

Chapter 21 Rigid Body Dynamics: Rotation and Translation about a Fixed Axis

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Chapter 21 Rigid Body Dynamics Rotation And Translation

Jack Phillips



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Dynamic Analysis of Robot Manipulators Constantinos A. Balafoutis,Rajnikant V. Patel,2012-12-06 The purpose of this monograph is to present computationally efficient algorithms for solving basic problems in robot manipulator dynamics In particular the following problems of rigid link open chain manipulator dynamics are considered i computation of inverse dynamics ii computation of forward dynamics and iii generation of linearized dynamic models Computationally efficient solutions of these problems are prerequisites for real time robot applications and simulations Cartesian tensor analysis is the mathematical foundation on which the above mentioned computational algorithms are based In particular it is shown in this monograph that by exploiting the relationships between second order Cartesian tensors and their vector invariants a number of new tensor vector identities can be obtained These identities enrich the theory of Cartesian tensors and allow us to manipulate complex Cartesian tensor equations effectively Moreover based on these identities the classical vector description for the Newton Euler equations of rigid body motion are rewritten in an equivalent tensor formulation which is shown to have computational advantages over the classical vector formulation Thus based on Cartesian tensor analysis a conceptually simple easy to implement and computationally efficient tensor methodology is presented in this monograph for studying classical rigid body dynamics XII Application of this tensor methodology to the dynamic analysis of rigid link open chain robot manipulators is simple and leads to an efficient formulation of the dynamic equations of motion

Applied Mechanics Reviews ,1970

Video Data Compression for Multimedia Computing Hua Harry Li,Shan Sun,Haluk Derin,2012-12-06 During the past few

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Engineering Mechanics, Dynamics Joseph F. Shelley, 1980 **Engineering Mechanics** Bela I. Sandor, Karen J. Richter, 1987 *Freedom in Machinery: Volume 2, Screw Theory Exemplified* Jack Phillips, 1984 Does a machine run well by virtue of its accuracies or its freedoms This work presents an exciting diagrammatic display of the hidden geometry of freedom and constraint It bolsters the imaginative design of robots but applies across all fields of machinery The figures and their captions comprise alone a self standing story and this connects effectively with the rigorously argued text The seamless combination of the two volumes 1984 1990 renders the internal cross referencing forward and backward within the volumes easier to look up The appearance of this paperback is a clear testament to the work's ongoing readership The term screw theory occurs throughout This relates after Ball to the book's philosophy and one might equally mention kinetostatics after Federhofer An all pervading counter intuitive fact accordingly presents itself while analogously angular velocity relates to force linear velocity relates to couple A direct consequence of Freedom in Machinery is a more recent book by the same author Specifically titled General Spatial Involute Gearing and published in Germany 2003 it exemplifies the many ways in which Freedom in Machinery clarifies the enigmatic field of spatial mechanism That field continuously expands with the current continuous thrust of ordinary engineering practice

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