connected to one of the jib parts and the other of which is connected to a jib part adjoining said jib part and which linear drives cooperate with each other via a guide on the jib.

Therefore, according to an aspect of the invention, a crane is disclosed, the crane comprising a base, an articulated jib which is supported by the base, as well as hoisting means which are guided from the base via the jib, such as a hoisting cable, which articulated jib comprises jib parts which are rotatably supported with respect to each other and with respect to the base, as well as respective jib part drives for varying the angular position of jib parts with respect to the base or with respect to another jib part, characterized in that one of the jib part drives comprises series-connected linear actuators, one of which is connected to one of the jib parts and the other of which is connected to a jib part adjoining said jib part and which linear drives cooperate with each other via a guide on the jib.

With the crane according to the invention, the jib parts can be rotated with respect to each other and be brought into the desired position and fixed by the linear actuators, preferably hydraulic piston/cylinder devices. However, in addition, one of the actuators of the two series-connected actuators can be used to displace the respective jib part around the position fixed by the other actuators. By means of this actuator, it is thus possible to generate adjusting movements of the jib, and thus of the hoisting cable. It is therefore not necessary to influence the winch for this purpose; the latter can be operated in the normal way for lifting or lowering the load. In particular, one of the actuators of the series-connected actuators can be operated as a heave compensator. This actuator which acts as a heave compensator is operated by the control system based on the detected heaving movements.

The guide may be configured in different ways, for example as a guide which is displaceable with respect to one of the jib parts in accordance with a predetermined path. This may involve linear or rectilinear movements, rotating movements or a combination thereof. Preference is given to a guide which comprises a tilting member which is rotatably suspended from at least one of the jib parts which are connected to the series-connected actuators.

In this case, various positions are conceivable. According to a first possibility, the tilting member may be suspended between and at a distance from both ends or both pivoting connections of one of the jib parts which are connected to the series-connected

actuators. In this variant, it is possible to ensure that the tilting member, the jib parts which are connected to the series-connected actuators and the actuator which is situated between the other jib part and tilting member, which actuator is set to a length which is equal to the distance between the pivoting connection of said one jib part and the tilting member on the one hand, and the pivoting connection between both jib parts on the other hand, cooperate according to pivoting connections which are situated on the four respective corners of a parallelogram. The actuator which is set to such a length that the parallelogram shape is obtained is then fixed, while the other actuator of the series-connected actuators acts as a heave compensator.