Computational Kinematics

Jadran Lenarčič,Manfred Husty

Computational Kinematics:

Computational Kinematics J. Angeles,Günter Hommel,Peter Kovács,2013-06-29 The aim of this book is to provide an account of the state of the art in Com putational Kinematics We understand here under this term that branch of kinematics research involving intensive computations not only of the numer ical type but also of a symbolic nature Research in kinematics over the last decade has been remarkably ori ented towards the computational aspects of kinematics problems In fact this work has been prompted by the need to answer fundamental question s such as the number of solutions whether real or complex that a given problem can admit Problems of this kind occur frequently in the analysis and synthesis of kinematic chains when finite displacements are considered The associated models that are derived from kinematic relations known as closure equations lead to systems of nonlinear algebraic equations in the variables or parameters sought What we mean by algebraic equations here is equations whereby the unknowns are numbers as opposed to differen tial equations where the unknowns are functions The algebraic equations at hand can take on the form of multivariate polynomials or may involve trigonometric functions of unknown angles Because of the nonlinear nature of the underlying kinematic models purely numerical methods turn out to be too restrictive for they involve iterative procedures whose convergence cannot in general be guaranteed Additionally when these methods converge they do so to only isolated solu tions and the question as to the number of solutions to expect still remains *Computational Kinematics* Andrés Kecskeméthy,Andreas Müller,2009-10-06 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 present book collects up to date methods as presented during the Fifth International Workshop on Computational Kinematics CK2009 held at the University of Duisburg Essen Germany 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 balancing and construction of novel mechanical devices detection and treatment of singularities as well as computational methods for gear design 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 **Computational Kinematics '95** J.-P. Merlet,Bahram Ravani,2012-12-06 The aim of this book is to provide an account of the state of the art in Com putational Kinematics We understand here under this term that branch of kinematics research involving intensive computations not only of the nu merical type but also of symbolic as well as geometric nature Research in kinematics over the last decade has been remarkably ori ented towards the computational aspects of kinematics problems In fact this work has been prompted by the need to answer fundamental questions such as the number of solutions whether real or complex that a given problem can admit as well as computational algorithms to support geo metric analysis Problems of the first kind occur frequently in the

analysis and synthesis of kinematic chains when fine displacements are considered The associated models that are derived from kinematic relations known as closure equations lead to systems of nonlinear algebraic equations in the variables or parameters sought The algebraic equations at hand can take the form of multivariate polynomials or may involve trigonometric functions of unknown angles **Computational Kinematics** Andrés Kecskeméthy,Andreas Müller,2009-05-20 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 present book collects up to date methods as presented during the Fifth International Workshop on Computational Kinematics CK2009 held at the University of Duisburg Essen Germany 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 balancing and construction of novel mechanical devices detection and treatment of singularities as well as computational methods for gear design 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 *Computational Kinematics* Saïd Zeghloul,Lotfi Romdhane,Med Amine Laribi,2017-07-03 This is the proceedings of IFToMM CK 2017 the 7th International Workshop on Computational Kinematics that was held in Futuroscope Poitiers France in May 2017 Topics treated include kinematic design and synthesis computational geometry in kinematics motion analysis and synthesis theory of mechanisms mechanism design kinematical analysis of serial and parallel robots kinematical issues in biomechanics molecular kinematics kinematical motion analysis and simulation geometric constraint solvers deployable and tensegrity structures robot motion planning applications of computational kinematics education in computational kinematics and theoretical foundations of kinematics Kinematics is an exciting area of computational mechanics and plays a central role in a great variety of fields and industrial applications nowadays Apart from research in pure kinematics the field deals with problems of practical relevance that need to be solved in an interdisciplinary manner in order for new technologies to develop The results presented in this book 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 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   Computational Kinematics '95 J.-P. Merlet,Bahram Ravani,1995 The trends and progress attained in computational kinematics over a broad class of problems are grouped into six parts describing the main themes kinematics algorithms discussing kinematics problems in light of their solution algorithms kinematics of mechanisms studying problems related to specific mechanisms singularities workspace discussing the determination of the workspace of given mechanisms parallel manipulators and motion and grasp planning touching on computational geometry The volume contains a representative sample of the most modern techniques available for kinetics problems including techniques based on advances in algebraic geometry Researchers graduate students and practising engineers in work relating to kinematics robotics machine design and computer science should find this work useful

Computational Kinematics Sandipan Bandyopadhyay,Gökhan Kiper,2026-05-02 This book includes the proceedings of the 8th International Workshop on Computational Kinematics CK2025 held in Chennai India during November 25 26 2025 Computational Kinematics is the science of analysis and synthesis of motions in mechanisms and robots covering both the theoretical as well as computational aspects of these The 23 research papers presented here cover a range of the topics from computational geometry and theoretical kinematics analysis and synthesis of mechanisms to motion planning and control of robots to kinematic aspects of biomechanics These research contributions have been received from 11 different countries and were selected via a rigorous process of peer review by globally renowned experts in the field This book can be of interest to researchers in the field as well as students and engineers working on design and analysis of mechanisms and robots biomechanics and many other applications of computational kinematics   *Computational Kinematics* Princeton University. Department of Computer Science,L. Joskowicz,E. Sacks,1990 We describe an efficient kinematic analysis program for feasible mechanisms The input is the shapes and the initial positions of the parts The output is a concise symbolic description of the mechanism s configuration space which characterizes its kinematic behavior The program computes the configuration space by identifying potential degrees of freedom constructing configuration spaces for all pairs of interacting parts and incrementally composing the pairwise configuration spaces   **Computational Kinematics** Frank C. Park,Cornel C. Iurascu,2001   *Computational Kinematics in the Analysis, Synthesis and Design of Mechanisms* F. Freudenstein,COLUMBIA UNIV NEW YORK.,1975 The report describes the results of research in the areas of mechanisms and mechanical systems as follows 1 Principles of logical functional design of mechanisms and mechanical systems 2 Development of efficient computer aided design techniques for unit mechanisms a tone arm articulation for minimum tracking error in automatic turntables b transmission angle optimization of a skew four bar linkage c rotatability criteria for the cranks of a geard five bar mechanism Development of general methods of computer aided kinematic desing a synthesis of numerically specified cam follower systems b development of heuristic combinatorial design methods for mechanisms and mechanical systems of small to moderate size   **Advances in Robot Kinematics 2024** Jadran Lenarčič,Manfred

Husty,2024-07-02 This book is aimed at researchers specializing in the kinematics of robot mechanisms as well as at doctoral students in guiding their research work A spectrum of the latest achievements in kinematics analysis modelling simulation design and control is covered New theories and methods are applied to serial parallel and cable driven mechanisms for use in industrial or service robotics The systems range from being less than fully mobile to kinematically redundant and over constrained Forty nine papers are included arranged in seven chapters as presented at the 19th Symposium on Advances in Robot Kinematics 2024 The symposium which has been held since 1988 was organized this time in Ljubljana Slovenia where it began thirty six years ago The papers have been rigorously selected based on peer review and are arranged in chapters randomly as is the prevailing tradition of these symposia In doing so we aim to give equal emphasis to each of these achievements   Technology Developments: the Role of Mechanism and Machine Science and IFToMM Marco Ceccarelli,2011-05-26 This is the first book of a series that will focus on MMS Mechanism and Machine Science This book also presents IFToMM the International Federation on the Promotion of MMS and its activity This volume contains contributions by IFToMM officers who are Chairs of member organizations MOs permanent commissions PCs and technical committees TCs who have reported their experiences and views toward the future of IFToMM and MMS The book is composed of three parts the first with general considerations by high standing IFToMM persons the second chapter with views by the chairs of PCs and TCs as dealing with specific subject areas and the third one with reports by the chairs of MOs as presenting experiences and challenges in national and territory communities This book will be of interest to a wide public who wish to know the status and trends in MMS both at international level through IFToMM and in national local frames through the leading actors of activities In addition the book can be considered also a fruitful source to find out who s who in MMS historical backgrounds and trends in MMS developments as well as for challenges and problems in future activity by IFToMM community and in MMS at large   **Special Issue on CK 2005, International Workshop on Computational Kinematics** ,2006   Advances in Robot Kinematics 2018 Jadran Lenarcic,Vincenzo Parenti-Castelli,2018-06-22 This is the proceedings of ARK 2018 the 16th International Symposium on Advances in Robot Kinematics that was organized by the Group of Robotics Automation and Biomechanics GRAB from the University of Bologna Italy ARK are international symposia of the highest level organized every two years since 1988 ARK provides a forum for researchers working in robot kinematics and stimulates new directions of research by forging links between robot kinematics and other areas The main topics of the symposium of 2018 were kinematic analysis of robots robot modeling and simulation kinematic design of robots kinematics in robot control theories and methods in kinematics singularity analysis kinematic problems in parallel robots redundant robots cable robots over constrained linkages kinematics in biological systems humanoid robots and humanoid subsystems   **Computer Aided Kinematics and Dynamics of Mechanical Systems: Basic methods** Edward J. Haug,1989   **Computational Kinematics of General Stewart Platform** Zongliang Mu,2005   Advances in Robot Kinematics and

Computational Geometry Jadran Lenarčič,Bahram Ravani,2013-06-29 Recently research in robot kinematics has attracted researchers with different theoretical profiles and backgrounds such as mechanical and electrica engineering computer science and mathematics It includes topics and problems that are typical for this area and cannot easily be met elsewhere As a result a specialised scientific community has developed concentrating its interest in a broad class of problems in this area and representing a conglomeration of disciplines including mechanics theory of systems algebra and others Usually kinematics is referred to as the branch of mechanics which treats motion of a body without regard to the forces and moments that cause it In robotics kinematics studies the motion of robots for programming control and design purposes It deals with the spatial positions orientations velocities and accelerations of the robotic mechanisms and objects to be manipulated in a robot workspace The objective is to find the most effective mathematical forms for mapping between various types of coordinate systems methods to minimise the numerical complexity of algorithms for real time control schemes and to discover and visualise analytical tools for understanding and evaluation of motion properties ofvarious mechanisms used in a robotic system **Computational Dynamics** Ahmed A. Shabana,2009-11-06 Computational Dynamics 3rd edition thoroughly revised and updated provides logical coverage of both theory and numerical computation techniques for practical applications The author introduces students to this advanced topic covering the concepts definitions and techniques used in multi body system dynamics including essential coverage of kinematics and dynamics of motion in three dimensions He uses analytical tools including Lagrangian and Hamiltonian methods as well as Newton Euler Equations An educational version of multibody computer code is now included in this new edition www wiley com go shabana that can be used for instruction and demonstration of the theories and formulations presented in the book and a new chapter is included to explain the use of this code in solving practical engineering problems Most books treat the subject of dynamics from an analytical point of view focusing on the techniques for analyzing the problems presented This book is exceptional in that it covers the practical computational methods used to solve real world problems This makes it of particular interest not only for senior graduate courses in mechanical and aerospace engineering but also to professional engineers Modern and focused treatment of the mathematical techniques physical theories and application of rigid body mechanics that emphasizes the fundamentals of the subject stresses the importance of computational methods and offers a wide variety of examples Each chapter features simple examples that show the main ideas and procedures as well as straightforward problem sets that facilitate learning and help readers build problem solving skills Special Issue on CK 2005, International Workshop on Computational Kinematics ,2006

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