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Preface xi 1 Introduction 1 1.1
Historical Development / 2 1.2 A
Sense of Mechanisms / 6 ...

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vast experience in the field as well as
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Robot Analysis: The Mechanics of Serial and Parallel ...

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Complete, state-of-the-art coverage of robot analysis This unique book provides the fundamental knowledge needed for understanding the mechanics of both serial and parallel manipulators. Presenting fresh and

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authoritative material on parallel manipulators that is not available in any other resource, it offers an in-depth treatment of position analysis, Jacobian analysis, statics and stiffness analysis, and dynamical analysis of both types of manipulators, including a discussion of industrial and research applications. It also features:

- * The homotopy continuation method and dialytic elimination method for solving polynomial systems that apply to robot kinematics
- * Numerous worked examples and problems to reinforce learning
- * An extensive bibliography offering many resources for more advanced study

Drawing on Dr. Lung-Wen Tsai's vast experience in the field as well as recent research publications, Robot Analysis is a first-rate text for upper-level undergraduate and graduate students

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Arm and Parallel Manipulators
in mechanical engineering, electrical engineering, and computer studies, as well as an excellent desktop reference for robotics researchers working in industry or in government.

Introduces the basic concepts of robot manipulation--the fundamental kinematic and dynamic analysis of manipulator arms, and the key techniques for trajectory control and compliant motion control. Material is supported with abundant examples adapted from successful industrial practice or advanced research topics. Includes carefully devised conceptual diagrams, discussion of current research topics with references to the latest publications, and end-of-book problem sets. Appendixes. Bibliography.

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And Parallel Manipulators
A modern and unified treatment of the mechanics, planning, and control of robots, suitable for a first course in robotics.

Complete, state-of-the-art coverage of robot analysis This unique book provides the fundamental knowledge needed for understanding the mechanics of both serial and parallel manipulators. Presenting fresh and authoritative material on parallel manipulators that is not available in any other resource, it offers an in-depth treatment of position analysis, Jacobian analysis, statics and stiffness analysis, and dynamical analysis of both types of manipulators, including a discussion of industrial and research applications. It also features: * The homotopy continuation method and dialytic elimination method for

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solving polynomial systems that apply to robot kinematics * Numerous worked examples and problems to reinforce learning * An extensive bibliography offering many resources for more advanced study Drawing on Dr. Lung-Wen Tsai's vast experience in the field as well as recent research publications, Robot Analysis is a first-rate text for upper-level undergraduate and graduate students in mechanical engineering, electrical engineering, and computer studies, as well as an excellent desktop reference for robotics researchers working in industry or in government.

Robot and Multibody Dynamics: Analysis and Algorithms provides a comprehensive and detailed exposition of a new mathematical approach, referred to as the Spatial

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Operator Algebra (SOA), for studying the dynamics of articulated multibody systems. The approach is useful in a wide range of applications including robotics, aerospace systems, articulated mechanisms, bio-mechanics and molecular dynamics simulation. The book also: treats algorithms for simulation, including an analysis of complexity of the algorithms, describes one universal, robust, and analytically sound approach to formulating the equations that govern the motion of complex multi-body systems, covers a range of more advanced topics including under-actuated systems, flexible systems, linearization, diagonalized dynamics and space manipulators. Robot and Multibody Dynamics: Analysis and Algorithms will be a valuable resource for researchers and engineers looking

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for new mathematical approaches to finding engineering solutions in robotics and dynamics.

Introduction to robot manipulators, with case studies of industrial robots.

In this comprehensive textbook about robot grasping, readers will discover an integrated look at the major concepts and technical results in robot grasp mechanics. A large body of prior research, including key theories, graphical techniques, and insights on robot hand designs, is organized into a systematic review, using common notation and a common analytical framework. With introductory and advanced chapters that support senior undergraduate and graduate level robotics courses, this book provides a full introduction

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to robot grasping principles that are needed to model and analyze multi-finger robot grasps, and serves as a valuable reference for robotics students, researchers, and practicing robot engineers. Each chapter contains many worked-out examples, exercises with full solutions, and figures that highlight new concepts and help the reader master the use of the theories and equations presented.

Advanced Theory of Constraint and Motion Analysis for Robot Mechanisms provides a complete analytical approach to the invention of new robot mechanisms and the analysis of existing designs based on a unified mathematical description of the kinematic and geometric constraints of mechanisms. Beginning with a high level introduction to

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mechanisms and components, the book moves on to present a new analytical theory of terminal constraints for use in the development of new spatial mechanisms and structures. It clearly describes the application of screw theory to kinematic problems and provides tools that students, engineers and researchers can use for investigation of critical factors such as workspace, dexterity and singularity. Combines constraint and free motion analysis and design, offering a new approach to robot mechanism innovation and improvement Clearly describes the use of screw theory in robot kinematic analysis, allowing for concise representation of motion and static forces when compared to conventional analysis methods Includes worked examples to translate

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theory into practice and demonstrate the application of new analytical methods to critical robotics problems

Foundations of Robotics presents the fundamental concepts and methodologies for the analysis, design, and control of robot manipulators. It explains the physical meaning of the concepts and equations used, and it provides, in an intuitively clear way, the necessary background in kinetics, linear algebra, and control theory. Illustrative examples appear throughout. The author begins by discussing typical robot manipulator mechanisms and their controllers. He then devotes three chapters to the analysis of robot manipulator mechanisms. He covers the kinematics of robot manipulators, describing the motion of manipulator

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links and objects related to manipulation. A chapter on dynamics includes the derivation of the dynamic equations of motion, their use for control and simulation and the identification of inertial parameters. The final chapter develops the concept of manipulability. The second half focuses on the control of robot manipulators. Various position-control algorithms that guide the manipulator's end effector along a desired trajectory are described Two typical methods used to control the contact force between the end effector and its environments are detailed For manipulators with redundant degrees of freedom, a technique to develop control algorithms for active utilization of the redundancy is described. Appendixes give compact reviews of the function atan2, pseudo

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inverses, singular-value decomposition, and Lyapunov stability theory. Tsuneo Yoshikawa teaches in the Division of Applied Systems Science in Kyoto University's Faculty of Engineering.

The revised text to the analysis, control, and applications of robotics The revised and updated third edition of Introduction to Robotics: Analysis, Control, Applications, offers a guide to the fundamentals of robotics, robot components and subsystems and applications. The author—a noted expert on the topic—covers the mechanics and kinematics of serial and parallel robots, both with the Denavit-Hartenberg approach as well as screw-based mechanics. In addition, the text contains information on microprocessor applications,

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control systems, vision systems, sensors, and actuators. Introduction to Robotics gives engineering students and practicing engineers the information needed to design a robot, to integrate a robot in appropriate applications, or to analyze a robot. The updated third edition contains many new subjects and the content has been streamlined throughout the text. The new edition includes two completely new chapters on screw-based mechanics and parallel robots. The book is filled with many new illustrative examples and includes homework problems designed to enhance learning. This important text: Offers a revised and updated guide to the fundamental of robotics Contains information on robot components, robot characteristics, robot languages, and robotic applications Covers the

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kinematics of serial robots with Denavit-Hartenberg methodology and screw-based mechanics Includes the fundamentals of control engineering, including analysis and design tools Discusses kinematics of parallel robots Written for students of engineering as well as practicing engineers, Introduction to Robotics, Third Edition reviews the basics of robotics, robot components and subsystems, applications, and has been revised to include the most recent developments in the field.

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