

1. Record Nr.	UNINA9910895861403321
Titolo	Technical bulletin
Pubbl/distr/stampa	Ottawa : , : Canadian Conservation Institute, National Museums of Canada, , 1975- Ottawa : , : Canadian Conservation Institute, Department of Canadian Heritage
Descrizione fisica	1 online resource
Soggetti	Museum buildings Museum techniques Museum conservation methods Musées - Méthodes de conservation - Canada - Collections Musées (Édifices) Muséologie Musées - Méthodes de conservation museums (buildings) museology Periodicals. periodicals. Périodiques.
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Periodico

2. Record Nr.	UNINA9910483997103321
Autore	Olgún Díaz Ernesto
Titolo	3D Motion of Rigid Bodies : A Foundation for Robot Dynamics Analysis // by Ernesto Olgún Díaz
Pubbl/distr/stampa	Cham : , : Springer International Publishing : , : Imprint : Springer, , 2019
ISBN	3-030-04275-8
Edizione	[1st ed. 2019.]
Descrizione fisica	1 online resource (488 pages)
Collana	Studies in Systems, Decision and Control, , 2198-4182 ; ; 191
Disciplina	629.892
Soggetti	Computational intelligence Robotics Automation Vibration Dynamics Automatic control Computational Intelligence Robotics and Automation Vibration, Dynamical Systems, Control Control and Systems Theory
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Nota di contenuto	Mathematic Foundations -- Classical Mechanics -- Rigid Motion -- Attitude Representations -- Dynamics of a Rigid Body -- Spacial Vectors Approach -- Lagrangian Formulation -- Model reduction under motion constraint.
Sommario/riassunto	This book offers an excellent complementary text for an advanced course on the modelling and dynamic analysis of multi-body mechanical systems, and provides readers an in-depth understanding of the modelling and control of robots. While the Lagrangian formulation is well suited to multi-body systems, its physical meaning becomes paradoxically complicated for single rigid bodies. Yet the most advanced numerical methods rely on the physics of these single rigid bodies, whose dynamic is then given among multiple formulations

by the set of the Newton–Euler equations in any of their multiple expression forms. This book presents a range of simple tools to express in succinct form the dynamic equation for the motion of a single rigid body, either free motion (6-dimension), such as that of any free space navigation robot or constrained motion (less than 6-dimension), such as that of ground or surface vehicles. In the process, the book also explains the equivalences of (and differences between) the different formulations.
