10. The composite crane of claim 9, wherein the distributed sensor is used to sense and predict at least one of (i) motion of a base platform to which the macro crane assembly is connected, (ii) relative motion and/or position between a base platform to which the macro crane assembly is connected and a target platform, (iii) relative motion and/or position between the macro crane assembly and the micro crane assembly, (iv) relative motion between a micro crane latch frame and a target cargo on a target platform, (v) a joint angle between a predetermined macro and micro crane component, (vi) a joint speed of a macro and micro crane component, or (vii) relative motion and/or position between the lifted cargo and the target platform.

11. A method of handling cargo, comprising:

a. positioning a composite crane into a predetermined position relative to cargo to be moved, the composite crane comprising:

i. a micro crane assembly, further comprising a support platform and a latch frame and adapted to control motion of the latch frame;

ii. a macro crane assembly adapted to be in communication with and control motion of the micro crane assembly; and

iii. a controller, operatively in communication with at least one of (a) the micro crane assembly or (b) the macro crane assembly;

b. connecting the micro crane assembly to the cargo; and

c. using a control algorithm accessible to the controller to maintain the support platform in a substantially steady state relative to inertial space.

12. The method of claim 11, wherein using a control algorithm further comprises at least one of (i) using a control algorithm accessible to the controller to move the latch frame so that its motion relative to the target platform (and cargo) is minimized or (ii) using a control algorithm accessible to the controller to move the latch frame and cargo once lifted so that its motion relative to the target platform and nearby cargo is minimized until lifted to a predetermined position.

13. The method of claim 11, wherein the controller is operatively in communication with a sensor useful to provide information to the controller.

14. The method of claim 11, further comprising powering the composite crane at least partially using enhanced motion control and energy storage.

15. A method of offloading an object from two ships at sea, comprising:

a. positioning a first ship proximate to a second ship at sea;

b. positioning a composite crane connected to a base platform on the first ship into a predetermined position relative to cargo to be moved with respect to the second ship, the composite crane comprising:

i. a micro crane assembly, comprising a controllable latch frame;

ii. a macro crane assembly adapted to be in communication with the micro crane assembly, the macro crane assembly connected to the base platform; and

iii. a controller, operatively in communication with at least one of (a) the micro crane assembly or (b) the macro crane assembly;

c. connecting the micro crane assembly to the cargo; and

d. using a control algorithm accessible to the controller to control the controllable latch frame in a predetermined number of degrees of freedom.

16. The method of claim 15, wherein using a control algorithm further comprises at least one of (i) using a control algorithm accessible to the controller to move the micro crane assembly so that its motion relative to the target platform (and cargo) is minimized or (ii) using a control algorithm accessible to the controller to move the micro crane assembly and cargo once lifted so that its motion relative to the target platform and nearby cargo is minimized until lifted to a predetermined position.

17. The method of claim 15, wherein the first ship and the second ship are at least one of (i) secured to each other, (ii) not secured to each other, (iii) at rest, or (iv) moving in a substantially parallel course.

18. The method of claim 15, further comprising using a kinematic control algorithm accessible to the controller to at least one of (i) maintain a suspension point of the micro crane assembly in a substantially steady state in inertial space despite motion of the base platform or (ii) moving to compensate for some of the movement of the target platform.

19. The method of claim 15, further comprising using a control algorithm accessible to the controller to move the latch frame so that motion of the latch frame relative to the target platform is maintained within a predetermined workspace.

20. The method of claim 15, further comprising using a control algorithm accessible to the controller to move the latch frame and cargo once lifted so that motion of the cargo relative to the target platform and nearby cargo is at least one of (i) minimized until lifted clear of the nearby cargo or (ii) such that the latching frame remains substantially centered in the workspace of the micro crane assembly.

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