DE 600 20 466 T2 furthermore discloses a "parallel robot" with four degrees of freedom which achieves the object of moving a mobile plate with four degrees of freedom at high speed and with a high acceleration and of positioning the mobile plate with a high rigidity and accuracy. Here, the term "parallel robot" is used to refer to a robot in which a multiplicity of actuators is arranged in parallel, it being possible to use a robot of this kind in a driving simulator for a motor vehicle, for example.

In this publication, parallel robots with six degrees of freedom are mentioned in connection with the prior art, these being used in flight simulators of the kind disclosed in US 5 333 514 and US 5 715 729, for example.

To achieve the object stated in DE 600 20 466 T2, a parallel robot is described which consists essentially of a special arrangement of a parallel linkage (3), a moving platform (4), coupling components (42) and kinematic elements (33). This publication does not deal with safety systems for the users of vehicle simulators.

It is therefore the underlying object of the apparatus according to the invention and of the corresponding method to propose an apparatus and a method where the primary concern is not only obtaining operational knowledge of vehicles but also the safety of the user of a vehicle simulator in the event of a technical fault or an accident.

The object is achieved by an apparatus as claimed in claim 1 and by a method as claimed in claim 6/7.

The apparatus according to the invention is described in greater detail below. More particularly: