

1. Record Nr.	UNINA9910785508503321
Autore	Brown Harold <1927-2019>
Titolo	Star spangled security : applying lessons learned over six decades safeguarding America / / Harold Brown. with Joyce Winslow
Pubbl/distr/stampa	Washington, D.C., : Brookings Institution Press, c2012
ISBN	1-283-61332-8 9786613925770 0-8157-2383-0
Descrizione fisica	1 online resource (xviii, 277 pages, 8 unnumbered pages of plates) : illustrations
Altri autori (Persone)	WinslowJoyce
Disciplina	355/.033573
Soggetti	Cabinet officers - United States National security - United States - Decision making National security - United States - History United States Military policy Decision making Case studies United States Military policy Planning
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	Prologue -- Oh, say can you see : the view from the top -- What so proudly we hail : insuring national defense through its budget -- Stripes and bright stars : how the team at the top affects security policy -- The perilous fight : Iranian revolution and the hostage crisis -- Rockets' red glare and bombs : plans, programs, and agreements -- The ramparts we watched : dealing with the outside world -- That banner yet waves : preparing for what lies ahead -- Land of the free : stimulating the national economy for international security -- Home of the brave : America at a tipping point.
Sommario/riassunto	Harold Brown served as U.S. secretary of defense when the Soviet Union posed an existential threat with superior conventional force capability and a daunting nuclear weapons arsenal. No one could have been better suited to deter the Soviets during that most dangerous period in the Cold War. A physicist, Brown had previously led Livermore Laboratory and its development of the Polaris missile warhead. By age 33 he was director of Defense Research and Engineering, and he later

2. Record Nr.	UNINA9910999785803321
Autore	Cardona Manuel
Titolo	Rehabilitation Robotics : Kinematics, Dynamics, and Control Techniques / / by Manuel Cardona, Fernando E. Serrano
Pubbl/distr/stampa	Cham : , : Springer Nature Switzerland : , : Imprint : Springer, , 2025
ISBN	3-031-83655-3
Edizione	[1st ed. 2025.]
Descrizione fisica	1 online resource (VIII, 184 p. 126 illus.)
Disciplina	610.28
Soggetti	Biomedical engineering Robotics Biomechanics Human-machine systems Biomedical Engineering and Bioengineering Robotic Engineering Biomechanical Analysis and Modeling Biomedical Devices and Instrumentation Human-Machine Interfaces
Lingua di pubblicazione	Inglese
Formato	Materiale a stampa
Livello bibliografico	Monografia
Nota di contenuto	Introduction -- Fundamentals of Exoskeleton Robots for Rehabilitation -- Mathematical Tools for Exoskeleton Robots.-Kinematics Analysis of Exoskeleton Robots -- Geometrical Approach -- Denavit & Hartenberg Method -- Successive Screw Method -- Dynamics Analysis of Exoskeleton Robots -- Newton-Euler Formulation -- Lagrange-Euler Approach -- Dalembert General Formulation -- Dynamic Solution Based on Dynamic Simulation.-Control Techniques for Exoskeleton Robots -- Robust Control Strategies -- Robust Control Lyapunov Functions -- Impedance Control -- Adaptive Control -- Uncertainties Found in Dynamic Systems.
Sommario/riassunto	Rehabilitation robotics is an important field of study focused on

improving the gait rehabilitation of people affected by neurological disorders, ictus, cerebral palsy, and spinal cord injuries, among others. The study of rehabilitation robotics includes medical activities, kinematics dynamics, and control analysis. This book presents a complete and exhaustive analysis of the kinematics and dynamics of exoskeleton robots for rehabilitation. The forward and inverse kinematics are studied using the geometric, Denavit-Hartenberg, and screw theory approach. The dynamics analysis of exoskeleton robots using Newton-Euler, Euler-Lagrange, and D'Alembert formulation are also studied. Moreover, the main control techniques for exoskeleton robots are analyzed, including robust control, impedance control, adaptive control, Lyapunov functions, and uncertainties found in dynamic systems. The book includes MATLAB applications and examples. Includes MATLAB applications and examples; Presents state of the art of exoskeleton robots for rehabilitation; Covers fundamental rehabilitation concepts.
