CLAIMS:

1. A tubular handling system comprising:

a pipe handler comprising:

a base;

a support rotatably attached to the base at one end of the support;

a first actuator configured to telescopically extend the support into engagement with a structure of a rig, wherein the engagement secures the support to the rig in a substantially vertical position, wherein the support is positioned vertically below a rig floor of the rig when the support is engaged with the structure; and

a pipe handler mechanism rotatably attached to the support proximate an opposite end of the support, the pipe handler mechanism being configured to grip and transport an object from a pick-up location to a delivery location, wherein the pipe handler mechanism comprises an arm rotationally coupled to the support, and wherein the arm comprises one or more grippers that are actuated to grip or release the object.

2. The system of claim 1, wherein the structure is a first structure, wherein the pipe handler is configured to engage the first structure and to access, via the pipe handler mechanism, a first horizontal storage area that is at a first vertical distance below the first structure, and wherein the pipe handler is configured to engage a second structure of a second rig and to adapt to access, via the pipe handler mechanism, a second horizontal storage area when the second structure is at a second vertical distance above the second horizontal storage area, with the first vertical distance being different than the second vertical distance.

3. The system of claim 1, wherein the pick-up location is one of a well center, the rig floor, a vertical storage area, another pipe handler, and horizontal storage area, and wherein the delivery location is another one of the well center, the rig floor, the vertical storage area, the other pipe handler, and the horizontal storage area.

4. The system of claim 1, wherein the pipe handler mechanism comprises first and second beams rotatably attached to the support proximate the opposite end of the support, and rotatably coupled to a first arm at an opposite end of the first and second beams, wherein the first and second beams are separated from each other by a horizontal space.

5. The system of claim 4, wherein the first arm is configured to rotate in a first direction through the horizontal space between the first and second beams when transporting the object between the pick-up location and the delivery location.

6. The system of claim 5, wherein the first beam is rotated relative to the second beam and the support, such that the first arm is rotated in a second direction which is substantially perpendicular to the first direction.

7. The system of claim 6, wherein grippers coupled to the first arm grip a tubular, and wherein rotation of the first arm in the second direction adjusts an alignment of the tubular to a well center.

8. The system of claim 4, wherein the first beam comprises a first upper beam and a first lower beam, wherein the first upper beam and the first lower beam are vertically aligned with each other and are separated by a first space therebetween, and wherein the support, the first upper beam, the first lower beam, and a coupling structure form a first parallelogram that is a four-bar linkage configuration.

9. The system of claim 8, wherein the second beam comprises a second upper beam and a second lower beam, wherein the second upper beam and the second lower beam are vertically aligned with each other and are separated by a second space therebetween, and wherein the support, the second upper beam, the second lower beam, and the coupling structure form a second parallelogram that is a four-bar linkage configuration.

10. The system of claim 1, wherein the support comprises: upper supports and lower supports, with the upper supports slidably coupled to the lower supports, wherein the first actuator slides the upper supports relative to the lower supports to telescopically extend or retract the upper supports relative to the lower supports.

11. A method for performing a subterranean operation, the method comprising:

rotating a support, via a first actuator, from a stowed position on a base to a substantially vertical position relative to the base;

vertically extending the support, via a second actuator, into engagement with a structure of a rig, wherein the engagement secures the support to the rig in the substantially vertical position;

rotating a pipe handler mechanism relative to the support from a stowed position to a deployed position, the pipe handler mechanism being rotationally coupled to the support and being configured to grip and transport an object from a pick-up location to a delivery location, wherein the pipe handler mechanism comprises an arm rotationally coupled to the support, and wherein the arm comprises one or more grippers that are actuated to grip or release the object; and

maintaining the engagement between the support and the structure via the second actuator while the pipe handler mechanism is operating.

12. The method of claim 11, further comprising:

gripping an object, via one or more grippers of the pipe handler mechanism, at the pick-up location;

transporting the object toward the delivery location by rotating a plurality of lift beams of the pipe handler mechanism and rotating at least one arm coupled the one or more grippers;

transporting the object through a space formed between the plurality of lift beams; and

delivering the object to the delivery location.

13. The method of claim 12, further comprising:

rotating the pipe handler mechanism to deployed positions from the pick-up location to the delivery location, while the support remains stationary in the substantially vertical position.

14. The method of claim 12, wherein the structure is a first rig and the object is a tubular with the method further comprising:

while transporting the tubular toward the delivery location, inserting an end of the tubular in a doping bucket; and

cleaning, drying, and applying a layer of dope to threads on the end of the tubular while the pipe handler mechanism is rotating the tubular relative to the doping bucket and the doping bucket remains stationary relative to a first rig floor of the first rig.

15. The method of claim 11, wherein the structure is a first rig, with the method further comprising:

rotating the pipe handler mechanism relative to the support from the deployed position to the stowed position;

vertically retracting the support, via the second actuator, from engagement with the first rig;

rotating the support from the vertical position to the stowed position on the base; transporting the base, the support, and the pipe handler mechanism in a stowed position from the first rig to a second rig via a conveyance; and

positioning the base proximate the second rig, where a second rig floor of the second rig is at a different height from a surface on which the base is resting when compared to a height of a first rig floor of the first rig from the surface on which the base was resting when positioned proximate the first rig.

16. The method of claim 15, further comprising:

rotating the support, via the first actuator, from the stowed position on the base to the vertical position relative to the base;

vertically extending the support, via the second actuator, into engagement with a structure of the second rig; and

rotating the pipe handler mechanism relative to the support from the stowed position to the deployed position.