

عنوان مقاله:

Pre- design trajectory of humanoid robot motion

محل انتشار:

هفدهمین کنفرانس سالانه مهندسی مکانیک (سال: 1388)

تعداد صفحات اصل مقاله: 6

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خلاصه مقاله:

One of the major problems of humanoid robots monvement is holding in balance which the major property would be the drift of robot. In this paper we have assumed a humanoid robot with 12 degrees of freedom and we have made the geomtrical parameters between links and so with help of a human pattern and intelligent algorithm the proper .movement has been defined which the equations has less complication and gives more optimized answers

کلمات کلیدی:

humanoid robot, balance, pre-design, kinematics - kinetic parameters

لینک ثابت مقاله در پایگاه سیویلیکا:

<https://civilica.com/doc/90566>

