

Contents

PREFACE

xv

1 ROBOTIC MANIPULATION

1

1-1	Automation and Robots	1
1-2	Robot Classification	3
	<i>1-2-1 Drive Technologies, 3</i>	
	<i>1-2-2 Work-Envelope Geometries, 4</i>	
	<i>1-2-3 Motion Control Methods, 7</i>	
1-3	Applications	8
1-4	Robot Specifications	9
	<i>1-4-1 Number of Axes, 9</i>	
	<i>1-4-2 Capacity and Speed, 10</i>	
	<i>1-4-3 Reach and Stroke, 10</i>	
	<i>1-4-4 Tool Orientation, 11</i>	
	<i>1-4-5 Repeatability, Precision, and Accuracy, 13</i>	
	<i>1-4-6 Operating Environment, 16</i>	
	<i>1-4-7 An Example: Rhino XR-3, 16</i>	
1-5	Notation	18
1-6	Problems	22
	References	24

2 DIRECT KINEMATICS: THE ARM EQUATION

- 2-1 Dot and Cross Products 26
2-2 Coordinate Frames 29
2-3 Rotations 33
 2-3-1 *Fundamental Rotations*, 33
 2-3-2 *Composite Rotations*, 36
2-4 Homogeneous Coordinates 41
 2-4-1 *Homogeneous Coordinate Frames*, 41
 2-4-2 *Translations and Rotations*, 42
 2-4-3 *Composite Homogeneous Transformations*, 45
 2-4-4 *Screw Transformations*, 49
2-5 Link Coordinates 51
 2-5-1 *Kinematic Parameters*, 51
 2-5-2 *Normal, Sliding, and Approach Vectors*, 53
 2-5-3 *The Denavit-Hartenberg (D-H) Representation*, 53
 2-5-4 *An Example: Microbot Alpha II*, 54
2-6 The Arm Equation 57
 2-6-1 *The Arm Matrix*, 57
 2-6-2 *The Arm Equation*, 60
 2-6-3 *An Example: Microbot Alpha II*, 60
2-7 A Five-Axis Articulated Robot (Rhino XR-3) 62
 2-7-1 *The Link-Coordinate Diagram*, 63
 2-7-2 *The Arm Matrix*, 63
 2-7-3 *Joint Coupling*, 67
2-8 A Four-Axis SCARA Robot (Adept One) 68
 2-8-1 *The Link-Coordinate Diagram*, 68
 2-8-2 *The Arm Matrix*, 70
2-9 A Six-Axis Articulated Robot (Intellegedex 660) 71
 2-9-1 *The Link-Coordinate Diagram*, 73
 2-9-2 *The Arm Matrix*, 74
2-10 Problems 76
References 80

3 INVERSE KINEMATICS: SOLVING THE ARM EQUATION

- 3-1 The Inverse Kinematics Problem 81
3-2 General Properties of Solutions 84
 3-2-1 *Existence of Solutions*, 84
 3-2-2 *Uniqueness of Solutions*, 85

3-3	Tool Configuration	87
	3-3-1 Tool-Configuration Vector,	87
	3-3-2 Tool Configuration of a Five-Axis Articulated Robot,	88
	3-3-3 Tool Configuration of a Four-Axis SCARA Robot,	89
3-4	Inverse Kinematics of a Five-Axis Articulated Robot (Rhino XR-3)	90
	3-4-1 Base Joint,	92
	3-4-2 Elbow Joint,	92
	3-4-3 Shoulder Joint,	93
	3-4-4 Tool Pitch Joint,	94
	3-4-5 Tool Roll Joint,	94
	3-4-6 Complete Solution,	95
3-5	Inverse Kinematics of a Four-Axis SCARA Robot (Adept One)	96
	3-5-1 Elbow Joint,	97
	3-5-2 Base Joint,	98
	3-5-3 Vertical Extension Joint,	98
	3-5-4 Tool Roll Joint,	98
	3-5-5 Complete Solution,	99
3-6	Inverse Kinematics of a Six-Axis Articulated Robot (Intelleddex 660)	100
	3-6-1 Tool Roll Joint,	101
	3-6-2 Shoulder Roll Joint,	101
	3-6-3 Base Joint,	102
	3-6-4 Elbow Joint,	102
	3-6-5 Shoulder Pitch Joint,	103
	3-6-6 Tool Pitch Joint,	104
	3-6-7 Complete Solution,	104
3-7	Inverse Kinematics of a Three-Axis Planar Articulated Robot	105
	3-7-1 Shoulder Joint,	107
	3-7-2 Base Joint,	108
	3-7-3 Tool Roll Joint,	108
	3-7-4 Complete Solution,	108
3-8	A Robotic Work Cell	109
3-9	Problems	112
	References	115

4 WORKSPACE ANALYSIS AND TRAJECTORY PLANNING

116

4-1	Workspace Analysis	116
4-2	Work Envelope of a Five-Axis Articulated Robot (Rhino XR-3)	118

4-3	Work Envelope of a Four-Axis SCARA Robot (Adept One)	122
4-4	Workspace Fixtures	124
	4-4-1 Part Feeders,	125
	4-4-2 Conveyers and Carousels,	127
	4-4-3 Fixed Tools,	128
4-5	The Pick-and-Place Operation	131
	4-5-1 Pick and Lift-Off Points,	131
	4-5-2 Place and Set-Down Points,	132
	4-5-3 Speed Variation,	134
4-6	Continuous-Path Motion	135
	4-6-1 Paths and Trajectories,	135
	4-6-2 Continuous-Path Control of a Five-Axis Articulated Robot (Rhino XR-3),	137
	4-6-3 Continuous-Path Control of a Four-Axis SCARA Robot (Adept One),	139
4-7	Interpolated Motion	140
	4-7-1 Cubic Polynomial Paths,	141
	4-7-2 Linear Interpolation with Parabolic Blends,	142
4-8	Straight-Line Motion	145
4-9	Problems	148
	References	151

5 DIFFERENTIAL MOTION AND STATICS

153

5-1	The Tool-Configuration Jacobian Matrix	153
	5-1-1 Tool Jacobian Matrix of a Five-Axis Articulated Robot (Rhino XR-3),	154
	5-1-2 Tool Jacobian Matrix of a Four-Axis SCARA Robot (Adept One),	156
	5-1-3 Tool Jacobian Matrix of a Three-Axis Planar Articulated Robot,	157
5-2	Joint-Space Singularities	158
5-3	Generalized Inverses	160
5-4	Resolved-Motion Rate Control: $n \leq 6$	164
5-5	Rate Control of Redundant Robots: $n > 6$	166
5-6	Rate Control Using {1}-Inverses	171

5-7	The Manipulator Jacobian	174
5-7-1	<i>Manipulator Jacobian of a Four-Axis SCARA Robot (Adept One)</i>	177
5-7-2	<i>Manipulator Jacobian of a Five-Axis Articulated Robot (Rhino XR-3)</i>	179
5-7-3	<i>Manipulator Jacobian of a Three-Axis Planar Articulated Robot</i>	181
5-8	Induced Joint Torques and Forces	182
5-8-1	<i>End-of-Arm Compliance and Stiffness</i>	184
5-8-2	<i>Joint-Space Singularities</i>	187
5-9	Problems	190
	References	193

6 MANIPULATOR DYNAMICS

194

6-1	Lagrange's Equation	195
6-2	Kinetic and Potential Energy	195
6-2-1	<i>Link Inertia Tensor</i>	196
6-2-2	<i>Link Jacobian</i>	198
6-2-3	<i>Manipulator Inertia Tensor</i>	199
6-2-4	<i>Gravity</i>	200
6-3	Generalized Force	201
6-3-1	<i>Actuators</i>	202
6-3-2	<i>Friction</i>	202
6-4	Lagrange-Euler Dynamic Model	204
6-5	Dynamic Model of a Two-Axis Planar Articulated Robot	208
6-6	Dynamic Model of a Three-Axis SCARA Robot	212
6-7	Direct and Inverse Dynamics	220
6-8	Recursive Newton-Euler Formulation	221
6-8-1	<i>Forward Newton-Euler Equations</i>	222
6-8-2	<i>Backward Newton-Euler Equations</i>	223
6-9	Dynamic Model of a One-Axis Robot (Inverted Pendulum)	226
6-9-1	<i>Lagrange-Euler Formulation</i>	226
6-9-2	<i>Newton-Euler Formulation</i>	228
6-10	Problems	231
	References	232

7 ROBOT CONTROL

234

- 7-1 The Control Problem 235
- 7-2 State Equations 236
 - 7-2-1 A One-Axis Robot (*Inverted Pendulum*), 237
 - 7-2-2 A Two-Axis Planar Articulated Robot, 238
 - 7-2-3 A Three-Axis SCARA Robot, 240
- 7-3 Constant Solutions 243
 - 7-3-1 Liapunov's First Method, 247
 - 7-3-2 Liapunov's Second Method, 250
- 7-4 Linear Feedback Systems 256
 - 7-4-1 Transfer Function, 256
 - 7-4-2 Steady-State Tracking, 261
 - 7-4-3 Transient Performance, 263
- 7-5 Single-Axis PID Control 265
 - 7-5-1 DC Motor and Load, 266
 - 7-5-2 Torque Regulator, 268
 - 7-5-3 PID Transfer Function, 272
- 7-6 PD-Gravity Control 276
- 7-7 Computed-Torque Control 283
- 7-8 Variable-Structure Control 289
- 7-9 Impedance Control 298
- 7-10 Problems 303
- References 306

8 ROBOT VISION

307

- 8-1 Image Representation 308
- 8-2 Template Matching 309
- 8-3 Polyhedral Objects 313
 - 8-3-1 Edge Detection, 313
 - 8-3-2 Corner Points, 317
 - 8-3-3 Run-Length Encoding, 318
- 8-4 Shape Analysis 319
 - 8-4-1 Line Descriptors, 319
 - 8-4-2 Area Descriptors, 321
 - 8-4-3 Principal Angle, 324

8-5	Segmentation	325
	8-5-1 Thresholding,	325
	8-5-2 Region Labeling,	326
8-6	Iterative Processing	330
	8-6-1 Shrink Operators,	330
	8-6-2 Swell Operators,	332
	8-6-3 Euler Number,	334
8-7	Perspective Transformations	337
	8-7-1 Perspective Transformation,	337
	8-7-2 Inverse Perspective Transformation,	340
	8-7-3 Pixel Coordinates,	343
8-8	Structured Illumination	345
	8-8-1 Light Sources,	345
	8-8-2 Light Patterns,	346
	8-8-3 Triangulation,	348
8-9	Camera Calibration	350
8-10	Problems	353
	References	355

9 TASK PLANNING 357

9-1	Task-Level Programming	358
9-2	Uncertainty	359
9-3	Configuration Space	362
	9-3-1 Translations,	362
	9-3-2 Rotations,	366
9-4	Gross-Motion Planning	368
	9-4-1 Generalized Voronoi Diagrams (GVD),	369
	9-4-2 Motion Heuristics,	375
9-5	Grasp Planning	378
9-6	Fine-Motion Planning	381
	9-6-1 Guarded Motion,	382
	9-6-2 Compliant Motion,	385
9-7	Simulation of Planar Motion	388
9-8	A Task-Planning Problem	391
	9-8-1 Source and Goal Scenes,	391

9-8-2	<i>Task-Planning Subproblems</i> , 392
9-8-3	<i>Task Planner Simulation</i> , 394
9-9	Problems 396
	References 398
APPENDIX 1 TRIGONOMETRIC IDENTITIES	
APPENDIX 2 MOMENTS OF INERTIA	
APPENDIX 3 LIST OF SYMBOLS	
INDEX	