

# Structural Synthesis Of Parallel Robots

[DOWNLOAD HERE](#)

Preface; Acknowledgements; List of abbreviations and notations; 1 Introduction; 1.1 Terminology; 1.2 Methodology of structural synthesis; 1.2.1 New formulae for mobility, connectivity, redundancy and overconstraint of parallel robots; 1.2.2 Evolutionary morphology approach; 1.2.3 Types of parallel robots with respect to motion coupling; 1.3 Translational parallel robots; 2 Translational parallel robots with two degrees of freedom; 2.1 T2-type translational parallel robots with coupled motions; 2.1.1 Overconstrained solutions; 2.1.2 Non overconstrained solutions; 2.2 T2-type translational parallel robots with decoupled motions; 2.2.1 Overconstrained solutions; 2.2.2 Non overconstrained solutions; 2.3 T2-type translational parallel robots with uncoupled motions; 2.3.1 Overconstrained solutions; 2.3.2 Non overconstrained solutions; 2.4 Maximally regular T2-type translational parallel robots; 2.4.1 Overconstrained solutions; 2.4.2 Non overconstrained solutions; 2.5 Other T2-type translational parallel robots; 2.5.1 Overconstrained solution; 2.5.2 Non overconstrained solutions; 3 Overconstrained T3-type TPMs with coupled motions; 3.1 Basic solutions with linear actuators; 3.2 Derived solutions with linear actuators; 3.3 Basic solutions with rotating actuators; 3.4 Derived solutions with rotating actuators; 4 Non overconstrained T3-type TPMs with coupled motions; 4.1 Basic solutions with linear actuators; 4.2 Derived solutions with linear actuators; 4.3 Basic solutions with rotating actuators; 4.4 Derived solutions with rotating actuators; 5 Overconstrained T3-type TPMs with uncoupled motions; 5.1 Basic solutions with rotating actuators; 5.2 Derived solutions with rotating actuators; 6 Non overconstrained T3-type TPMs with uncoupled motions; 6.1 Basic solutions with rotating actuators; 6.2 Derived solutions with rotating actuators; 7 Maximally regular T3-type translational parallel robots; 7.1 Overconstrained solutions; 7.1.1 Basic solutions with no idle mobilities; 7.1.2 Derived solutions with idle mobilities; 7.2 Non overconstrained solutions; References; Index EAN/ISBN : 9781402097942 Publisher(s): Springer Netherlands Discussed keywords: Roboter Format: ePub/PDF Author(s): Gogu, Grigore - Gladwell, Graham M. L.

[DOWNLOAD HERE](#)

## Similar manuals:

[Structural Synthesis Of Parallel Robots](#)

[Simulation Verschiedener Steuerstrategien FÃ¼r Einen Autonomen Industrieroboter FÃ¼r Das UmwÃ¤lzen Von Eingelagertem Getreide - Thomas Nickel](#)

[Sammlung Von Versuchsprotokollen FÃ¼r Die Bereiche Gasbrennschneiden, Montageroboter, FÃ¼gen-Stabelektrode, Pneumatisches Handling, Schraubverfahren - Nadja Lachmund](#)

[AUDIO SOUND: Industrial Roboter Smally](#)

[Sicherheit In Der Mensch-Roboter-Kooperation - , Ralf Giessler](#)