1. Record Nr. UNIORUON00219329

Titolo	Coloquio internacional sobre la obra de Jose Lezama Lima : Universadad de Poitiers, Centro de Investigaciones Latino-americanas, 1982 / [Edicion a cargo de Cristina Vizcaino y Eugenio Suarez Galban]
Pubbl/distr/stampa	Madrid, : Editorial Fundamentos, 1984. 2 v. ; 20 cm Vol. 1, : Poesia Vol. 2, : Prosa
ISBN	84-245-0403-8
Disciplina	Cu861
Soggetti	LEZAMA LIMA JOSE
Lingua di pubblicazione	Spagnolo
Formato	Materiale a stampa
Livello bibliografico	Monografia

2. Record Nr. UNINA9910254357003321

Autore	Huang L
Titolo	A Concise Introduction to Mechanics of Rigid Bodies : Multidisciplinary Engineering / / by L. Huang
Pubbl/distr/stampa	Cham : , : Springer International Publishing : , : Imprint : Springer, , 2017
ISBN	3-319-45041-7
Edizione	[2nd ed. 2017.]
Descrizione fisica	1 online resource (XV, 191 p.)
Disciplina	531.3
Soggetti	Mechanics Mechanics, Applied Mechanical engineering Mechatronics Robotics Automation Theoretical and Applied Mechanics Mechanical Engineering Robotics and Automation
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia

Nota di contenuto	Preliminary on vector, matrix, complex number and quaternion -- Orientation and position representation -- Velocity and acceleration -- Dynamics -- Case studies -- References -- Index.
Sommario/riassunto	This updated second edition broadens the explanation of rotational kinematics and dynamics — the most important aspect of rigid body motion in three-dimensional space and a topic of much greater complexity than linear motion. It expands treatment of vector and matrix, and includes quaternion operations to describe and analyze rigid body motion which are found in robot control, trajectory planning, 3D vision system calibration, and hand-eye coordination of robots in assembly work, etc. It features updated treatments of concepts in all chapters and case studies. The textbook retains its comprehensiveness in coverage and compactness in size, which make it easily accessible to the readers from multidisciplinary areas who want to grasp the key concepts of rigid body mechanics which are usually scattered in multiple volumes of traditional textbooks. Theoretical concepts are explained through examples taken from across engineering disciplines and links to applications and more advanced courses (e.g. industrial robotics) are provided. Ideal for students and practitioners, this book provides readers with a clear path to understanding rigid body mechanics and its significance in numerous sub-fields of mechanical engineering and related areas. Streamlines the treatment of rigid body motions in; one-, two, or three-dimensional spaces within an unified mathematical framework supported with vector, matrix, and quaternion operations; Maximizes reader understanding of analysis of rotational kinematics and dynamics; Explains theoretical concepts through examples taken from across engineering disciplines and provides linkages to applications and more advanced courses (e.g. industrial robotics); Features updated treatments of concepts in all chapters and case studies.