

3976

Contents

Series Preface	v
Preface	vii
1 Introduction	1
1.1 Background	1
1.2 Elements of a Robotic System	3
1.3 Degrees-of-Freedom of a System	6
1.4 Regional and Orientational Structures	9
1.5 Coordinate Systems	12
1.6 Displacements	20
1.7 Problems	39
2 Kinematic Analysis	45
2.1 Background	45
2.2 Governing Equations	46
2.3 Stanford Arm Manipulator	52
2.4 Manipulator Case 2	58
2.5 Manipulator Case 3	62
2.6 PUMA by ZRP Method	64
2.7 PUMA by Pieper-Roth Method	68
2.8 Cincinnati Milacron T ³	72
2.9 Geared Wrists	76
2.10 Velocity Relations	80
2.11 Acceleration Relations	93
2.12 Iterative Position Analysis	93
2.13 Problems	102

3	Robot Workspace	109
3.1	Background	109
3.2	Workspace Classification	109
3.3	Nature of Workspace	113
3.4	Determination of Primary Workspace	116
3.5	Determination of Workspace	121
3.6	Free Spin of the Hand	123
3.7	Problems	127
4	Dynamics and Control	129
4.1	Background	129
4.2	Kinematics	129
4.3	Kinetics	130
4.4	Recursion Relations	139
4.5	Lagrangian Formulation	145
4.6	Control	147
4.7	Problems	157
	References	161
	Index	173