
Contents

1. Introduction 1	
1.1 Introduction	1
1.2 Brief History	1
1.3 Types of Robots	7
1.4 Technology of Robots	9
1.5 Basic Principles in Robotics	12
1.6 Notation	15
1.7 Symbolic Computation and Numerical Analysis	15
2. Mathematical Representation of Robots 19	
2.1 Introduction	19
2.2 Position and Orientation of a Rigid Body	19
2.2.1 Some Properties of Rotation Matrices	22
2.2.2 Successive Rotations of a Rigid Body	25
2.2.3 Representation of Orientation by Three Angles	27
2.2.4 Other Representations of Orientation	30
2.3 Transformation Between Coordinate Systems	32
2.3.1 Homogeneous Transformation	34
2.4 Properties of ${}^A_B[T]$	34
2.5 Representation of Joints	36
2.5.1 Rotary Joint	38
2.5.2 Prismatic Joint	39
2.5.3 Screw Joint	40
2.5.4 Cylindrical Joint	41
2.5.5 Spherical Joint	41
2.5.6 Spherical–Spherical Joint Pair	42
2.5.7 Other Joints	43
2.6 Representation of Links Using Denavit–Hartenberg Parameters	43
2.6.1 Link Parameters for Intermediate Links	44
2.6.2 First and Last Links	45
2.6.3 Summary of Link Parameters	46
2.7 Link Transformation Matrices	47
Example 2.1: The planar 3R manipulator	48

Example 2.2: The PUMA 560 manipulator	51
Example 2.3: A SCARA manipulator	53
Example 2.4: The planar four-bar mechanism	55
Example 2.5: A three-DOF parallel manipulator	56
Example 2.6: A six-DOF parallel manipulator	58
2.8* Homogeneous Coordinates, Lines, Screws, and Twists	60
3. Kinematics of Serial Manipulators	69
3.1 Introduction	69
3.2 Degrees of Freedom of a Manipulator	69
3.3 Direct Kinematics of Serial Manipulators	71
Example 3.1: The planar 3R manipulator	72
Example 3.2: The PUMA 560 manipulator	72
Example 3.3: A SCARA manipulator	73
3.4 Inverse Kinematics of Serial Manipulators	73
Example 3.4: The planar 3R manipulator	74
Example 3.5: The PUMA 560 manipulator	76
3.5 Manipulator With Non-intersecting Wrist	82
3.6* Inverse Kinematics of a General 6R Robot	85
3.7 Inverse Kinematics for Manipulators With $n < 6$	88
3.8 Inverse Kinematics of Redundant Manipulators	89
3.9* Solution Methods for Non-linear Equations	92
4. Kinematics of Parallel Manipulators	102
4.1 Introduction	102
4.2 Degrees of Freedom	103
4.3 Loop-closure Constraint Equations	103
4.4 Direct Kinematics of Parallel Manipulators	110
Example 4.1: The planar four-bar mechanism	111
Example 4.2: A three-DOF parallel manipulator	114
Example 4.3: A six-DOF parallel manipulator	117
4.5* Direct Kinematics of Stewart–Gough Platform	119
4.6 Mobility of Parallel Manipulators	123
Example 4.4: The planar four-bar mechanism	124
Example 4.5: A three-DOF parallel manipulator	126
4.7 Inverse Kinematics of Parallel Manipulators	127
Example 4.6: A six-DOF hybrid manipulator	129
Example 4.7: The Stewart platform	131
5. Velocity Analysis and Statics of Manipulators	137
5.1 Introduction	137
5.2 Linear and Angular Velocities of a Rigid Body	138

5.3	Linear and Angular Velocities of Links in Serial Manipulators	143
	Example 5.1: The planar 3R manipulator	144
5.4	Serial Manipulator Jacobian	146
5.5	Parallel Manipulator Jacobians	152
	Example 5.2: The planar four-bar mechanism	155
	Example 5.3: A three-DOF parallel manipulator	155
5.6	Singularities of Serial and Parallel Manipulators	158
	Example 5.4: The planar four-bar mechanism	162
	Example 5.5: A three-DOF parallel manipulator	163
5.7	Statics of Serial Manipulators	166
	Example 5.6: The planar 3R manipulator	168
5.8	Statics of Parallel Manipulators	171
5.9	Singularity in Force Domain	173
5.10	Resolution of Redundancy at Velocity Level	177
6.	Dynamics of Manipulators	183
6.1	Introduction	183
6.2	Inertia of a Link	185
6.3	The Lagrangian Formulation	187
	Example 6.1: Equations of motion of a planar 2R manipulator	192
	Example 6.2: Equations of motion of a planar four-bar mechanism	196
6.4	Dynamic Equations in Cartesian Space	201
6.5	Inverse Dynamics of Manipulators	202
	Example 6.3: Inverse dynamics of planar 2R manipulator	202
6.6	Simulation of Equations of Motion	204
	Example 6.4: Simulation of a planar 2R manipulator	207
	Example 6.5: Simulation of a planar four-bar mechanism	208
6.7	Recursive Formulations of Dynamics of Manipulators	210
	6.7.1 Newton–Euler Formulation for Inverse Dynamics	210
	6.7.2* Algorithms for Forward Dynamics	213
	6.7.3* Recursive Algorithms for Parallel Manipulators	216
7.	Trajectory Planning and Generation	220
7.1	Introduction	220
7.2	Joint Space Schemes	221
	Example 7.1: A cubic trajectory	223
7.3	Joint Space Schemes With Via Points	226
	Example 7.2: A cubic trajectory with a via point	226
	Example 7.3: A cubic trajectory with matching velocity and acceleration at a via point	228

7.4	Cartesian Space Schemes	229
7.4.1	Cartesian Straight Line Motion	230
7.4.2	Cartesian Circular Motion	231
7.4.3	Trajectory Planning for Orientation	233
7.5	Some Additional Issues in Trajectory Planning	234
8.	Position and Force Control of Manipulators	238
8.1	Introduction	238
8.2	Feedback Control of a Single-link Manipulator	239
8.2.1	Usefulness of Feedback	243
8.2.2	First-order System	245
8.2.3	Second-order System	246
8.2.4	PID Control of a Single-link Manipulator	248
8.2.5	Digital Control of a Single-link Manipulator	250
8.3	PID Control of a Multi-link Manipulator	252
8.4	Non-linear Control of Manipulators	255
8.4.1	Time Required to Compute the Model	258
8.4.2	Lack of Knowledge of Model Parameters	259
8.5	Simulation and Experimental Results	259
8.5.1	Simulation Results	259
8.5.2	Experimental Results	267
8.6	Non-linear Control of Constrained and Parallel Manipulators	271
8.7	Cartesian Control of Manipulators	276
8.8	Force Control of Manipulators	279
8.8.1	Force Control of a Single Mass	280
8.8.2	Partitioning a Task for Force and Position Control	283
	Example 8.1: Peg-in-hole assembly	286
8.9	Hybrid Position/Force Controller	288
8.10	Stability Analysis of Non-linear Control Schemes	290
8.10.1	Stability Analysis Using Lyapunov's Method	290
	Example 8.2: Stability analysis of a single-link manipulator	292
8.10.2	Stability Analysis of PD-and Model-based Control	295
8.11*	Advanced Topics in Non-linear Control of Manipulators	296
9.	Modelling and Control of Flexible Manipulators*	304
9.1	Introduction	304
9.2	Modelling of a Flexible Joint	305
9.3	Euler–Bernoulli Beam Model	307
9.3.1	Rotating Flexible Link	309
9.3.2	Translating Flexible Link	313
9.4	Kinematic Modelling of Multi-link Flexible Manipulators	315
9.5	Discretization Methods	319

9.5.1	Assumed Modes Method	319
9.5.2	FiniteElement Method	325
9.5.3	Comparison of Discretization Methods	329
9.6	Equations of Motion of Multi-link Flexible Manipulators	331
9.6.1	Kinetic Energy	332
9.6.2	Potential Energy	333
9.6.3	Symbolic Equations of Motion	336
9.7	Control of Flexible Link Manipulators	337
9.7.1	Controllability of Flexible-link Manipulators	339
9.7.2	Model-based Controlfor Trajectory Following	340
9.7.3	End Position Vibration Control	343
9.7.4	A Two-stage Control Algorithm	347
9.7.5	Effect of Uncertainty in Massand Stiffness	349
9.7.6	Numerical Simulation of a Flexible Manipulator	351
9.8	Other Topics in Flexible Manipulators	355
10.	Modelling and Analysis of Wheeled Mobile Robots*	362
10.1	Introduction	362
10.2	Motion of a Single Wheel on Uneven Terrain	365
10.2.1	Model of a Torus-shaped Wheel	365
10.2.2	Representation of Uneven Terrain in \mathcal{R}^3	368
10.2.3	Kinematics of Contact	372
10.2.4	Kinematics of a Single Wheel	374
10.3	Dynamics of a Torus-shaped Wheel on Uneven Terrain	378
10.4	Kinematic Modelling of a Three-wheeled Mobile Robot	383
10.4.1	Direct and Inverse Kinematics of the 3-DOFWMR	385
10.4.2	Numerical Simulation Results	388
10.5	Dynamic Modelling of a Three-wheeled Mobile Robot	394
10.5.1	Equations of Motion of a Three-wheeled Mobile Robot	394
10.5.2	Algorithm for Solving the Equations of Motion	397
10.5.3	Numerical Simulation Results	398
10.6	Traversability of a Single Wheel	401
10.7	More on Modelling of Wheeled Mobile Robots	407
	Index	413