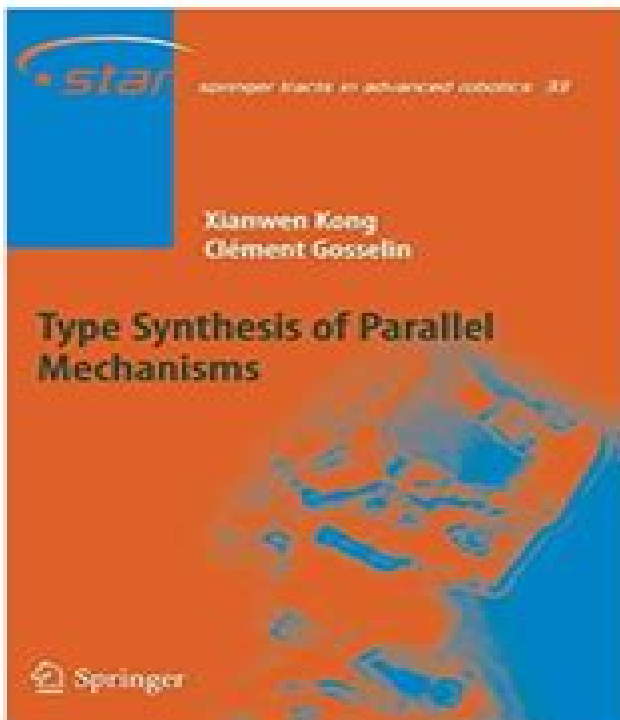




Type Synthesis Of Parallel Mechanisms Springer Tracts In Advanced Robotics

Christian Hatzfeld, Thorsten A. Kern



Type Synthesis Of Parallel Mechanisms Springer Tracts In Advanced Robotics:

Type Synthesis of Parallel Mechanisms Xianwen Kong, Clément M. Gosselin, 2007-10-28 This unique monograph focuses on the systematic type synthesis of parallel mechanisms PMs a key issue in the creative design of a wide variety of innovative devices such as parallel manipulators motion simulators and haptic devices Essential reading for researchers developers engineers and graduate students with interests in robotics this book covers the classification of PMs as well as providing a large number of PMs ready to be used in practical applications *Analysis and Synthesis of Compliant Parallel Mechanisms—Screw Theory Approach* Chen Qiu, Jian S. Dai, 2020-06-23 This book addresses the design of compliant mechanisms presenting readers with a good understanding of both the solid mechanics of flexible elements and their configuration design based on a mechanism equivalent approach in the framework of screw theory The book begins with the theoretical background of screw theory and systematically addresses both the compliance characteristics of flexible elements and their configuration design The book then covers a broad range of compliant parallel mechanism design topics from stiffness to constraint decomposition from conceptual design to dimensional design and from analysis to synthesis as well as the large deformation problem this is followed by both simulations and physical experiments offering readers a solid foundation and useful tools Given its scope and the results it presents the book will certainly benefit and inform future research on the topic It offers a valuable asset for researchers developers engineers and graduate students with an interest in compliant mechanisms robotics and screw theory *Topology Design of Robot Mechanisms* Ting-Li Yang, Anxin Liu, Huiping Shen, LuBin Hang, Yufeng Luo, Qiong Jin, 2018-01-02 This book focuses on the topology theory of mechanisms developed by the authors and provides a systematic method for the topology design of robot mechanisms The main original theoretical contributions of this book include A Three basic concepts The geometrical constraint type of axes is introduced as the third element of the topological structure of a mechanism When it is combined with the other two elements the kinematic pair and the connection of links the symbolic expression of the topological structure is independent of the motion positions except for the singularity positions and the fixed coordinate system Chapter 2 The position and orientation characteristic POC set is used to describe the POC of the relative motion between any two links The POC set derived from the unit vector set of the velocity of a link is only depend on the topological structure of a mechanism Therefore it is also independent of the motion positions and the fixed coordinate system Chapter 3 The single open chain SOC unit is the base unit of the topological structure used to develop the four basic equations of the mechanism topology Chapters 2 4 6 B The mechanism composition principle based on the SOC units This book proposes a mechanism composition principle based on the SOC units to establish a systematic theory for the unified modeling of the topology kinematics and dynamics of mechanisms based on the SOC units Chapter 7 C Four basic equations The POC equation of serial mechanisms with 10 symbolic operation rules Chapter 4 The POC equation of parallel mechanisms with 14 symbolic operation rules Chapter 5 The general DOF formula for spatial

mechanisms Chapter 6 The coupling degree formula for the Assur kinematic chain Chapter 7 D One systematic method for the topology design of robot mechanisms Chapters 8 10 Based on the three basic concepts and the four basic equations addressed above this book puts forward a systematic method for the topology design of parallel mechanisms which is fundamentally different from all existing methods Its main characteristics are as follows The design process includes two stages the first is structure synthesis which derives many structure types the second involves the performance analysis classification and optimization of structure types derived from the first stage The design operation is independent of the motion positions and the fixed coordinate system Therefore the proposed method is essentially a geometrical method which ensures the full cycle DOF and the generality of geometric conditions of mechanism existence Each individual design step follows an explicit formula or the guidelines for design criteria making the operation simple feasible and reproducible In addition the topology design of the SCARA PMs is studied in detail to demonstrate the proposed method Chapter 10

Advances in Robot Kinematics: Motion in Man and Machine Jadran Lenarčič, Michael M. Stanišić, 2010-07-20 The 1st International Meeting of Advances in Robot Kinematics ARK occurred in September 1988 by invitation to Ljubljana Slovenia of a group of 20 internationally recognized researchers representing six different countries from three continents There were 22 lectures and approximately 150 attendees This success of bringing together excellent research and the international community led to the formation of a Scientific Committee and the decision to repeat the event biannually The meeting was made open to all individuals with a critical peer review process of submitted papers The meetings have since been continuously supported by the Jozef Stefan Institute and since 1992 have come under patronage of the International Federation for the Promotion of Mechanism and Machine Science IFToMM Springer published the 1st book of the series in 1991 and since 1994 Kluwer and Springer have published a book of the presented papers every two years The papers in this book present the latest topics and methods in the kinematics control and design of robotic manipulators They consider the full range of robotic systems including serial parallel and cable driven manipulators both planar and spatial The systems range from being less than fully mobile to kinematically redundant to overconstrained The meeting included recent advances in emerging areas such as the design and control of humanoids and humanoid subsystems the analysis modeling and simulation of human body motion the mobility analysis of protein molecules and the development of systems which integrate man and machine

Mechanism Design for Robotics Marco Ceccarelli, Alessandro Gasparetto, 2019-06-21 MEDER 2018 the IFToMM International Symposium on Mechanism Design for Robotics was the fourth event in a series that was started in 2010 as a specific conference activity on mechanisms for robots The aim of the MEDER Symposium is to bring researchers industry professionals and students together from a broad range of disciplines dealing with mechanisms for robots in an intimate collegial and stimulating environment In the 2018 MEDER event we received significant attention regarding this initiative as can be seen by the fact that the Proceedings contain contributions by authors from all around the world The Proceedings of

the MEDER 2018 Symposium have been published within the Springer book series on MMS and the book contains 52 papers that have been selected after review for oral presentation These papers cover several aspects of the wide field of robotics dealing with mechanism aspects in theory design numerical evaluations and applications This Special Issue of Robotics https://www.mdpi.com/journal/robotics/special_issues MDR has been obtained as a result of a second review process and selection but all the papers that have been accepted for MEDER 2018 are of very good quality with interesting contents that are suitable for journal publication and the selection process has been difficult

Computational Kinematics Federico Thomas, Alba Perez Gracia, 2013-10-17 Computational kinematics is an enthralling area of science with a rich spectrum of problems at the junction of mechanics robotics computer science mathematics and computer graphics The covered topics include design and optimization of cable driven robots analysis of parallel manipulators motion planning numerical methods for mechanism calibration and optimization geometric approaches to mechanism analysis and design synthesis of mechanisms kinematical issues in biomechanics construction of novel mechanical devices as well as detection and treatment of singularities The results should be of interest for practicing and research engineers as well as Ph D students from the fields of mechanical and electrical engineering computer science and computer graphics

Advances in Robot Kinematics 2022 Oscar Altuzarra, Andr s Kecskem thy, 2022-06-17 This book reports on the latest scientific achievements on robot kinematics provided by the prominent researchers participating in the 18th International Symposium on Advances in Robot Kinematics ARK2022 organized in the University of the Basque Country Bilbao Spain It is of interest to researchers wanting to know more about the latest topics and methods in the fields of the kinematics control and design of robotic systems The book brings together 53 peer reviewed papers These cover the full range of robotic systems including serial parallel flexible mechanisms and cable driven manipulators and tackle problems such as kinematic analysis of robots robot modelling and simulation theories and methods in kinematics singularity analysis kinematic problems in parallel robots redundant robots cable robots kinematics in biological systems flexible parallel manipulators humanoid robots and humanoid subsystems

Advances in Mechanisms Design Jaroslav Beran, Martin B lek, Monika Hejnova, Petr Zabka, 2012-08-21 The International Conference on the Theory of Machines and Mechanisms is organized every four years under the auspices of the International Federation for the Promotion of Mechanism and Machine Science IFToMM and the Czech Society for Mechanics This eleventh edition of the conference took place at the Technical University of Liberec Czech Republic 4 6 September 2012 This volume offers an international selection of the most important new results and developments in 73 papers grouped in seven different parts representing a well balanced overview and spanning the general theory of machines and mechanisms through analysis and synthesis of planar and spatial mechanisms dynamics of machines and mechanisms linkages and cams computational mechanics rotor dynamics biomechanics mechatronics vibration and noise in machines optimization of mechanisms and machines control and monitoring systems of machines accuracy and reliability of machines

and mechanisms robots and manipulators to the mechanisms of textile machines

Microactuators and

Micromechanisms Erwin-Christian Lovasz,Gondi Kondaiah Ananthasuresh,Burkhard Corves,Victor Petuya,2015-04-02 This book contains applications of micromechanisms and microactuators in several very modern technical fields such as mechatronics biomechanics machines micromachines robotics and apparatuses In connection with its topic the work combines the theoretical results with experimental tests on micromechanisms and microactuators The book presents the most recent research advances in Machine and Mechanisms Science It includes the accepted reviewed papers of researchers specialized in the topics of the conference microactuators and micro assembly micro sensors involving movable solids micro opto mechanical devices mechanical tools for cell and tissue studies micromanipulation and micro stages micro scale flight and swimming micro robotics and surgical tools micron scale power generation miniature manufacturing machines micromechatronics and micro mechanisms biomechanics micro and nano scales and control issues in microsystems The presented applications of micromechanisms and microactuators in many technical fields will interest industrial companies and encourage scientific knowledge and cooperation between academia and industry

Smart Devices and Machines for Advanced Manufacturing Lihui Wang,Fengfeng Xi,2008-02-28 Manufacturing has been one of the key areas that support and influence a nation s economy since the 18th century Being the primary driving force in economic growth manufacturing constantly serves as the foundation of and contributes to other industries In the past centuries manufacturing has contributed to the modern civilisation and created momentum that is continuously driving today s economy Despite various revolutionary changes and innovations in the 20th century that contributed to manufacturing advancements we are facing new challenges when striving to achieve greater success in winning global competitions Machines and robots as the constituent components in manufacturing have contributed significantly to the success of advanced manufacturing After evolving from the initial mechanisation era where mechanical devices were created to replace human labours to the later automation era where control devices were invented to replace human operations the history of machines has now entered into the modern era of autonomisation where intelligent devices are being developed in an attempt to eventually replace human decision making While machines are becoming more and more intelligent through integration with new technologies including sensors controls computers and even the Internet machine structures and theories have also advanced most noticeably in the area of parallel kinematic machines and micro machines

Springer Handbook of Robotics Bruno Siciliano,Oussama Khatib,2016-07-27 The second edition of this handbook provides a state of the art overview on the various aspects in the rapidly developing field of robotics Reaching for the human frontier robotics is vigorously engaged in the growing challenges of new emerging domains Interacting exploring and working with humans the new generation of robots will increasingly touch people and their lives The credible prospect of practical robots among humans is the result of the scientific endeavour of a half a century of robotic developments that established robotics as a modern scientific discipline

The ongoing vibrant expansion and strong growth of the field during the last decade has fueled this second edition of the Springer Handbook of Robotics. The first edition of the handbook soon became a landmark in robotics publishing and won the American Association of Publishers PROSE Award for Excellence in Physical Sciences Mathematics as well as the organization's Award for Engineering Technology. The second edition of the handbook, edited by two internationally renowned scientists with the support of an outstanding team of seven part editors and more than 200 authors, continues to be an authoritative reference for robotics researchers, newcomers to the field, and scholars from related disciplines. The contents have been restructured to achieve four main objectives: the enlargement of foundational topics for robotics, the enlightenment of design of various types of robotic systems, the extension of the treatment on robots moving in the environment, and the enrichment of advanced robotics applications. Further to an extensive update, fifteen new chapters have been introduced on emerging topics, and a new generation of authors have joined the handbook's team. A novel addition to the second edition is a comprehensive collection of multimedia references to more than 700 videos which bring valuable insight into the contents. The videos can be viewed directly augmented into the text with a smartphone or tablet using a unique and specially designed app: Springer Handbook of Robotics Multimedia Extension Portal <http://handbookofrobotics.org>.

Multibody Mechatronic Systems João Carlos Mendes Carvalho, Daniel Martins, Roberto Simoni, Henrique Simas, 2017-09-29. These are the Proceedings of the 6th International Symposium on Multibody Systems and Mechatronics MUSME 2017 which was held in Florianópolis, Brazil, October 24-28, 2017. Topics addressed include analysis and synthesis of mechanisms, dynamics of multibody systems, design algorithms for mechatronic systems, simulation procedures and results, prototypes and their performance, robots and micromachines, experimental validations, theory of mechatronic simulation, mechatronic systems and control of mechatronic systems. The MUSME 2017 Symposium was one of the activities of the FEI/IBIM Commission for Mechatronics and IFToMM technical Committees for Multibody Dynamics, Robotics, and Mechatronics.

Engineering Haptic Devices Christian Hatzfeld, Thorsten A. Kern, 2014-09-15. In this greatly reworked second edition of Engineering Haptic Devices, the psychophysics content has been thoroughly revised and updated. Chapters on haptic interaction, system structures, and design methodology were rewritten from scratch to include further basic principles and recent findings. New chapters on the evaluation of haptic systems and the design of three exemplary haptic systems from science and industry have been added. This book was written for students and engineers that are faced with the development of a task-specific haptic system. It is a reference book for the basics of haptic interaction and existing haptic systems and methods, as well as an excellent source of information for technical questions arising in the design process of systems and components. Divided into two parts, Part I contains typical application areas of haptic systems and a thorough analysis of haptics as an interaction modality. The role of the user in the design of haptic systems is discussed, and relevant design and development stages are outlined. Part II presents all relevant problems in the design of haptic systems, including general system and control structures, kinematic

structures actuator principles and sensors for force and kinematic measures Further chapters examine interfaces and software development for virtual reality simulations

The 2005 DARPA Grand Challenge Martin Buehler, Karl Iagnemma, Sanjiv Singh, 2007-09-06 The DARPA Grand Challenge was a landmark in the field of robotics a race by autonomous vehicles through 132 miles of rough Nevada terrain It showcased exciting and unprecedented capabilities in robotic perception navigation and control The event took place in October 2005 and drew teams of competitors from academia and industry as well as many garage hobbyists This book presents fifteen technical papers that describe each team s driverless vehicle race strategy and insights As a whole they present the state of the art in autonomous vehicle technology and offer a glimpse of future technology for tomorrow s driverless cars

Robotics and Cognitive Approaches to Spatial Mapping Margaret E. Jefferies, Wai-Kiang Yeap, 2008-01-10 This important work is an attempt to synthesize two areas that need to be treated in tandem The book brings together the fields of robot spatial mapping and cognitive spatial mapping which share some common core problems One would expect some cross fertilization of research between the two areas to have occurred yet this has begun only recently There are now signs that some synthesis is happening so this work is a timely one for students and engineers in robotics

Maple in Mathematics Education and Research Robert M. Corless, Jürgen Gerhard, Ilias S. Kotsireas, 2021-07-19 This book constitutes refereed proceedings of the 4th Maple Conference MC 2020 held in Waterloo Ontario Canada in November 2020 The 25 revised full papers and 3 short papers were carefully reviewed and selected out of 75 submissions one invited paper is also presented in the volume The papers included in this book cover topics in education algorithms and applications of the mathematical software Maple

Experimental Robotics Oussama Khatib, Vijay Kumar, Daniela Rus, 2008-01-30 At the dawn of the new millennium robotics is undergoing a major transformation in scope and dimension From a largely dominant industrial focus robotics is rapidly expanding into the challenges of unstructured environments Interacting with assisting serving and exploring with humans the emerging robots will increasingly touch people and their lives The goal of the new series of Springer Tracts in Advanced Robotics STAR is to bring in a timely fashion the latest advances and developments in robotics on the basis of their significance and quality It is our hope that the wider dissemination of research developments will stimulate more exchanges and collaborations among the research community and contribute to further advancement of this rapidly growing field Since its inception wanted by my STAR Co Editor Oussama Khatib some twenty years ago the International Symposium on Experimental Robotics ISER was published by Springer Since the two past editions ISER has found a more suitable home under STAR together with other thematic symposia devoted to excellence in robotics research

Field and Service Robotics Christian Laugier, Roland Siegwart, 2008-06-19 FSR the International Conference on Field and Service Robotics is a robotics Symposium which has established over the past ten years the latest research and practical results towards the use of field and service robotics in the community with particular focus on proven technology The first meeting was held in Canberra Australia in 1997 Since

then the meeting has been held every two years in the pattern Asia America Europe This books presents the results of the sixth edition of Field and Service Robotics FSR03 held in Chamonix France on 9th 12th July 2003 The conference provided a forum for researchers professionals and robot manufacturers to exchange up to date technical knowledge and experience Field robots are non factory robots typically mobile that operate in complex and dynamic environments on the ground of Earth or planets under the ground underwater in the air or in space Service robots are those that work closely with humans to help them with their lives This book offers a collection of a broad range of topics including Underwater Robots and Systems Autonomous Navigation for Unmanned Aerial Vehicles Simultaneous Localization and Mapping Climbing Robotics Sensor Fusion *3D-Position Tracking and Control for All-Terrain Robots* Pierre Lamon,2008-02-12 Rough terrain robotics is a fast evolving field of research and a lot of effort is deployed towards enabling a greater level of autonomy for outdoor vehicles This book demonstrates how the accuracy of 3D position tracking can be improved by considering rover locomotion in rough terrain as a holistic problem Although the selection of appropriate sensors is crucial to accurately track the rover s position it is not the only aspect to consider Indeed the use of an unadapted locomotion concept severely affects the signal to noise ratio of the sensors which leads to poor motion estimates In this work a mechanical structure allowing smooth motion across obstacles with limited wheel slip is used In particular it enables the use of odometry and inertial sensors to improve the position estimation in rough terrain A method for computing 3D motion increments based on the wheel encoders and chassis state sensors is developed Because it accounts for the kinematics of the rover this method provides better results than the standard approach To further improve the accuracy of the position tracking and the rover s climbing performance a controller minimizing wheel slip is developed The algorithm runs online and can be adapted to any kind of passive wheeled rover Finally sensor fusion using 3D Odometry inertial sensors and visual motion estimation based on stereovision is presented The experimental results demonstrate how each sensor contributes to increase the accuracy and robustness of the 3D position estimation Algorithmic Foundation of Robotics VII Srinivas Akella,Nancy M. Amato,Wesley Huang,Bud Mishra,2008-07-10 Algorithms are a fundamental component of robotic systems they control or reason about motion and perception in the physical world They receive input from noisy sensors consider geometric and physical constraints and operate on the world through imprecise actuators The design and analysis of robot algorithms therefore raises a unique combination of questions in control theory computational and differential geometry and computer science This book contains the proceedings from the 2006 Workshop on the Algorithmic Foundations of Robotics This biannual workshop is a highly selective meeting of leading researchers in the field of algorithmic issues related to robotics The 32 papers in this book span a wide variety of topics from fundamental motion planning algorithms to applications in medicine and biology but they have in common a foundation in the algorithmic problems of robotic systems

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