

1.	Record Nr.	UNINA990008861920403321
	Autore	Polacco, Vittorio <1859-1926>
	Titolo	Se la surroga ipotecaria legale possa esercitarsi su beni non appartenenti al debitore comune del creditore evincente e dell'evitto : studio
	Pubbl/distr/stampa	Venezia : Fontana, 1886
	Descrizione fisica	32 p. ; in 8°
	Locazione	FGBC
	Collocazione	BUSTA 3 (12)
	Lingua di pubblicazione	Italiano
	Formato	Materiale a stampa
	Livello bibliografico	Monografia
2.	Record Nr.	UNICAMPANIASUN0025803
	Autore	Kuznets, Simon
	Titolo	Popolazione, tecnologia, sviluppo / Simon Kuznets
	Pubbl/distr/stampa	Bologna : Il mulino, 1990
	ISBN	88-15-02854-4
	Descrizione fisica	366 p. ; 22 cm.
	Soggetti	Sviluppo economico
	Lingua di pubblicazione	Italiano
	Formato	Materiale a stampa
	Livello bibliografico	Monografia

3. Record Nr.	UNINA9910438052403321
Autore	Prats Mario
Titolo	Robot physical interaction through the combination of vision, tactile and force feedback : applications to assistive robotics / / Mario Prats, Angel P. del Pobil, and Pedro J. Sanz
Pubbl/distr/stampa	Berlin ; ; Heidelberg, : Springer, c2013
ISBN	9783642332418 3642332412
Edizione	[1st ed. 2013.]
Descrizione fisica	1 online resource (XVIII, 178 p.)
Collana	Springer tracts in advanced robotics, , 1610-7438 ; ; 84
Altri autori (Persone)	PobilAngel Pasqual del SanzPedro J
Disciplina	629.892
Soggetti	Autonomous robots Human-robot interaction
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Bibliographic Level Mode of Issuance: Monograph
Nota di bibliografia	Includes bibliographical references.
Nota di contenuto	Part I -- Part -II -- Part- III.
Sommario/riassunto	Robot manipulation is a great challenge; it encompasses versatility - adaptation to different situations-, autonomy -independent robot operation-, and dependability -for success under modeling or sensing errors. A complete manipulation task involves, first, a suitable grasp or contact configuration, and the subsequent motion required by the task. This monograph presents a unified framework by introducing task-related aspects into the knowledge-based grasp concept, leading to task-oriented grasps. Similarly, grasp-related issues are also considered during the execution of a task, leading to grasp-oriented tasks which is called framework for physical interaction (FPI). The book presents the theoretical framework for the versatile specification of physical interaction tasks, as well as the problem of autonomous planning of these tasks. A further focus is on sensor-based dependable execution combining three different types of sensors: force, vision and tactile. The FPI approach allows to perform a wide range of robot manipulation tasks. All contributions are validated with several experiments using different real robots placed on household environments; for instance, a high-DoF humanoid robot can

successfully operate unmodeled mechanisms with widely varying structure in a general way with natural motions. This research was recipient of the European Georges Giralt Award and the Robotdalen Scientific Award Honorary Mention. .
