

Tendon-based Robotics

Area:	Analysis and synthesis of work spaces
Person in charge:	Tobias Bruckmann
Duration:	2005 – 2009

A tendon-based robot can be implemented with a certain amount of flexibility. For a certain task, different geometrical configurations may be used. Through this project, tools are developed with which the optimum configuration of a tendon-based robot for a specific requirement is derived.

