

Methods in Kinematics

P. Fanghella and C. Galletti

Using body flexibility to simplify the solution of kinematic equations in the dynamic analysis of robot mechanisms and multibody systems

M. Hofer, H. Pottmann, and B. Ravani

Subdivision algorithms for motion design based on homologous points

J.M. Rico and B. Ravani

Group theory can explain the mobility of paradoxical linkages

J.M. Porta, L. Ros, F. Thomas, and C. Torras

Solving multi-loop linkages by iterating 2D clippings

N. Andreff and B. Espiau

Revisiting Plücker coordinates in vision-based control

I.A. Parkin and J.E. Baker

On displacing a screw about a screw

W. Korb, W. Schlegel, J.P. Schlöder, and H.G. Bock

Algebraic solution of inverse kinematics revisited

I. Zabalza, J. Ros, J.J. Gil, J.M. Pintor, and J.M. Jiménez

A variant of a 6-RKS hunt-type parallel manipulator to easily use insensitivity position configurations