



## Advances in Robot Kinematics

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## Advances in Robot Kinematics

This book presents the most recent research advances in the theory, design, control and application of robotic systems, which are intended for a variety of purposes such as manipulation, manufacturing, automation, surgery, locomotion and biomechanics. The issues addressed are fundamentally kinematic in nature, including synthesis, calibration, redundancy, force control, dexterity, inverse and forward kinematics, kinematic singularities, as well as over-constrained systems. Methods used include line geometry, quaternion algebra, screw algebra, and linear algebra. These methods are applied to both parallel and serial multi-degree-of-freedom systems. The results should interest researchers, teachers and students, in fields of engineering and mathematics related to robot theory, design, control and application. All articles in the book were reported at the seventh international symposium on Advances in Robot Kinematics that was organised in June 2000 in the beautiful ancient Mediterranean town of Piran in Slovenia. The preceding symposia of the series took place in Ljubljana (1988), Linz (1990), Ferrara (1992), Ljubljana (1994), and Piran (1996), and Salzburg (1998).

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