

Program of June 4

X'ian (UTC+8:00)	Paris (UTC+2:00)	New-York (UTC-4:00)	
14h30-15h00	8h30-9h00	2h30-3h00	Welcome of participants and Introduction words
15h00-17h20	9h00-11h20	3h00-5h20	Session 1: Keynotes (Chair: S. Briot) <u>4 talks</u> 25 minutes of presentation + 10 minutes of questions
15h00-15h35	9h00-9h35	3h00-3h35	<ul style="list-style-type: none"> • “Real-World Applications of the Fundamental and Practical Development of Cable-Driven Parallel Robots” by D. Lau
15h35-16h10	9h35-10h10	3h35-4h10	<ul style="list-style-type: none"> • “Tensegrity Mechanisms as candidates for the design of medical robots” by P. Renaud
16h10-16h45	10h10-10h45	4h12-4h45	<ul style="list-style-type: none"> • “Synthesis, Modelling and Optimization of Compliant Parallel Manipulators” by G. Hao
16h45-17h20	10h45-11h20	4h45-5h20	<ul style="list-style-type: none"> • “Soft Hands or: How I Learned to Stop Worrying and Love the Data” by C. Della Santina
17h20-17h40	11h20-11h40	5h20-5h40	(Virtual) coffee break and informal discussions
17h40-19h00	11h40-13h00	5h40-7h00	Session 2: Selected-paper session (Chair: D. Lau) <u>4 talks</u> 15 minutes of presentation + 5 minutes of questions
17h40-18h00	11h40-12h00	5h40-6h00	<ul style="list-style-type: none"> • “An opinion on the research on parallel robots” <u>J.-P. Merlet</u>
18h00-18h20	12h00-12h20	6h00-6h20	<ul style="list-style-type: none"> • “Cable-Driven Parallel Robots: Stiffness vs. Transparency” <u>M. Métillon, C. Charron, K. Subrin and S. Caro</u>
18h20-18h40	12h20-12h40	6h20-6h40	<ul style="list-style-type: none"> • “A Study on Flexible Parallel Robots via Additive Manufacturing” <u>D. Shah and A. Parmiggiani</u>
18h40-19h00	12h40-13h00	6h40-7h00	<ul style="list-style-type: none"> • “A Geometrically-Exact Assumed Strain Modes Approach for the Modelling of Continuum Parallel Robots” <u>S. Briot and F. Boyer</u>
19h00-20h30	13h00-14h30	7h00-8h30	Break
20h30-22h50	14h30-16h50	8h30-10h50	Session 3: Keynotes (Chair: M. Carricato) <u>4 talks</u> 25 minutes of presentation + 10 minutes of questions
20h30-21h05	14h30-15h05	8h30-9h05	<ul style="list-style-type: none"> • “Parallel Continuum Robot – Reconfigurable Designs” by J. Burgner-Kahrs
21h05-21h40	15h05-15h40	9h05-9h40	<ul style="list-style-type: none"> • “Autonomous Agile Cooperative Aerial Transportation” by G. Loianno
21h40-22h15	15h40-16h15	9h40-10h15	<ul style="list-style-type: none"> • “Modeling and Characterization of Parallel Continuum Robots” by C. Rucker
22h15-22h50	16h15-16h50	10h15-10h50	<ul style="list-style-type: none"> • “Taking Parallel Kinematics Robots to the Market” by J.-B. Izard

22h50-23h05	16h50-17h05	10h50-11h05	(Virtual) coffee break and informal discussions
23h05-0h00	17h05-18h00	11h05-12h00	<p>Session 4: My work in 5 minutes (Chair: J. Burgner-Kahrs) <u>10</u> talks 5 minutes per presentation</p> <ul style="list-style-type: none"> • “Challenges on Workspace Evaluation of Continuum Parallel Robots” <u>F. Zaccaria</u>, E. Idà, S. Briot, and M. Carricato • “Robot Hand based on a Spherical Parallel Mechanism for Within-Hand Rotations about a Fixed Point” V. V. Patel and A. M. Dollar • “Kinematic and Singularity Analysis of Tendon-Driven Parallel Continuum Robots” <u>K. Wen</u> and J. Burgner-Kahrs • “The Stewart Hand: A Highly Dexterous, 6-DoF Manipulator Based on the Stewart-Gough Platform” <u>C. M. McCann</u>, V. V. Patel, and A. M. Dollar • “Triskèle-Bot: Study and Development of a Parallel Continuum Robot for Micropositioning Applications” <u>B. Mauzé</u>, G. J. Laurent, R. Dahmouche, and C. Clévy • “Modeling and Design of an Underactuated Parallel Robot for Safe Physical Interaction” <u>G. Jeanneau</u>, V. Bégoc and S. Briot • “Computed Torque Control for a VSA type Hybrid Shoulder Joint” <u>S. Mghames</u>, M. G. Catalano, A. Bicchi and G. Grioli • “Design, Modeling and Evaluation of Tendon Driven Parallel Continuum Robots” <u>S. Lilqe</u> and J. Burgner-Kahrs • “Modeling and design of a new 5-DOF Delta-like robot for fast PnP operations” <u>V. Le Mesle</u>, V. Bégoc and S. Briot • “Dynamics of underactuated cable-driven parallel robots” <u>E. Idà</u>, and M. Carricato
0h00-0h15 (J+1)	18h00-18h15	12h00-12h15	(Virtual) coffee break and informal discussions
0h15-1h00 (J+1)	18h15-19h00	12h15-13h00	Session 5: Round table (Chair: J.-P. Merlet)
1h00 (J+1)	19h00	13h00	End of the workshop