

# CableCon 2025

## Seventh International Conference on Cable-Driven Parallel Robots

July 8-11, 2025, Hong Kong

The first six conferences of this series successfully established a worldwide forum for research on cable-driven parallel robots. From Stuttgart, Duisburg, Quebec City, Krakow and Montpellier (online), Nantes, the next edition of the conference will be in Hong Kong on 8-11 July 2025. CableCon2025 aims at presenting new results, continuing the forum for the exchange of ideas, and establishing contacts amongst all international teams, for academics, researchers and industry.

### Important Dates

Paper submission: January 20, 2025

Notification of acceptance: March 1, 2025

Final paper: March 15, 2025

### Organization

The Chinese University of Hong Kong, Hong Kong

University of Duisburg-Essen, Germany

University of Stuttgart, Germany



### General Chair

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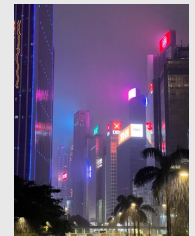
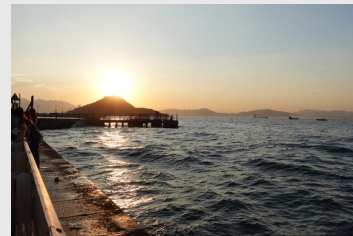
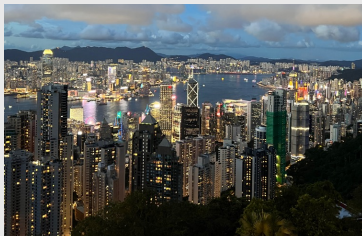
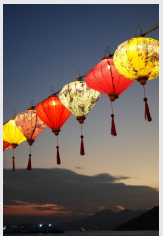
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### Location

Hong Kong is a special administrative region of the People's Republic of China. Originally a fishing village, it has grown into the metropolis it is today. The name 'Hong Kong' means 'fragrant harbour' in Chinese, and its unique blend of Eastern and Western influences has led to traditions and culture unlike anywhere else. This region, home to nearly 7.5 million people, is known for its iconic harbour skyline, though over 40 percent of its land is made up of country parks and nature reserves. The conference will be held at The Chinese University of Hong Kong, which is located on a 138.4 hectare campus built on a hillside, offering breathtaking views of the natural surroundings and the ocean in the New Territories region.



### Scientific Committee

Clément Gosselin, Université Laval  
Sunil K Agrawal, Columbia University  
Philippe Cardou, Université Laval  
Marc Gouttefarde, LIRMM, Univ. Montpellier, CNRS  
Marco Carricato, University of Bologna  
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Dieter Schramm, University of Duisburg-Essen  
Alexander Verl, University of Stuttgart

### Topics

Theory and application of cable-driven parallel robots including:

- Kinematics and Singularity Analysis
- Workspace Analysis and Synthesis
- Statics and Dynamics
- Cable Modeling and Technology
- Motion Planning and Control
- Calibration and Parameter Identification
- Multi-link Cable-driven Manipulators
- Design Methodology
- Hardware Development
- Experimental Evaluation
- Prototypes and Demonstrations
- Applications of Cable-Driven Robots in the Real World

### Electronic Submissions

Full papers of 12 pages to be submitted in pdf and LaTeX/MS Word format via the conference website.

### Instructions for Authors

Guidelines will be available on the webpage:  
<https://cablecon-2025.sciencesconf.org/>

### Presentation and Proceedings

The conference language is English. Proceedings will be published by Springer.