

How to use Huijue cable tray obstacle avoidance



Overview

Abstract—In this paper, a mechanical design of cable-driven hyper-redundant manipulator (CDHRM) is presented, and for which an obstacle-avoidance-based motion control method is proposed. First, cables are mounted to drive CDHRM, and the actuating subsystem is designed to be separated from the. The Cable Tray Institute (CTI) was founded in 1991 to support the cable tray industry by engaging in research, development, education, and the dissemination of information designed to promote, enhance, and increase the visibility of the industry. Copyright 2026© Cable Tray Institute | All rights. The following recommendations are intended to be a practical guide to ensure the safe and proper installation of cable ladder and cable tray systems and channel support and other support systems.

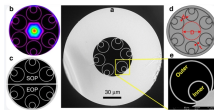
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Learn how to manage cables in cable trays effectively with our comprehensive guide for cable classification, protection, and installation to ensure electrical system safety and efficiency.



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Cable tray length is selected based on the load to be supported, the distance between the supports (also referred to as the span), and handling and installation constraints.



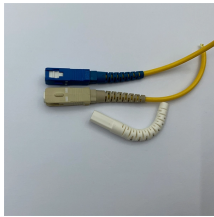
However, how to effectively avoid the surrounding obstacles for both its end effector and overall configuration has become a key problem. This paper proposes an embodied obstacle-avoidance ...



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Manipulators with a hyperredundant and large aspect ratio are becoming more commonly used to detect complex and narrow spaces. The hyperredundant feature confers advantages for ...



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To enhance the stiffness performance of the cable-driven humanoid manipulator during obstacle avoidance motion, we propose a high stiffness obstacle avoidance motion planning algorithm.



Once the cable is installed in an open cable tray installation, take care to protect the exposed cables from falling objects or debris that could cause damage to the cable. In areas where the cable tray ...



This paper presents a mechanical design of a cable-driven hyper-redundant manipulator (CDHRM), for which an obstacle-avoidance-based motion control method is proposed.

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