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A robot manipulator is a movable chain of links interconnected by joints. One end is fixed to the ground, and a hand or end effector that can move freely in space is attached at the other end. This book begins with an introduction to the subject of robot manipulators. Next, it describes in detail a forward and reverse analysis for serial robot arms. Most of the text focuses on closed form solution techniques applied to a broad range of manipulator geometries, from typical industrial robot designs (relatively simple geometries) to the most complicated case of seven general links serially connected by six revolute joints. A unique feature is its detailed analysis of 6R-P and 7R mechanisms. Case studies show how the techniques described in the book are used in real engineering applications. The book will be useful to both graduate students and engineers working in the field of robotics.