1. Record Nr. UNINA9910788909103321

Titolo	The call of Abraham : essays on the election of Israel in honor of Jon D. Levenson / / edited by Gary A. Anderson and Joel S. Kaminsky
Pubbl/distr/stampa	Notre Dame, Indiana : , : University of Nore Dame Press, , [2013] ©2013
ISBN	0-268-07476-3
Descrizione fisica	1 online resource (408 p.)
Collana	Christianity and Judaism in antiquity series ; ; volume 19
Altri autori (Persone)	LevensonJon Douglas AndersonGary A. <1955-> KaminskyJoel S. <1960->
Disciplina	221.6
Soggetti	Jews - Election, Doctrine of Election (Theology)
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	part I. The Hebrew Bible -- part II. Reception of the Hebrew Bible -- part III. Theological essays.

2. Record Nr. UNINA9910482975103321

Autore	Li Qinchuan
Titolo	Geometric Method for Type Synthesis of Parallel Manipulators / / by Qinchuan Li, Jacques M. Hervé, Wei Ye
Pubbl/distr/stampa	Singapore : , : Springer Nature Singapore : , : Imprint : Springer, , 2020
ISBN	981-13-8755-9
Edizione	[1st ed. 2020.]
Descrizione fisica	1 online resource (XIII, 238 p. 135 illus., 61 illus. in color.)
Collana	Springer Tracts in Mechanical Engineering, , 2195-9870
Disciplina	629.8
Soggetti	Control engineering Robotics Automation Mechanics, Applied Mathematics Control, Robotics, Automation Engineering Mechanics Applications of Mathematics
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Nota di contenuto	Introduction -- Fundamentals of group theory -- Rotation and displacements of rigid body -- Lie group based method for type synthesis of parallel mechanisms -- Type Synthesis of 5-DOF 3R2T Parallel Mechanisms -- Type Synthesis of 4-DOF 2R2T Parallel Mechanisms -- Type Synthesis of 4-DOF Parallel Mechanisms with Bifurcation of Schoenflies Motion -- Type Synthesis of 3-DOF RPR-equivalent Parallel Mechanisms -- Type Synthesis of 3-DOF PU-equivalent Parallel Mechanisms -- Type Synthesis of a Special Family of Remote Center-of-Motion Parallel Manipulators with Fixed Linear Actuators for Minimally Invasive Surgery -- Type synthesis of Non-overconstrainted 3-DOF Translational parallel mechanisms with Less Structural Shakiness -- Type synthesis of Pan-Tilt Wrists with Uncoupled Actuation.
Sommario/riassunto	This book focuses on the synthesis of lower-mobility parallel manipulators, presenting a group-theory-based method that has the advantage of being geometrically intrinsic. Rotations and translations

of a rigid body as well as a combination of the two can be expressed and handled elegantly using the group algebraic structure of the set of rigid-body displacements. The book gathers the authors' research results, which were previously scattered in various journals and conference proceedings, presenting them in a unified form. Using the presented method, it reveals numerous novel architectures of lower-mobility parallel manipulators, which are of interest to those in the robotics community. More importantly, readers can use the method and tool to develop new types of lower-mobility parallel manipulators independently.