

## LIST OF TABLES

---

<b>Table 3.1.</b> Denavit-Hartenberg parameters of ABB IRB 6640.....	70
<b>Table 4.1.</b> Position and orientation of industry and proposed layout: units [m] & [degree]...	82
<b>Table 4.2.</b> Net joint angular displacement values of motors.....	83
<b>Table 4.3.</b> Computation time.....	85
<b>Table 5.1.</b> Initial feasible configuration of the multirobot and single robot workcell.....	97
<b>Table 5.2.</b> Optimal location and orientation of the multirobot workcell.....	98
<b>Table 5.3.</b> Area occupied by machines in the workcells.....	101
<b>Table 5.4.</b> Operation time and robot idle time at each machine.....	102
<b>Table 6.1.</b> DH & kinodynamic parameters of ABB IRB 6640 robot.....	115
<b>Table 6.2.</b> Optimal results.....	122
<b>Table 6.3.</b> Multi via-point optimal solutions.....	124