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Robot Modeling and Control introduces the fundamentals of robot modeling and control and provides background material on terminology, linear algebra, dynamical systems and stability theory, followed by detailed coverage of forward and in-verse kinematics, Jacobians, Lagrangian dynamics, motion planning, robust and adaptive motion and force control, and computer vision. Both basic and advanced material is presented in a style that is readable and mathematically rigorous. The book provides relevant applications from industrial robotics and mobile robotics. Suitable for a one or two term course, this text is appropriate for undergraduate and graduate students from electrical engineering, mechanical engineering, computer science, and mathematics and can be used as a research reference. Many detailed worked examples and extensive problems illustrate theory and point the reader to more advanced topics.