

Abstract:

A method for moving a lifting device (1), wherein: in a presetting phase, at least one target position for the lifting device (1) is preset; in a measuring phase, the instantaneous geometry of the arm system is detected; in a selection phase, a selection of at least one target position specified in the presetting phase takes place; in a comparison phase, a geometrical deviation ($\Delta\alpha$, $\Delta\beta$, $\Delta\phi$, $\Delta\gamma$, ΔL , ΔJ , ΔH) between the geometry of the at least one target position selected in the selection phase and the instantaneous geometry detected in the measuring phase is determined; in a generation phase, at least one control command is generated on the basis of the geometrical deviation ($\Delta\alpha$, $\Delta\beta$, $\Delta\phi$, $\Delta\gamma$, ΔL , ΔJ , ΔH) determined in the comparison phase; and in a control phase, at least partial movement of the lifting device (1) into the selected target position is effected by actuating the actuators (20, 21, 22, 23, 25) of the arm system with the at least one control command generated in the generation phase.

(Fig. 7b)