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Nota di contenuto	Preface -- Theoretical kinematics: Kinematical Capabilities of an Inversion of the Double Linked Fourbar for UAV Morphing Wing Actuation, by J. Aguirrebeitia, R. Avilés, I. Fernandez de Bustos and M. Abasolo -- Kinematic waves in linear statically determinate adjustable structures, by V. Bujakas -- Perturbation of symmetric 3-RPR manipulators and asymptotic singularities, by M. Coste, D. Chablat and P. Wenger -- Workspace and Singularities Analysis of a 6- DOF Parallel Mechanism with two Kinematic Chains for Platform Guidance, by R. Dadarlat, N. Plitea, B. Konya, C. Vaida and D. Pisla -- The kinematics of a new reconfigurable parallel robot with six degrees of freedom, by B. Konya, N. Plitea, R. Dadarlat, C. Vaida and D. Pisla -- A restoring stress doesn't always exist, by M. Kovalev -- Mobility Analysis of Non Series-Parallel Mechanisms, by P. Lambert and J. Herder -- Multiple-Mode Closed 7-Link Chains Based on Overconstrained 4-Link Mechanisms, by M. Pfurner -- Computational kinematics: Confirmation of Hypothesis on Cable Properties for Cable-driven Robots, by J. Alexandre dit Sandretto, G. Trombettoni and D. Daney -- Analytical Determination of the Instantaneous Motion Capabilities of Robotic Manipulators, by O. Altuzarra, O. Salgado, A. Hernández and C. Pinto -- Computation of the Protein Molecular Mechanism Using Adaptive Dihedral Angle Increments, by M. Diez, V. Petuya, M. Urizar, E. Macho and O. Altuzarra -- Handling with inequality constraints in a general method of optimal kinematic synthesis, by P. García, A. de-Juan, R. Sancibrián, A. Fernández, M. Iglesias and F. Viadero -- Self-Motions of 3-RPS Manipulators, by M. Husty, J. Schadlbauer, S. Caro and P. Wenger -- Scenario-based dimensioning of the actuator of parallel cable-driven robots, by W. Kraus and A. Pott -- Position problem in Assur's groups with revolute pairs, by A. Noriega, M. Cadenas and R. Fernández -- Workspace and Singularity Analysis for a parallel robot used in surgicalapplications, by A. Stoica, D. Pisla , A. Szilaghyi, B. Gherman and N. Plitea -- Workspace Identification using Neural Network for an Optimal Designed 2-DOF Orientation Parallel Device, by I. Tanase, T. Itul, E. Campean and A. Pisla -- Mechanism design: Design Methodology for a Compliant Binary Actuated Parallel Mechanism with Flexure Hinges, by G. Borchert, C. Löchte, S. Brumme, G. Carbone, M. Ceccarelli and A. Raatz -- Optimal design of motorcycle rear suspension systems using genetic algorithms, by J. J. Castillo, P. Giner, A. Simón and J. A. Cabrera -- Influence of the contact stiffness between the cam and the roller in the dynamic behaviour of the train follower applied in a conjugate cam mechanism, by P. Català, S. Cardona, M. A. De los Santos and J. M. Veciana -- 3-DOF Translational and Rotational Parallel Manipulators, by V. Glazunov, P. Laryushkin and S. Kheylo -- Engineering aspects in solving guidance tasks with geared linkages, by U. Hanke, K. Modler, A. Schmidtpott and S. Lin -- Motor positioning and drive train design for a 3-DOF robotic structure, by S. Kurtenbach, T. Detert, M. Riedel, M. Hüsing and B. Corves -- Interactive design of opening and closing mechanisms for skylight domes, by G. Lonij, S.

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Sommario/riassunto

This book contains the papers of the European Conference on Mechanisms Science (EUCOMES 2012 Conference). The book presents the most recent research developments in the mechanism and machine science field and their applications. Topics addressed are theoretical kinematics, computational kinematics, mechanism design, experimental mechanics, mechanics of robots, dynamics of machinery, dynamics of multi-body systems, control issues of mechanical systems, mechanisms for biomechanics, novel designs, mechanical transmissions, linkages and manipulators, micro-mechanisms, teaching methods, history of mechanism science and industrial and non-industrial applications. This volume will also serve as an interesting reference for European activity in the fields of Mechanism and Machine Science as well as a source of inspiration for future works and developments.