procedures with improved safety and efficacy, ultimately leading to better patient outcomes[20]. Furthermore, the adaptability of redundantly actuated PKMs allows for the development of versatile surgical platforms capable of accommodating a wide range of procedures and surgical instruments, thereby enhancing the versatility and utility of robotic-assisted surgery in healthcare settings.

Aerospace manufacturing presents another compelling application domain for redundantly actuated PKMs, where precision, efficiency, and adaptability are critical for producing complex aircraft components and structures. Case studies have demonstrated the use of redundantly actuated PKMs in aerospace manufacturing for tasks such as drilling, riveting, and composite layup. These robotic systems offer advantages in terms of accessibility, reach, and accuracy, allowing manufacturers to achieve tighter tolerances and higher quality standards in aircraft production. By integrating advanced control strategies and sensor feedback systems, redundantly actuated PKMs can adapt to variations in part geometry and material properties, ensuring consistent and reliable manufacturing processes. Additionally, the flexibility of these robotic systems enables rapid reconfiguration for accommodating changes in production schedules and part designs, thereby enhancing the agility and responsiveness of aerospace manufacturing operations[21].

The automotive industry presents diverse opportunities for the application of redundantly actuated PKMs across various stages of vehicle production, including assembly, welding, and inspection. Case studies have showcased the use of these robotic systems in automotive manufacturing for tasks such as body-in-white assembly, powertrain assembly, and chassis welding. Redundantly actuated PKMs offer advantages in terms of flexibility, speed, and precision, enabling manufacturers to achieve higher throughput and quality in automotive production. By implementing advanced control strategies and vision-based sensing systems, these robotic systems can adapt to variations in part geometry and assembly tolerances, ensuring accurate and reliable assembly processes[22]. Furthermore, the versatility of redundantly actuated PKMs allows for seamless integration into existing manufacturing lines, enabling automotive manufacturers to optimize production workflows and respond efficiently to changes in market demand and product configurations.

## 7. Future Directions and Challenges

The future of redundantly actuated parallel kinematics mechanisms (PKMs) in agile manufacturing hinges on the integration of advanced artificial intelligence (AI) and machine learning techniques. AI algorithms can enhance the autonomy and adaptability of PKMs by enabling them to learn from experience, optimize performance, and make intelligent decisions in real-time. Machine learning algorithms, such as reinforcement learning and neural networks, can be leveraged to develop predictive models for dynamic modeling, control optimization, and predictive maintenance of PKMs. Furthermore, AI-powered vision systems can enable PKMs to perceive and interpret their environment, facilitating tasks such as object recognition, localization, and tracking[23]. By integrating AI and machine learning techniques into redundantly actuated PKMs, manufacturers can unlock new capabilities and efficiencies, paving the way for more intelligent and autonomous manufacturing systems.

As the role of robotics in agile manufacturing continues to expand, human-robot collaboration (HRC) is poised to become increasingly prevalent. HRC enables humans and robots to work together seamlessly, leveraging their respective strengths to achieve common goals. In the context of redundantly actuated PKMs, HRC holds the potential to enhance productivity, flexibility, and safety in manufacturing operations. By enabling direct interaction between humans and PKMs, collaborative systems can facilitate intuitive task programming, adaptive control, and dynamic task allocation[24]. Furthermore, advanced safety features and proximity sensors can ensure safe coexistence between humans and PKMs in shared workspaces. However, the successful implementation of HRC in agile manufacturing requires addressing technical, ergonomic, and regulatory challenges, such as ensuring robust collision detection, designing intuitive human-machine interfaces, and establishing clear guidelines for safe interaction between humans and robots.

The widespread adoption of redundantly actuated PKMs in agile manufacturing hinges on the development of standardized interfaces, protocols, and best practices. Standardization efforts can streamline the integration of PKMs into existing manufacturing systems, facilitate interoperability between different hardware and software platforms, and accelerate the deployment of advanced control strategies and optimization algorithms. Moreover, scalable design architectures and modular components can enable manufacturers to easily customize and reconfigure PKMs to meet evolving production requirements. However, achieving standardization and scalability in the context of redundantly actuated PKMs requires collaboration across industry stakeholders, including manufacturers, researchers, and regulatory bodies. By establishing common standards and guidelines, the industry can foster innovation, reduce barriers to entry, and accelerate the adoption of redundantly actuated PKMs in agile manufacturing.

Ensuring the safety of redundantly actuated PKMs in agile manufacturing environments remains a paramount concern. As these robotic systems operate in close proximity to human operators and interact with dynamic and unpredictable environments, robust safety measures and compliance with regulatory standards are essential. Safety considerations for redundantly actuated PKMs include risk assessment, hazard analysis, safety-rated control systems, and protective measures such as physical barriers and emergency stop mechanisms. Furthermore, compliance with international safety standards, such as ISO 10218 and ISO/TS 15066, is critical for demonstrating the safety and reliability of PKMs in industrial settings[25]. Addressing safety considerations and compliance requirements requires a multidisciplinary approach, involving collaboration between engineers, safety experts, and regulatory authorities to develop comprehensive safety strategies and ensure the safe deployment of redundantly actuated PKMs in agile manufacturing environments.

## 8. Conclusion

In conclusion, the dynamic modeling and control of redundantly actuated parallel kinematics mechanisms (PKMs) represent a crucial area of research with significant implications for the advancement of agile manufacturing systems. Through this paper, we have explored the principles, challenges, and advantages of redundantly actuated PKMs, highlighting their potential to enhance flexibility, precision, and adaptability in dynamic manufacturing environments. By investigating various dynamic modeling techniques and control strategies tailored to exploit redundancy, we have identified opportunities to optimize performance, improve efficiency, and enable rapid reconfiguration in agile manufacturing operations. Furthermore, through case studies and applications across diverse industries, we have illustrated the practical relevance and potential impact of redundantly actuated PKMs in addressing real-world manufacturing challenges. Looking ahead, the integration of advanced technologies such as AI, machine learning, and human-robot collaboration holds promise for further enhancing the capabilities of redundantly actuated PKMs and unlocking new opportunities for innovation in agile manufacturing. However, challenges remain in areas such as standardization, scalability, and safety, which must be addressed through collaborative efforts among industry stakeholders, researchers, and regulatory bodies. By addressing these challenges and leveraging the opportunities presented by redundantly actuated PKMs, we can accelerate the transition towards agile, adaptive, and resilient manufacturing systems capable of meeting the demands of an ever-changing global marketplace.

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