1. Record Nr. UNINA9910701294803321

Titolo	Failure to verify the continuity of shunt trip contact attachments in manual safety injection and reactor trip switches [[electronic resource]]
Pubbl/distr/stampa	Washington, D.C. : , : U.S. Nuclear Regulatory Commission, Office of Nuclear Material Safety and Safeguards, , [1993]
Descrizione fisica	1 online resource
Collana	NRC information notice ; ; 93-15
Soggetti	Nuclear power plants - Safety measures
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
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Titolo	Intelligent Robotics and Applications : 14th International Conference, ICIRA 2021, Yantai, China, October 22–25, 2021, Proceedings, Part IV / / edited by Xin-Jun Liu, Zhenguo Nie, Jingjun Yu, Fugui Xie, Rui Song
Pubbl/distr/stampa	Cham : , : Springer International Publishing : , : Imprint : Springer, , 2021
ISBN	3-030-89092-9
Edizione	[1st ed. 2021.]
Descrizione fisica	1 online resource (780 pages)
Collana	Lecture Notes in Artificial Intelligence, , 2945-9141 ; ; 13016
Disciplina	006.3
Soggetti	Artificial intelligence Computer engineering Computer networks Computer vision Numerical analysis Artificial Intelligence Computer Engineering and Networks Computer Vision Numerical Analysis

Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Nota di contenuto	Intro -- Preface -- Organization -- Contents - Part IV -- Novel Mechanisms, Robots and Applications -- Optimal Design of Cam Curve Dedicated to Improving Load Uniformity of Bidirectional Antagonistic VSA -- 1 Introduction -- 2 Overall Structural Design -- 3 Stiffness Adjustment Principle and Nonlinear Compensation -- 3.1 Stiffness Adjustment Principle and Nonlinear Analysis -- 3.2 Stiffness Nonlinear Compensation -- 4 Optimization Design of Cam Drive Profile -- 4.1 Constraint Analysis of Cam Curve Design Parameters -- 4.2 Cam Curve Design Optimization and Result Analysis -- 5 Conclusion -- References -- Research on Foot Slippage Estimation of Mammal Type Legged Robot -- 1 Introduction -- 2 Foot Terrain Interaction for Slippage -- 3 Data Fusion Method Based on EKF -- 3.1 Calibration for Sensor Data -- 3.2 State Estimation by Data Fusion -- 4 Slippage Estimation and State Determination -- 4.1 Acceleration Model of Foot Slippage for Mammal Type Walking -- 4.2 Foot Slippage State Analysis Based on EKF -- 5 Experimental Verification -- 6 Conclusion -- References -- Design of Deformable Flapping Structure of Bat-Like Flapping Air Vehicle -- 1 Introduction -- 2 Structural Design -- 2.1 Flapping Mechanism -- 2.2 Deformable Mechanism -- 2.3 Coupling Design Mechanism -- 3 Simulation -- 4 Conclusion -- References -- An Autonomous Flight Control Strategy Based on Human-Skill Imitation for Flapping-Wing Aerial Vehicle -- 1 Introduction -- 2 Control Strategy -- 2.1 Manual Control -- 2.2 Human-Skill Imitation -- 3 Experiment -- 3.1 Takeoff -- 3.2 Cruise -- 3.3 Landing -- 4 Conclusions -- References -- A New Moving Target Interception Algorithm for an AUV in the Ocean Current Environment -- 1 Introduction -- 2 The Basic Model for an AUV Intercepting Moving Target -- 2.1 The Overview of Interception Problem -- 2.2 A Model of the Underwater Environment. 3 The Proposed APF-VS-KF Algorithm -- 3.1 Planning Intercept Path of the AUV -- 3.2 Update Moving Position of Target Based on KF -- 4 Simulation Results and Analysis -- 4.1 The AUV Intercepts a Target Moving Along a Constant Straight Line in a 2-D Environment with Ocean Vurrent of 90 -- 4.2 The AUV Intercepts a Target Moving Along a Constant Straight Line in a 2-D Environment with Ocean Current of 180 -- 5 Conclusion -- References -- Design and Control of In-Pipe Inspection Robot forPre-commissioning -- 1 Introduction -- 2 Kinematic Properties of HL-6 Robot in Pipes -- 2.1 Overview of the LH-6 Robotic System -- 2.2 Kinematics of HL-6 Robot in Pipes -- 3 Dynamical Model of HL-6 Robot in Pipes -- 4 Control of HL-6 Robot Based on Kinetic Model -- 4.1 Control of CoM's Position and Trunk's Orientation -- 4.2 Computation of the Desired Supporting Force -- 4.3 Details of Control -- 5 Experiments -- 6 Conclusions -- References -- Research on Technology of Pipeline Detection Robot Based on Spiral Propulsion -- 1 Introduction -- 2 Pipeline Robot Design -- 2.1 Structure Composition of Pipeline Robot -- 2.2 Robot Travel Method -- 3 Robot Control System -- 4 Pipeline Inner Wall Scanning Detection Strategy -- 4.1 Point Cloud Data Acquisition -- 4.2 Poisson Surface Reconstruction -- 4.3 Pipe Roundness Detection -- 5 Experimental Verification -- 5.1 Robot Pipeline Travel Test -- 5.2 Point Cloud Surface Reconstruction -- 6 Conclusion -- References -- Dynamic Characteristics of Two-Mass Inertial Pipeline Robot Driven

by Noncircular Gears -- 1 Introduction -- 2 Mechanism Principle of Two-Mass Inertial Pipeline Robot -- 3 Dynamic Modeling of Two-Mass Inertial Pipeline Robot -- 3.1 Transmission Ratio of Non-circular Gear -- 3.2 Dynamic Equation -- 4 Simulation Results and Discussion -- 4.1 System Parameters and Motion Characteristics.
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2.2 Deduction of Delta Robot as Limb.

Sommario/riassunto

The 4-volume set LNAI 13013 – 13016 constitutes the proceedings of the 14th International Conference on Intelligent Robotics and Applications, ICIRA 2021, which took place in Yantai, China, during October 22-25, 2021. The 299 papers included in these proceedings were carefully reviewed and selected from 386 submissions. They were organized in topical sections as follows: Robotics dexterous manipulation; sensors, actuators, and controllers for soft and hybrid robots; cable-driven parallel robot; human-centered wearable robotics; hybrid system modeling and human-machine interface; robot manipulation skills learning; micro_nano materials, devices, and systems for biomedical applications; actuating, sensing, control, and instrumentation for ultra-precision engineering; human-robot collaboration; robotic machining; medical robot; machine intelligence for human motion analytics; human-robot interaction for service robots; novel mechanisms, robots and applications; space robot and on-orbit service; neural learning enhanced motion planning and control for human robot interaction; medical engineering.