

# DIRECT-DRIVE ROBOTS

THEORY AND PRACTICE

HARUHIKO ASADA AND KAMAL YUCEF-TOUMI

THE MIT PRESS CLASSICS

# Direct Drive Robots Theory And Practice

**American Society of Mechanical  
Engineers. Winter Annual Meeting**



## **Direct Drive Robots Theory And Practice:**

**Direct-drive Robots** Haruhiko Asada, Kamal Youcef-Toumi, 1987-01 This book describes the design concept and discusses the control issues related to the performance of a direct drive robot specifically a direct drive mechanical arm capable of carrying up to 10 kilograms at 10 meters per second accelerating at 5 G a unit of acceleration equal to the acceleration of gravity These are remarkable achievements compared to current industrial robots that move with speeds on the order of 1 meter per second Direct Drive Robot presents the most current research in manipulator design and control emphasizing the high performance direct drive robot arm in which the shafts of articulated joints are directly coupled to the rotors of motors with high torque It describes fundamental technologies of key components such as motors amplifiers and sensors arm linkage design and control system design and makes significant contributions in the areas of power efficiency analysis dynamic mass balancing and decoupling theory The book provides a good balance between theory and practice covering the practical design and implementation of this special robot as well as the theoretical design tools Contents Part I Direct Drive Technologies Introduction Components Part II Arm Design Theory Power Efficiency Arm Design for Simplified Dynamics Actuator Relocation Design of Decoupled Arm Structures Part III Development of the MIT Arm Mechanisms Control Systems Part IV Selected Papers on Direct Drive Robot Design and Control Haruhiko Asada is an Associate Professor Kyoto University and Lecturer at MIT He has built two prototypes of the direct drive arm described here Kamal Youcef Toumi is an Assistant Professor Department of Mechanical Engineering System Dynamics and Controls Division at MIT He has worked for three years with Asada on the development of the MIT high speed directdrive robot

**DIRECT DRIVE ROBOTS** Haruhiko Asada, *Robotics and Automation Handbook* Thomas R. Kurfess, 2018-10-03 As the capability and utility of robots has increased dramatically with new technology robotic systems can perform tasks that are physically dangerous for humans repetitive in nature or require increased accuracy precision and sterile conditions to radically minimize human error The Robotics and Automation Handbook addresses the major aspects of designing fabricating and enabling robotic systems and their various applications It presents kinetic and dynamic methods for analyzing robotic systems considering factors such as force and torque From these analyses the book develops several controls approaches including servo actuation hybrid control and trajectory planning Design aspects include determining specifications for a robot determining its configuration and utilizing sensors and actuators The featured applications focus on how the specific difficulties are overcome in the development of the robotic system With the ability to increase human safety and precision in applications ranging from handling hazardous materials and exploring extreme environments to manufacturing and medicine the uses for robots are growing steadily The Robotics and Automation Handbook provides a solid foundation for engineers and scientists interested in designing fabricating or utilizing robotic systems

Robot Control 1991 (SYROCO'91) I. Troch, 2014-05-23 This volume contains 92 papers on the state of the art in robotics research In this volume topics on

modelling and identification are treated first as they build the basis for practically all control aspects Then the most basic control tasks are discussed i e problems of inverse kinematics Groups of papers follow which deal with various advanced control aspects They range from rather general methods to more specialized topics such as force control and control of hydraulic robots The problem of path planning is addressed and strategies for robots with one arm for mobile robots and for multiple arm robots are presented Also covered are computational improvements and software tools for simulation and control the integration of sensors and sensor signals in robot control

### **Legged Robots that Balance** Marc H.

Raibert,1986 This book by a leading authority on legged locomotion presents exciting engineering and science along with fascinating implications for theories of human motor control It lays fundamental groundwork in legged locomotion one of the least developed areas of robotics addressing the possibility of building useful legged robots that run and balance The book describes the study of physical machines that run and balance on just one leg including analysis computer simulation and laboratory experiments Contrary to expectations it reveals that control of such machines is not particularly difficult It describes how the principles of locomotion discovered with one leg can be extended to systems with several legs and reports preliminary experiments with a quadruped machine that runs using these principles Raibert s work is unique in its emphasis on dynamics and active balance aspects of the problem that have played a minor role in most previous work His studies focus on the central issues of balance and dynamic control while avoiding several problems that have dominated previous research on legged machines Marc Raibert is Associate Professor of Computer Science and Robotics at Carnegie Mellon University and on the editorial board of The MIT Press journal Robotics Research Legged Robots That Balance is fifteenth in the Artificial Intelligence Series edited by Patrick Winston and Michael Brady

### **Proceedings of the 2018 International Symposium on Experimental Robotics** Jing Xiao,Torsten Kröger,Oussama Khatib,2020-01-22

In addition to the contributions presented at the 2018 International Symposium on Experimental Robotics ISER 2018 this book features summaries of the discussions that were held during the event in Buenos Aires Argentina These summaries authored by leading researchers and session organizers offer important insights on the issues that drove the symposium debates Readers will find cutting edge experimental research results from a range of robotics domains such as medical robotics unmanned aerial vehicles mobile robot navigation mapping and localization field robotics robot learning robotic manipulation human robot interaction and design and prototyping In this unique collection of the latest experimental robotics work the common thread is the experimental testing and validation of new ideas and methodologies The International Symposium on Experimental Robotics is a series of bi annual symposia sponsored by the International Foundation of Robotics Research whose goal is to provide a dedicated forum for experimental robotics research In recent years robotics has broadened its scientific scope deepened its methodologies and expanded its applications However the significance of experiments remains at the heart of the discipline The ISER gatherings are an essential venue where scientists can meet and have in depth

discussions on robotics based on this central tenet      **Applied Mechanics Reviews** ,1988      **MFI ...** ,1999

**Telemanipulator and Telepresence Technologies** ,1994      *IROS* ,1999      *Proceedings of the 26th IEEE Conference on Decision and Control* ,1987      *Telemanipulator Technology* Hari Das,1993      **Proceedings** ,1992      **Robomatix Reporter** ,1986      *Recent Development in Stability, Vibration, and Control of Structural Systems* American Society of Mechanical Engineers. Applied Mechanics Division,1993      **Proceedings of the First Asian Control Conference, Tokyo Metropolitan Institute of Technology, Tokyo, July 27-30, 1994** ,1994      *Modeling and Control of Robotic Manipulators and Manufacturing Processes* American Society of Mechanical Engineers. Winter Annual Meeting,1987      **Proceedings of the 1991 American Control Conference** ,1991      **Proceedings of the NASA Conference on Space Telerobotics, Volume 1** ,1989      **Modeling, Analysis, and Tracking Control of Brushless DC Motors for Robotic Applications** Neyram Hemati,1988

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