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Direct Drive Robot

Dai Gil Lee, Nam Pyo Suh



Direct Drive Robot:

Direct-Drive Robots Haruhiko Asada, Kamal Youcef-Toumi, 1987-05 An introduction to the design concept and control issues of the high performance direct drive robot arm **The Aisne and Montidier-Noyon Operations** ,1922 **Precise Motion Control of a Direct Drive Robot in Fast Maneuvers** Chih-Lung Yang, 1994 *Mini Direct Drive Robot for Biomedical Applications* Pierre-Henry Marbot, 1991 System Identification and Control of a Direct-drive Robot Yu-Ming Wang, 1986 Dynamics and Robust Control of Robot-environment Interaction Miomir Vukobratovi?, 2009 This book covers the most attractive problem in robot control dealing with the direct interaction between a robot and a dynamic environment including the human robot physical interaction It provides comprehensive theoretical and experimental coverage of interaction control problems starting from the mathematical modeling of robots interacting with complex dynamic environments and proceeding to various concepts for interaction control design and implementation algorithms at different control layers Focusing on the learning principle it also shows the application of new and advanced learning algorithms for robotic contact tasks The ultimate aim is to strike a good balance between the necessary theoretical framework and theoretical aspects of interactive robots **Axiomatic Design and Fabrication of Composite Structures** Dai Gil Lee, Nam Pyo Suh, 2006 The idea that materials can be designed to satisfy specific performance requirements is relatively new With high performance composites however the entire process of designing and fabricating a part can be worked out before manufacturing The purpose of this book is to present an integrated approach to the design and manufacturing of products from advanced composites It shows how the basic behavior of composites and their constitutive relationships can be used during the design stage which minimizes the complexity of manufacturing composite parts and reduces the repetitive design build test cycle Designing it right the first time is going to determine the competitiveness of a company the reliability of the part the robustness of fabrication processes and ultimately the cost and development time of composite parts Most of all it should expand the use of advanced composite parts in fields that use composites only to a limited extent at this time To achieve these goals this book presents the design and fabrication of novel composite parts made for machine tools and other applications like robots and automobiles This book is suitable as a textbook for graduate courses in the design and fabrication of composites It will also be of interest to practicing engineers learning about composites and axiomatic design A CD ROM is included in every copy of the book containing Axiomatic CLPT software This program developed by the authors will assist readers in calculating material properties from the microstructure of the composite This book is part of the Oxford Series on Advanced Manufacturing *Analysis and Design of a Direct Drive Robot* Shoeb (Shoeb Saifuddin) Rajguru, 1989 *Position and Force Control of Direct Drive Robot Arms* Mohammad Sahirad, 1988 **Studies of a Direct Drive Robot with a Parallel Configuration** ,1990 A new light weight six degrees of freedom direct drive robot is studied in this project The robot has a dual arm or a semi parallel configuration and it has the characteristics between those of a serial robot and

those of a parallel robot That is it has a large payload to weight ratio and high stiffness of a parallel robot and a large workspace compact structure and simple control algorithm of a serial robot Because of the use of direct drive motors and composite materials the robot is light weight and has high precision Different robot configurations are synthesized for different motion requirements Motion and force analysis are carried out in the project and motion simulation programs are completed Possible army applications are explored

Robust Motion Control of a Two-axis SCARA Type Direct Drive Robot Praveen Kashyap,1992 Robotics: From Automaton to the Roomba Racquel Foran,2015-01-01 This title presents the history of robotics Vivid text details how early mechanical automaton led to the advanced intelligent robots of today It also puts a spotlight on the brilliant scientists who made these advances possible Useful sidebars rich images and a glossary help readers understand the science and its importance Maps and diagrams provide context for critical discoveries in the field Aligned to Common Core Standards and correlated to state standards Essential Library is an imprint of ABDO Publishing a division of ABDO

Continuous Path Generation for a Direct-drive Robot Arm Thomas E. Desmond,1985 *Robotics and Manufacturing* International Association of Science and Technology for Development,1989 Trajectory Control of the M.I.T. Direct-drive Robot Tong-Yuan Andrew Kuo,1987 Robotics Science Michael Brady,1989 These 16 contributions provide a field guide to robotics science today Each takes up current work the problems addressed and future directions in the areas of perception planning control design and actuation In a substantial introduction Michael Brady summarizes a personal list of 30 problems problem areas and issues that lie on the path to development of a science of robotics These involve sensing vision mobility design control manipulation reasoning geometric reasoning and systems integration ContentsThe Problems of Robotics Michael Brady Perception A Few Steps Toward Artificial 3 D Vision Olivier D Faugeras Contact Sensing for Robot Active Touch Paolo Dario Learning and Recognition in Natural Environments Alex Pentland and Robert Bolles 3 D Vision for Outdoor Navigation by an Autonomous Vehicle Martial Hebert and Takeo Kanade Planning Geometric Issues in Planning Robot Tasks Tomas Lozano Perez and Russell Taylor Robotic Manipulation Mechanics and Planning Matthew Mason Control A Survey of Manipulation and Assembly Development of the Field and Open Research Issues Daniel Whitney Control Suguru Arimoto Kinematics and Dynamics for Control John Hollerbach The Whole Iguana Rodney Brooks Design and Actuation Design and Kinematics for Force and Velocity Control of Manipulators and End Effectors Bernard Roth Arm Design Haruhiko Asada Behavior Based Design of Robot Effectors Stephen Jacobsen Craig Smith Klaus Biggers and Edwin Iversen Using an Articulated Hand to Manipulate Objects Kenneth Salisbury David Brock and Patrick O Donnell Legged Robots Marc RaibertRobotics Science is included in the System Development Foundation Benchmark series System Development Foundation grants have contributed significantly to the development of robotics in the United States during the 1980s

Computer Aided Analysis and Design of a Direct Drive Robot Mark Andrews,1986 *Robotics and Manufacturing* Mohammad Jamshidi,Mehrdad Saif,1990 The

presentations of the technical papers in this volume have been grouped in accordance to specialized areas of robotics and manufacturing for easy access to the reader The 145 technical papers cover topics in these important areas Kinematics and Dynamics Path and Task Planning Sensors Magnetic Levitation and Control Architectures Robotic Control Robots in Unstructured Environments Redundant and Flexible Robots Automated and Flexible Manufacturing AI and Simulation Dual and Mobile Robots Education and Research and Neural Networks and Learning Design of Direct-Drive Mechanical Arms Haruhiko Asada,Takeo Kanade,CARNEGIE-MELLON UNIV PITTSBURGH PA ROBOTICS INST.,1981 This paper describes the design concept of a new robot based on the direct drive method using rare earth DC torque motors Because these motors have high torque light weight and compact size we can construct robots with far better performance than those presently available For example we can eliminate all the transmission mechanism between the motors and their loads such as reducers and chain belts and construct a simple mechanism direct drive where the arm links are directly coupled to the motor rotors This elimination can lead to excellent performance no backlash low friction low inertia low compliance and high reliability all of which are suited for high speed high precision robots First we propose a basic configuration of direct drive robots Second a general procedure for designing direct drive robots is shown and the feasibility of direct drive for robot actuation is discussed in terms of weights and torques of joints One of the difficulties in designing direct drive robots is that motors to drive wrist joints are loads for motors to drive elbow joints and they are loads for motors at shoulders To reduce this increasing series of loads is an essential issue for designing practical robots We analyze the series of joint mass for a simplified kinematic model of the direct drive robots and show how the loads are reduced significantly by using rare earth motors with light weight and high torque We also discuss optimum kinematic structures with minimum arm weight Finally we describe the direct drive robotic manipulator CMU arm developed at Carnegie Mellon University and verify the design theory Author **Modeling and Control of Robotic Manipulators and Manufacturing Processes** American Society of Mechanical Engineers. Winter Annual Meeting,1987

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