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Intended as an introduction to robot mechanics for students of mechanical, industrial, electrical, and bio-mechanical engineering, this graduate text presents a wide range of approaches and topics. It avoids formalism and proofs but nonetheless discusses advanced concepts and contemporary applications. It will thus also be of interest to practicing engineers. The book begins with kinematics, emphasizing an approach based on rigid-body displacements instead of coordinate transformations; it then turns to inverse kinematic analysis, presenting the widely used Pieper-Roth and zero-reference-position methods. This is followed by a discussion of workplace characterization and determination. One focus of the discussion is the motion made possible by spherical and other novel wrist designs. The text concludes with a brief discussion of dynamics and control. An extensive bibliography provides access to the current literature.

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Engineering Mechanics is written in a style that is concise and authoritative which has been thoroughly tested and proven for organization of topics and presentation of theory geared to student understanding. The major emphasis is on basic principles and problem formulation rather than on a multitude of special cases. The authors have received widespread acclaim from students and instructors for their attention to detail and remarkably error-free treatment.