1. Record Nr. UNISA996279417003316

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| Titolo | IEEE Std 529-1980 : supplement for strapdown applications to IEEE standard specification format guide and test procedure for single-degree-of-freedom rate-integrating gyros / / IEEE |
| Pubbl/distr/stampa | [Place of publication not identified] : , : IEEE, , 1981 |
| ISBN | 0-7381-0547-3 |
| Descrizione fisica | 1 online resource |
| Disciplina | 629.454 |
| Soggetti | Space vehicles - Testing<br>Aerospace engineering |
| Lingua di pubblicazione | Inglese |
| Formato | Materiale a stampa |
| Livello bibliografico | Monografia |
| Sommario/riassunto | A specification format guide for the preparation of a rate-integrating gyroscope specification is presented. Recommended procedures for testing a rate-integrating gyroscope are compiled. This standard, when combined with IEEE Std 517-1974 (R1980), defines the requirements and test procedures in terms of characteristics unique to the gyroscope or those applications in which the dynamic angular inputs are significantly greater than the limitations identified in IEEE Std 517. |

2. Record Nr. UNINA9911046545903321

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| Autore | Qi Chenkun |
| Titolo | Control of Hardware-In-The-Loop Space Contact Simulation Robot / / by Chenkun Qi, Feng Gao, Yan Hu |
| Pubbl/distr/stampa | Singapore : , : Springer Nature Singapore : , : Imprint : Springer, , 2026 |
| ISBN | 981-9511-72-0 |
| Edizione | [1st ed. 2026.] |
| Descrizione fisica | 1 online resource (164 pages) |
| Collana | Intelligent Technologies and Robotics Series |
| Altri autori (Persone) | GaoFeng<br>HuYan |
| Disciplina | 629.8 |
| Soggetti | Automatic control<br>Robotics<br>Automation<br>Computational intelligence<br>Control, Robotics, Automation<br>Computational Intelligence |
| Lingua di pubblicazione | Inglese |
| Formato | Materiale a stampa |
| Livello bibliografico | Monografia |
| Nota di contenuto | Introduction -- Robot System for Hardware in the loop Simulation of Space Contact Dynamics -- Modeling and Distortion Analysis of Hybrid Simulation System -- Compensation of Force Measurement Delay -- Compensation of Robot Dynamic Response Delay -- Compensation of Robot Structure Dynamics -- Compensation of Upper Platform Structure Dynamics -- Lumped Distortion Compensation Control -- Distributed Distortion Compensation Control -- Learning based Distortion Compensation Control. |
| Sommario/riassunto | The book focuses on control methods of hardware-in-the-loop simulation robots on the ground to simulate the contact dynamics of spacecraft and space manipulators in space. Both principles and engineering practice have been addressed. This is achieved by providing an in-depth study of several major topics such as control system structure and modeling, simulation distortion analysis, distortion compensation control methods, simulation and experimental verification, and applications. The comprehensive and systematic treatment of practical issues in the control of hardware-in-the-loop |

space contact simulation robots is one of the main features of the book, which is particularly suitable for readers who are interested in learning practical solutions in the control of hardware-in-the-loop space contact simulation robots. The book can benefit researchers, engineers, and graduate students in the fields of aerospace engineering, mechanical engineering, and control engineering, etc.