

Advanced Theory of Constraint and Motion Analysis for Robot Mechanisms, 2013, 496 pages, Jingshan Zhao, Zhijing Feng, Fulei Chu, Ning Ma, 0124202233, 9780124202238, Academic Press, 2013

Advanced Theory of Constraint and Motion Analysis for Robot Mechanisms provides a complete analytical approach to the invention of new robot mechanisms and the analysis of existing designs based on a unified mathematical description of the kinematic and geometric constraints of mechanisms. Beginning with a high level introduction to mechanisms and components, the book moves on to present a new analytical theory of terminal constraints for use in the development of new spatial mechanisms and structures. It clearly describes the application of screw theory to kinematic problems and provides tools that students, engineers and researchers can use for investigation of critical factors such as workspace, dexterity and singularity. Combines constraint and free motion analysis and design, offering a new approach to robot mechanism innovation and improvement. Clearly describes the use of screw theory in robot kinematic analysis, allowing for concise representation of motion and static forces when compared to conventional analysis methods. Includes worked examples to translate theory into practice and demonstrate the application of new analytical methods to critical robotics problems.

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