

1. Record Nr.	UNISA990003101400203316
Autore	PEZZINI, Barbara
Titolo	Il Bundesrat della Germania federale : il modello tedesco e la riforma del bicameralismo nello Stato a base regionale / Barbara Pezzini
Pubbl/distr/stampa	Milano : A. Giuffrè, 1990
ISBN	88-140-2343-3
Descrizione fisica	XVI, 304 p. ; 24 cm
Collana	Pubblicazioni della Facoltà di giurisprudenza ; 4
Disciplina	342.43042
Soggetti	Livelli di governo - Germania
Collocazione	342.43042 PEZ
Lingua di pubblicazione	Italiano
Formato	Materiale a stampa
Livello bibliografico	Monografia

2. Record Nr.	UNINA9910437911803321
Autore	Carbone Giuseppe
Titolo	Grasping in Robotics // edited by Giuseppe Carbone
Pubbl/distr/stampa	London : , : Springer London : , : Imprint : Springer, , 2013
ISBN	1-283-91132-9 1-4471-4664-6
Edizione	[1st ed. 2013.]
Descrizione fisica	1 online resource (463 p.)
Collana	Mechanisms and Machine Science, , 2211-0992 ; ; 10
Disciplina	629.892
Soggetti	Automatic control Robotics Automation Artificial intelligence Computer simulation Control, Robotics, Automation Artificial Intelligence Control and Systems Theory Computer Modelling
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Description based upon print version of record.
Nota di bibliografia	Includes bibliographical references and index.
Nota di contenuto	Historical Background of Grasping -- A Survey on Different Control Techniques for Grasping -- Path Planning for Grasping Tasks -- Wrists for Enhancing Grasping Performance -- Industrial Grippers: State-of-Art and Main Design Characteristics -- Microgrippers: State-of-Art and Main Design Solutions -- A New Way of Grasping: ParaGrip – Robot and Gripper Rolled Into One -- Robotic Hands: State-of-Art and Low-Cost Design Solutions -- Hardware Control for Robotic Hands -- Finger Orientation for Robotic Hands -- Using Vision in Grasping Tasks -- Integrated Grasp and Motion Planning for Humanoid Robots -- Grasping in Agriculture -- A Multibody Dynamics Formulation.
Sommario/riassunto	Grasping in Robotics contains original contributions in the field of grasping in robotics with a broad multidisciplinary approach. This gives the possibility of addressing all the major issues related to robotized grasping, including milestones in grasping through the centuries,

mechanical design issues, control issues, modelling achievements and issues, formulations and software for simulation purposes, sensors and vision integration, applications in industrial field and non-conventional applications (including service robotics and agriculture). The contributors to this book are experts in their own diverse and wide ranging fields. This multidisciplinary approach can help make Grasping in Robotics of interest to a very wide audience. In particular, it can be a useful reference book for researchers, students and users in the wide field of grasping in robotics from many different disciplines including mechanical design, hardware design, control design, user interfaces, modelling, simulation, sensors and humanoid robotics. It could even be adopted as a reference textbook in specific PhD courses. .
