1. Record Nr. UNISALENTO991003420789707536

Titolo	Proprietà e controllo delle imprese in Italia : alle radici delle difficoltà competitive della nostra industria / Marcello Bianchi... [et al.]
Pubbl/distr/stampa	Bologna : Il mulino, 2005
ISBN	8815106022
Descrizione fisica	216 p. ; 21 cm
Collana	Studi e ricerche , 543
Altri autori (Persone)	Bianchi, Marcello
Disciplina	338.6
Soggetti	Imprese - Competitività - Italia
Lingua di pubblicazione	Italiano
Formato	Materiale a stampa
Livello bibliografico	Monografia

2. Record Nr. UNISALENTO991003426689707536

Autore	Thiry, Marcel
Titolo	Attouchements des sonnets de Shakespeare : précédés d'un argument / Marcel Thiry
Pubbl/distr/stampa	Bruxelles : A. De Rache, c1970
Descrizione fisica	51 p. ; 25 cm
Disciplina	822.33
Soggetti	Shakespeare, William Sonetti Shakespeare, William Sonetti
Lingua di pubblicazione	Francese
Formato	Materiale a stampa
Livello bibliografico	Monografia

3. Record Nr. UNINA9910716294003321

Titolo	Frank K. Logan and Dr. F.B. Cogswell. Communication from the President of the United States, transmitting two communications from the Comptroller General of the United States submitting estimates of appropriations in the sum of $ 78.85, to pay claims for damages or losses of privately owned property. April 8, 1926. -- Referred to the Committee on Appropriations and ordered to be printed [[electronic resource]]
Pubbl/distr/stampa	[Washington, D.C.] : , : [U.S. Government Printing Office], , 1926
Descrizione fisica	1 online resource (2 pages)
Collana	House document / 69th Congress, 1st session. House ; ; no. 296 [United States congressional serial set] ; ; [serial no. 8579]
Altri autori (Persone)	CoolidgeCalvin <1872-1933.>
Soggetti	Automobiles Claims Malicious mischief Vandalism Traffic accidents Legislative materials.
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Note generali	Batch processed record: Metadata reviewed, not verified. Some fields updated by batch processes. FDLP item number not assigned.

4. Record Nr. UNINA9910743352703321

Autore	Phan Gia Hoang
Titolo	Bio-inspired Motor Control Strategies for Redundant and Flexible Manipulator with Application to Tooling Tasks / / by Gia Hoang Phan, Vijender Kumar Solanki, Nguyen Ho Quang
Pubbl/distr/stampa	Singapore : , : Springer Nature Singapore : , : Imprint : Springer, , 2022
ISBN	981-16-9550-4 981-16-9551-2
Edizione	[1st ed. 2022.]
Descrizione fisica	1 online resource (x, 91 pages) : illustrations (some color)
Collana	SpringerBriefs in Computational Intelligence, , 2625-3712
Disciplina	610.285
Soggetti	Automatic control Robotics Automation Computational intelligence Control, Robotics, Automation Computational Intelligence Robotic Engineering
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Nota di contenuto	Chapter 1. Bio – inspired Motor Control Strategies for Redundant Manipulators -- Chapter 2. Bio – inspired Motor Control Strategies: Cable – driven Manipulator using Agonist – Antagonis actuation -- Chapter 3. Design and Control of 2D-Plotter Planar Parallel Robot -- Chapter 4. Combining 3D motion tracker with IMU sensor signals of muscles to discover macro- and micro-vibration for Stroke Rehabilitation -- Chapter 5. A Pneumatic Actuator-Powered Robotic Glove for Hand Rehabilitation -- Chapter 6. Artificial Intelligence in Rehabilitation Evaluation Based Robotic Exoskeletons: A Review.
Sommario/riassunto	This book presents a multi-disciplinary view of all aspects of rehabilitation robotics and non-invasive surgery, ideal for anyone new to the field. It includes perspectives from both engineers and clinicians. For skilled researchers and clinicians, it also summarizes current robot technologies and their application to various pathologies. The book will help the readers to develop the know-how and expertise necessary to

guide those seeking a comprehensive understanding of this topic through their use of several commercial devices for robotic rehabilitation. The book targets the implementation of efficient robot strategies to facilitate the re-acquisition of motor skills. This technology incorporates the outcomes of behavioral studies on motor learning and its neural correlates into the design, implementation, and validation of robot agents that behave as optimal trainers, efficiently exploiting the structure and plasticity of the human sensorimotor systems.