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Clément Gosselin

Type Synthesis of Parallel Mechanisms

Type Synthesis Of Parallel Mechanisms Springer Tracts In Advanced Robotics

Federico Thomas, Alba Perez Gracia



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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 first 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 first 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, Andrés Kecskeméthy, 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 Bílek, 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

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