

ABSTRACT

5 The invention relates to a high-speed parallel robot with four degrees
of freedom comprising four kinematic chains (1) articulated at one of their
ends to a mobile platform (4) carrying the tool (5) and at their other end,
through a rotational joint (2), to an actuator integral with a base plate (3).
The mobile platform (4) is formed by four members (11), (11'), (12), (12'),
linked together by means of articulated linkages (13), at least two of the
10 members being parallel to each other, forming an articulated mobile platform
with one degree of freedom in the plane of the mobile platform. The
actuators are positioned with any orientation in the base plate (2) and
preferably at 45°, 135°, 225° and 315°.