

Tetrobot

Simona Vlad,Radu V. Ciupa,Anca I. Nicu

Tetrobot Gregory J. Hamlin, Arthur C. Sanderson, 2013-03-09 Robotic systems are characterized by the intersection of computer intelligence with the physical world. This blend of physical reasoning and computational intelligence is well illustrated by the Tetrobot study described in this book. *Tetrobot: A Modular Approach to Reconfigurable Parallel Robotics* describes a new approach to the design of robotic systems. The Tetrobot approach utilizes modular components which may be reconfigured into many different mechanisms which are suited to different applications. The Tetrobot system includes two unique contributions: a new mechanism (a multilink spherical joint design), and a new control architecture based on propagation of kinematic solutions through the structure. The resulting Tetrobot system consists of fundamental components which may be mechanically reassembled into any modular configuration, and the control architecture will provide position control of the resulting structure. A prototype Tetrobot system has been built and evaluated experimentally. Tetrobot arms, platforms, and walking machines have been built and controlled in a variety of motion and loading conditions. The Tetrobot system has applications in a variety of domains where reconfiguration, flexibility, load capacity, and failure recovery are important aspects of the task. A number of key research directions have been opened by the Tetrobot research activities. Continuing topics of interest include: development of a more distributed implementation of the computer control architecture, analysis of the dynamics of the Tetrobot system motion for improved control of high-speed motions, integration of sensor systems to control the motion and shape of the high-dimensionality systems, and exploration of self-reconfiguration of the system. *Tetrobot: A Modular Approach to Reconfigurable Parallel Robotics* will be of interest to research workers, specialists and professionals in the areas of robotics, mechanical systems and computer engineering.

International Conference on Advancements of Medicine and Health Care through Technology; 23 - 26 September 2009 Cluj-Napoca, Romania
Simona Vlad, Radu V. Ciupa, Anca I. Nicu, 2010-02-01 Projections for advances in medical and biological technology will transform medical care and treatment. This in great part is due to the result of the interaction and collaboration between medical sciences and engineering. These advances will result in substantial progress in health care and in the quality of life of the population. Frequently however, the implications of technologies in terms of increasing recurrent costs, additional required support services, change in medical practice and training needs are underestimated. As a result, the widespread irrational use of technologies leads to a wastage of scarce resources and weakens health systems performance. To avoid such problems, a systematic and effective Health Technology System must be developed and introduced, requiring the support and commitment of decision makers of all levels of the health system. The MediTech2009 conference aims to provide a special opportunity for the Romanian professionals involved in basic research, R&D, industry and medical applications to exchange their know-how and build up collaboration in one of the most human field of science and techniques. The conference is intended to be an international forum for researchers and practitioners interested in the advance in, and applications of biomedical engineering to exchange the latest research results and ideas in the areas covered by the topics (and not only!). We believe the reader will find the proceedings an impressive document of progress to date in this rapidly changing field.

Sensor Fusion and Decentralized Control in Robotic Systems ,2001

Sensor Fusion and Decentralized Control in Robotic Systems II G. T. McKee, Paul S. Schenker, 1999 This work presents a series of papers examining various aspects of sensor fusion and decentralized control in robotic systems.

Self-Organizing Robots Satoshi Murata, Haruhisa Kurokawa, 2012-01-22 It is man's ongoing hope that a machine could somehow adapt to its environment by reorganizing itself. This is what the notion of self-organizing robots is based on. The theme of this book is to examine the feasibility of creating such robots within the limitations of current mechanical engineering. The topics comprise the following aspects of such a pursuit: the

philosophy of design of self-organizing mechanical systems; self-organization in biological systems; the history of self-organizing mechanical systems; a case study of a self-assembling/self-repairing system as an autonomous distributed system; a self-organizing robot that can create its own shape and robotic motion; implementation and instrumentation of self-organizing robots; and the future of self-organizing robots. All topics are illustrated with many up-to-date examples, including those from the authors' own work. The book does not require advanced knowledge of mathematics to be understood, and will be of great benefit to students in the robotics discipline, including in the areas of mechanics, control, electronics, and computer science. It is also an important source for researchers who wish to investigate the field of robotics or who have an interest in the application of self-organizing phenomena.

IROS ,1999

Technical Report Adriano, Christian,Bleifuß, Tobias,Cheng, Lung-Pan,Diba, Kiarash,Fricke, Andreas,Grapentin, Andreas,Kovacs, Robert,Krejca, Martin,Jiang, Lan,Mandal, Sankalita,Marwecki, Sebastian,Matthies, Christoph,Mattis, Toni,Meinel, Christoph,Niephaus, Fabio,Pirl, Lukas,Quinza, Francesco,Ramson, Stefan,Rezaei, Mina,Risch, Julian,Rothenberger, Ralf,Roumen, Thijs,Stojanovic, Vladeta,Wolf, Johannes,2019 Der Entwurf und die Realisierung dienstbasierender Architekturen wirft eine Vielzahl von Forschungsfragestellungen aus den Gebieten der Softwaretechnik, der Systemmodellierung und -analyse, sowie der Adaptierbarkeit und Integration von Applikationen auf. Komponentenorientierung und WebServices sind zwei Ansätze für den effizienten Entwurf und die Realisierung komplexer Web-basierender Systeme. Sie ermöglichen die Reaktion auf wechselnde Anforderungen ebenso, wie die Integration großer komplexer Softwaresysteme. Heute übliche Technologien, wie J2EE und .NET, sind de facto Standards für die Entwicklung großer verteilter Systeme. Die Evolution solcher Komponentensysteme führt über WebServices zu dienstbasierenden Architekturen. Dies manifestiert sich in einer Vielzahl von Industriestandards und Initiativen wie XML, WSDL, UDDI, SOAP. All diese Schritte führen letztlich zu einem neuen, vielversprechenden Paradigma für IT Systeme, nach dem komplexe Softwarelösungen durch die Integration vertraglich vereinbarter Software-Dienste aufgebaut werden sollen. Service-Oriented Systems Engineering repräsentiert die Symbiose bewährter Praktiken aus den Gebieten der Objektorientierung, der Komponentenprogrammierung, des verteilten Rechnen sowie der Geschäftsprozesse und berücksichtigt auch die Integration von Geschäftsanliegen und Informationstechnologien. Die Klausurtagung des Forschungskollegs Service-oriented Systems Engineering findet einmal jährlich statt und bietet allen Kollegiaten die Möglichkeit den Stand ihrer aktuellen Forschung darzulegen. Bedingt durch die Querschnittstruktur des Kollegs deckt dieser Bericht ein weites Spektrum aktueller Forschungsthemen ab. Dazu zählen unter anderem Human Computer Interaction and Computer Vision as Service; Service-oriented Geovisualization Systems; Algorithm Engineering for Service-oriented Systems; Modeling and Verification of Self-adaptive Service-oriented Systems; Tools and Methods for Software Engineering in Service-oriented Systems; Security Engineering of Service-based IT Systems; Service-oriented Information Systems; Evolutionary Transition of Enterprise Applications to Service Orientation; Operating System Abstractions for Service-oriented Computing; sowie Services Specification, Composition, and Enactment. Design and Implementation of service-oriented architectures imposes a huge number of research questions from the fields of software engineering, system analysis and modeling, adaptability, and application integration. Component orientation and web services are two approaches for design and realization of complex web-based system. Both approaches allow for dynamic application adaptation as well as integration of enterprise application. Commonly used technologies, such as J2EE and .NET, form de facto standards for the realization of complex distributed systems. Evolution of component systems has lead to web services and service-based architectures. This has been manifested in a multitude of industry standards and initiatives such as XML, WSDL UDDI, SOAP, etc. All these achievements lead to a new and promising paradigm in IT systems engineering which proposes to design complex software solutions as collaboration of contractually defined software services. Service-Oriented Systems Engineering

represents a symbiosis of best practices in object-orientation, component-based development, distributed computing, and business process management. It provides integration of business and IT concerns. The annual Ph.D. Retreat of the Research School provides each member the opportunity to present his/her current state of their research and to give an outline of a prospective Ph.D. thesis. Due to the interdisciplinary structure of the research school, this technical report covers a wide range of topics. These include but are not limited to: Human Computer Interaction and Computer Vision as Service; Service-oriented Geovisualization Systems; Algorithm Engineering for Service-oriented Systems; Modeling and Verification of Self-adaptive Service-oriented Systems; Tools and Methods for Software Engineering in Service-oriented Systems; Security Engineering of Service-based IT Systems; Service-oriented Information Systems; Evolutionary Transition of Enterprise Applications to Service Orientation; Operating System Abstractions for Service-oriented Computing; and Services Specification, Composition, and Enactment.

Proceedings of 1995 IEEE International Conference on Robotics and Automation, May 21-27, 1995, Nagoya, Aichi, Japan IEEE Robotics and Automation Society, 1995

Robot Teams Tucker Balch, Lynne E. Parker, 2002-04-17 This is a comprehensive volume on robot teams that will be the standard reference on multi-robot systems. The volume provides not only the essentials of multi-agent robotics theory but also descriptions of exemplary implemented systems demonstrating the key concepts of multi-robot research. Information is presented in a descriptive manner and augme

2nd IMA Conference on Mathematics of Robotics William Holderbaum, J. M. Selig, 2021-11-20 This book highlights the mathematical depth and sophistication of techniques used in different areas of robotics. Each chapter is a peer-reviewed version of a paper presented during the 2021 IMA Conference on the Mathematics of Robotics, held online September 8–10, 2021. The conference gave a platform to researchers with fundamental contributions and for academic and to share new ideas. The book illustrates some of the current interest in advanced mathematics and robotics such as algebraic geometry, tropical geometry, monodromy and homotopy continuation methods applied to areas such as kinematics, path planning, swam robotics, dynamics and control. It is hoped that the conference and this publications will stimulate further related mathematical research in robotics.

Dissertation Abstracts International, 2001

IROS , 1990

Foundations of Robotics Damith Herath, David St-Onge, 2022-09-25 This open access book introduces key concepts in robotics in an easy to understand language using an engaging project-based approach. It covers contemporary topics in robotics, providing an accessible entry point to fundamentals in all the major domains. A section is dedicated to introducing programming concepts using Python, which has become a language of choice in robotics and AI. The book also introduces the reader to the Robot Operating System (ROS), the ubiquitous software and algorithmic framework used by researchers and the industry. The book provides an inspired, up-to-date and multidisciplinary introduction to robotics in its many forms, including emerging topics related to robotics on Machine Learning, ethics, Human-Robot Interaction, and Design Thinking. The book also includes interviews with industry experts, providing an additional layer of insight into the world of robotics. The book is made open access through the generous support from Kinova Robotics. The book is suitable as an undergraduate textbook in a relevant engineering course. It is also suitable for students in art and design, high school students, and self-learners who would like to explore foundational concepts in robotics. "This book provides the 'foundation' for understanding how robots work. It is the accessible introduction that artists and engineers have been waiting for." - Ken Goldberg, William S. Floyd Jr. Distinguished Chair in Engineering, UC Berkeley.

Programmable Matter Fouad Sabry, 2022-01-16 What Is Programmable Matter Programmable matter is matter which has the ability to change

its physical properties in a programmable fashion, based upon user input or autonomous sensing. Programmable matter is thus linked to the concept of a material which inherently has the ability to perform information processing. How You Will Benefit (I) Insights, and validations about the following topics: Chapter 1: Programmable matter Chapter 2: Metamaterial Chapter 3: Electropermanent magnet Chapter 4: Self-reconfiguring modular robot Chapter 5: Claytronics Chapter 6: Cellular automaton Chapter 7: Quantum well Chapter 8: Synthetic biology (II) Answering the public top questions about programmable matter. (III) Real world examples for the usage of programmable matter in many fields. (IV) 17 appendices to explain, briefly, 266 emerging technologies in each industry to have 360-degree full understanding of programmable matter' technologies. Who This Book Is For Professionals, undergraduate and graduate students, enthusiasts, hobbyists, and those who want to go beyond basic knowledge or information for any kind of programmable matter.

Perceptual Metrics for Image Database Navigation Yossi Rubner,Carlo Tomasi,2013-03-14 The increasing amount of information available in today's world raises the need to retrieve relevant data efficiently. Unlike text-based retrieval, where keywords are successfully used to index into documents, content-based image retrieval poses up front the fundamental questions how to extract useful image features and how to use them for intuitive retrieval. We present a novel approach to the problem of navigating through a collection of images for the purpose of image retrieval, which leads to a new paradigm for image database search. We summarize the appearance of images by distributions of color or texture features, and we define a metric between any two such distributions. This metric, which we call the Earth Mover's Distance (EMD), represents the least amount of work that is needed to rearrange the mass in one distribution in order to obtain the other. We show that the EMD matches perceptual dissimilarity better than other dissimilarity measures, and argue that it has many desirable properties for image retrieval. Using this metric, we employ Multi-Dimensional Scaling techniques to embed a group of images as points in a two- or three-dimensional Euclidean space so that their distances reflect image dissimilarities as well as possible. Such geometric embeddings exhibit the structure in the image set at hand, allowing the user to understand better the result of a database query and to refine the query in a perceptually intuitive way.

Mobile Robots: The Evolutionary Approach Nadia Nedjah,2007-03-08 Researchers have obtained robots that display an amazing slew of behaviors and perform a multitude of tasks, including perception of environment, negotiating rough terrain, and pushing boxes. This volume offers a wide spectrum of sample works developed in leading research throughout the world about evolutionary mobile robotics and demonstrates the success of the technique in evolving efficient and capable mobile robots.

Engineering Approaches to Mechanical and Robotic Design for Minimally Invasive Surgery (MIS) Ali Faraz,Shahram Payandeh,2012-12-06 Within the past twenty years, the field of robotics has been finding many areas of applications ranging from space to underwater explorations. One of these areas which is slowly gaining popularity among the users group is the notion of service robotics. This book is an investigation and exploration of engineering principles in the design and development of mechanisms and robotic devices that can be used in the field of surgery. Specifically the results of this book can be used for designing tools for class of Minimally Invasive Surgery (MIS). Generally, Minimal Invasive Surgery (MIS), e. g. laparoscopic surgery, is performed by using long surgical tools, that are inserted through small incisions at the ports of entry to the body (e. g. abdominal wall) for reaching the surgical site. The main drawback of current designs of endoscopic tools is that they are not able to extend all the movements and sensory capabilities of the surgeon's hand to the surgical site. By improving surgical procedures, training, and more practice, it is possible for surgeons to reduce completion time for each task and increase their level of skill. However, even in the best cases the level of performance of a surgeon in Minimally Invasive Surgery is still a fraction of the conventional surgery. Any dramatically improvement is usually driven by introduction of new tools or systems that in turn bring totally new procedures and set of skills.

Design by Composition for Rapid Prototyping Michael Binnard,2012-12-06 At first glance, a book on Design by Composition for Rapid Prototyping may seem out of place in a series on Robotics. However, this work has a couple of strong connections to the field of robotics and the robotics community, and I am delighted to introduce it to the series. The first connection is the motivation behind Binnard's work. Michael Binnard came to Stanford after having done his Masters thesis at the M.LT. Artificial Intelligence Lab, where he designed and built small walking robots, such as Boadicea (<http://www.ai.mit.edu/projects/boadicea/>). At M.LT. he observed first-hand how difficult it is to align, connect and support standard actuators, sensors, and processors in small mobile robots. Figure 1(a) below shows how complicated it is just to connect a simple motor to one link of a robot leg using conventional methods. Surely there had to be a better way! Shape deposition manufacturing, an emerging rapid prototyping process, offered a possible solution. Actuators, sensors, processors and other components could be embedded directly into almost arbitrary three-dimensional shapes, without any of the fasteners and couplings that complicate the design in Figure 1(a). The process makes it possible to construct integrated robotic mechanisms, such as the example shown in Figure 1 (b) and the additional examples found in Chapters 7 and 8 of this monograph.

Distributed Autonomous Robotic Systems 3 Tim Lueth,Rüdiger Dillmann,Paolo Dario,Heinz Wörn,2012-12-06 Distributed autonomous robotic systems (DARS) are systems composed of multiple autonomous units such as modules, cells, processors, agents, and robots. Combination or cooperative operation of multiple autonomous units is expected to lead to desirable features such as flexibility, fault tolerance, and efficiency. The DARS is the leading established conference on distributed autonomous systems. All papers have the common goal to contribute solutions to the very demanding task of designing distributed systems to realize robust and intelligent robotic systems.

Climbing and Walking Robots M. Osman Tokhi,G.S. Virk,2006-01-25 The interest in climbing and walking robots (CLAWAR) has intensified in recent years, and novel solutions for complex and very diverse applications have been anticipated by means of significant progress in this area of robotics. The shift of robotics from manufacturing to services is clearly gaining pace as witnessed by the growth in activities in the CLAWAR area. Moreover, the amalgamation of original ideas and related innovations, search for new potential applications and the use of state of the art support technologies indicate that important steps are likely in the near future and the results could have a significant beneficial socio-economic impact. This book reports on state of the art latest research and development findings and results presented in the CLAWAR 2005 Conference. These are presented in 131 technical articles by authors from 27 countries worldwide. The book is structured into 21 sections, which include some of the traditional topics featured in previous CLAWAR conferences with a set of new topics such as bioengineering, flexible manipulators, personal assistance applications, non-destructive test applications, security and surveillance applications and space applications of robotics. The editors are grateful to colleagues within the committee structure of the CLAWAR 2005 for their help in the review process of the articles and their support throughout this project.

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