

Contents

List of Abbreviations LXIII

1 Robotics and the Handbook

<i>Bruno Siciliano, Oussama Khatib</i>	1
1.1 A Brief History of Robotics	1
1.2 The Robotics Community	3
1.3 This Handbook	4
Video-References	5

Part A Robotics Foundations

2 Kinematics

<i>Kenneth J. Waldron, James Schmiedeler</i>	11
2.1 Overview	12
2.2 Position and Orientation Representation	12
2.3 Joint Kinematics	21
2.4 Geometric Representation	25
2.5 Workspace	27
2.6 Forward Kinematics	28
2.7 Inverse Kinematics	29
2.8 Forward Instantaneous Kinematics	31
2.9 Inverse Instantaneous Kinematics	32
2.10 Static Wrench Transmission	33
2.11 Conclusions and Further Reading	33
References	33

3 Dynamics

<i>Roy Featherstone, David E. Orin</i>	37
3.1 Overview	38
3.2 Spatial Vector Notation	39
3.3 Canonical Equations	45
3.4 Dynamic Models of Rigid-Body Systems	47
3.5 Kinematic Trees	51
3.6 Kinematic Loops	58
3.7 Conclusions and Further Reading	61
References	63

4 Mechanism and Actuation

<i>Victor Scheinman, J. Michael McCarthy, Jae-Bok Song</i>	67
4.1 Overview	68
4.2 System Features	68
4.3 Kinematics and Kinetics	69
4.4 Serial Robots	72
4.5 Parallel Robots	73
4.6 Mechanical Structure	75
4.7 Joint Mechanisms	76

4.8	Actuators	78
4.9	Robot Performance	85
4.10	Conclusions and Further Reading	87
	Video-References	87
	References	87
5	Sensing and Estimation	
	<i>Henrik I. Christensen, Gregory D. Hager</i>	91
5.1	Introduction	91
5.2	The Perception Process	92
5.3	Sensors	94
5.4	Estimation Processes	98
5.5	Representations	109
5.6	Conclusions and Further Readings	111
	References	111
6	Model Identification	
	<i>John Hollerbach, Wisama Khalil, Maxime Gautier</i>	113
6.1	Overview	113
6.2	Kinematic Calibration	115
6.3	Inertial Parameter Estimation	122
6.4	Identifiability and Numerical Conditioning	127
6.5	Conclusions and Further Reading	135
	Video-References	136
	References	137
7	Motion Planning	
	<i>Lydia E. Kavraki, Steven M. LaValle</i>	139
7.1	Robotics Motion Planning	139
7.2	Motion Planning Concepts	140
7.3	Sampling-Based Planning	141
7.4	Alternative Approaches	144
7.5	Differential Constraints	148
7.6	Extensions and Variations	151
7.7	Advanced Issues	154
7.8	Conclusions and Further Reading	157
	Video-References	158
	References	158
8	Motion Control	
	<i>Wan Kyun Chung, Li-Chen Fu, Torsten Kröger</i>	163
8.1	Introduction to Motion Control	164
8.2	Joint Space Versus Operational Space Control	166
8.3	Independent-Joint Control	167
8.4	PID Control	169
8.5	Tracking Control	172
8.6	Computed-Torque Control	174
8.7	Adaptive Control	177
8.8	Optimal and Robust Control	181
8.9	Trajectory Generation and Planning	183
8.10	Digital Implementation	187

8.11 Learning Control	190
Video-References	191
References	191
9 Force Control	
<i>Luigi Villani, Joris De Schutter</i>	195
9.1 Background	195
9.2 Indirect Force Control	198
9.3 Interaction Tasks.....	205
9.4 Hybrid Force/Motion Control.....	211
9.5 Conclusions and Further Reading.....	216
Video-References	217
References	218
10 Redundant Robots	
<i>Stefano Chiaverini, Giuseppe Oriolo, Anthony A. Maciejewski</i>	221
10.1 Overview	221
10.2 Task-Oriented Kinematics	224
10.3 Inverse Differential Kinematics.....	227
10.4 Redundancy Resolution via Optimization	232
10.5 Redundancy Resolution via Task Augmentation	233
10.6 Second-Order Redundancy Resolution	236
10.7 Cyclicity.....	237
10.8 Fault Tolerance	237
10.9 Conclusion and Further Reading	239
Video-References	239
References	240
11 Robots with Flexible Elements	
<i>Alessandro De Luca, Wayne J. Book</i>	243
11.1 Robots with Flexible Joints	244
11.2 Robots with Flexible Links.....	263
Video-References	279
References	279
12 Robotic Systems Architectures and Programming	
<i>David Kortenkamp, Reid Simmons, Davide Brugali</i>	283
12.1 Overview	283
12.2 History.....	285
12.3 Architectural Components	289
12.4 Case Study – GRACE.....	296
12.5 The Art of Robot Architectures.....	298
12.6 Implementing Robotic Systems Architectures	299
12.7 Conclusions and Further Reading.....	302
Video-References	302
References	302
13 Behavior-Based Systems	
<i>François Michaud, Monica Nicolescu</i>	307
13.1 Robot Control Approaches	308
13.2 Basic Principles of Behavior-Based Systems	310

13.3 Basis Behaviors	313
13.4 Representation in Behavior-Based Systems	313
13.5 Learning in Behavior-Based Systems	314
13.6 Applications and Continuing Work	318
13.7 Conclusions and Further Reading	322
Video-References	322
References	323
 14 AI Reasoning Methods for Robotics	
<i>Michael Beetz, Raja Chatila, Joachim Hertzberg, Federico Pecora</i>	329
14.1 Why Should a Robot Use AI-Type Reasoning?	330
14.2 Knowledge Representation and Processing	330
14.3 Reasoning and Decision Making	338
14.4 Plan-Based Robot Control	346
14.5 Conclusions and Further Reading	351
Video-References	351
References	352
 15 Robot Learning	
<i>Jan Peters, Daniel D. Lee, Jens Kober, Duy Nguyen-Tuong, J. Andrew Bagnell, Stefan Schaal</i>	357
15.1 What Is Robot Learning	358
15.2 Model Learning	360
15.3 Reinforcement Learning	372
15.4 Conclusions	385
Video-References	386
References	386
 Part B Design	
 16 Design and Performance Evaluation	
<i>Jorge Angeles, Frank C. Park</i>	399
16.1 The Robot Design Process	400
16.2 Workspace Criteria	401
16.3 Dexterity Indices	405
16.4 Other Performance Indices	408
16.5 Other Robot Types	411
16.6 Summary	416
References	416
 17 Limbed Systems	
<i>Shuuji Kajita, Christian Ott</i>	419
17.1 Design of Limbed Systems	420
17.2 Conceptual Design	420
17.3 Whole Design Process Example	423
17.4 Model Induced Design	427
17.5 Various Limbed Systems	434
17.6 Performance Indices	437
Video-References	439
References	440

18 Parallel Mechanisms	
<i>Jean-Pierre Merlet, Clément Gosselin, Tian Huang</i>	443
18.1 Definitions	443
18.2 Type Synthesis of Parallel Mechanisms	445
18.3 Kinematics	446
18.4 Velocity and Accuracy Analysis	447
18.5 Singularity Analysis	448
18.6 Workspace Analysis	450
18.7 Static Analysis	451
18.8 Dynamic Analysis	452
18.9 Design	452
18.10 Wire-Driven Parallel Robots	453
18.11 Application Examples	455
18.12 Conclusion and Further Reading	455
Video-References	456
References	456
19 Robot Hands	
<i>Claudio Melchiorri, Makoto Kaneko</i>	463
19.1 Basic Concepts	464
19.2 Design of Robot Hands	465
19.3 Technologies for Actuation and Sensing	470
19.4 Modeling and Control of a Robot Hand	473
19.5 Applications and Trends	477
19.6 Conclusions and Further Reading	478
Video-References	478
References	479
20 Snake-Like and Continuum Robots	
<i>Ian D. Walker, Howie Choset, Gregory S. Chirikjian</i>	481
20.1 Snake Robots – Short History	481
20.2 Continuum Robots – Short History	485
20.3 Snake-Like and Continuum Robot Modeling	487
20.4 Modeling of Locomotion for Snake-Like and Continuum Mechanisms	491
20.5 Conclusion and Extensions to Related Areas	492
Video-References	492
References	493
21 Actuators for Soft Robotics	
<i>Alin Albu-Schäffer, Antonio Bicchi</i>	499
21.1 Background	500
21.2 Soft Robot Design	502
21.3 Modeling Actuators for Soft Robotics	508
21.4 Modeling Soft Robots	511
21.5 Stiffness Estimation	513
21.6 Cartesian Stiffness Control	515
21.7 Periodic Motion Control	518
21.8 Optimal Control of Soft Robots	521
21.9 Conclusions and Open Problems	524

Video-References	525
References	526
22 Modular Robots	
<i>I-Ming Chen, Mark Yim</i>	531
22.1 Concepts and Definitions	531
22.2 Reconfigurable Modular Manipulators	533
22.3 Self-Reconfigurable Modular Robots	535
22.4 Conclusion and Further Reading	539
Video-References	540
References	540
23 Biomimetic Robots	
<i>Kyu-Jin Cho, Robert Wood</i>	543
23.1 Overview	544
23.2 Components of Biomimetic Robot Design	544
23.3 Mechanisms	545
23.4 Material and Fabrication	561
23.5 Conclusion	567
Video-References	568
References	570
24 Wheeled Robots	
<i>Woojin Chung, Karl Iagnemma</i>	575
24.1 Overview	575
24.2 Mobility of Wheeled Robots	576
24.3 Wheeled Robot Structures	582
24.4 Wheel-Terrain Interaction Models	586
24.5 Wheeled Robot Suspensions	589
24.6 Conclusions	592
Video-References	592
References	593
25 Underwater Robots	
<i>Hyun-Taek Choi, Junku Yuh</i>	595
25.1 Background	595
25.2 Mechanical Systems	596
25.3 Power Systems	599
25.4 Underwater Actuators and Sensors	601
25.5 Computers, Communications, and Architecture	606
25.6 Underwater Manipulators	614
25.7 Conclusions and Further Reading	617
Video-References	617
References	618
26 Flying Robots	
<i>Stefan Leutenegger, Christoph Hürzeler, Amanda K. Stowers, Kostas Alexis, Markus W. Achtelik, David Lentink, Paul Y. Oh, Roland Siegwart</i>	623
26.1 Background and History	624
26.2 Characteristics of Aerial Robotics	625
26.3 Basics of Aerodynamics and Flight Mechanics	629
26.4 Airplane Modeling and Design	641

26.5 Rotorcraft Modeling and Design	647
26.6 Flapping Wing Modeling and Design	653
26.7 System Integration and Realization	659
26.8 Applications of Aerial Robots	662
26.9 Conclusions and Further Reading	666
Video-References	666
References	667
27 Micro-/Nanorobots	
<i>Bradley J. Nelson, Lixin Dong, Fumihiro Arai</i>	671
27.1 Overview of Micro- and Nanorobotics	671
27.2 Scaling	674
27.3 Actuation at the Micro- and Nanoscales	675
27.4 Imaging at the Micro- and Nanoscales	676
27.5 Fabrication	678
27.6 Microassembly	681
27.7 Microrobotics	687
27.8 Nanorobotics	692
27.9 Conclusions	704
Video-References	704
References	705
Part C Sensing and Perception	
28 Force and Tactile Sensing	
<i>Mark R. Cutkosky, William Provancher</i>	717
28.1 Overview	717
28.2 Sensor Types	718
28.3 Tactile Information Processing	725
28.4 Integration Challenges	730
28.5 Conclusions and Future Developments	731
Video-References	731
References	731
29 Inertial Sensing, GPS and Odometry	
<i>Gregory Dudek, Michael Jenkin</i>	737
29.1 Odometry	737
29.2 Gyroscopic Systems	739
29.3 Accelerometers	742
29.4 IMU Packages	743
29.5 Satellite-Based Positioning (GPS and GNSS)	744
29.6 GPS-IMU Integration	749
29.7 Further Reading	750
29.8 Currently Available Hardware	750
References	751
30 Sonar Sensing	
<i>Lindsay Kleeman, Roman Kuc</i>	753
30.1 Sonar Principles	754
30.2 Sonar Beam Pattern	756
30.3 Speed of Sound	758

30.4	Waveforms	758
30.5	Transducer Technologies	759
30.6	Reflecting Object Models	760
30.7	Artifacts	761
30.8	TOF Ranging	762
30.9	Echo Waveform Coding	765
30.10	Echo Waveform Processing	767
30.11	CTFM Sonar	769
30.12	Multipulse Sonar	772
30.13	Sonar Rings and Arrays	773
30.14	Motion Effects	775
30.15	Biomimetic Sonars	778
30.16	Conclusions	779
	Video-References	780
	References	780
31	Range Sensing	
	<i>Kurt Konolige, Andreas Nüchter</i>	783
31.1	Range Sensing Basics	783
31.2	Sensor Technologies	785
31.3	Registration	794
31.4	Navigation and Terrain Classification and Mapping	804
31.5	Conclusions and Further Reading	807
	References	807
32	3-D Vision for Navigation and Grasping	
	<i>Danica Kragic, Kostas Daniilidis</i>	811
32.1	Geometric Vision	812
32.2	3-D Vision for Grasping	820
32.3	Conclusion and Further Reading	822
	Video-References	822
	References	822
33	Visual Object Class Recognition	
	<i>Michael Stark, Bernt Schiele, Aleš Leonardis</i>	825
33.1	Object Classes	825
33.2	Review of the State of the Art	826
33.3	Discussion and Conclusions	837
	References	838
34	Visual Servoing	
	<i>François Chaumette, Seth Hutchinson, Peter Corke</i>	841
34.1	The Basic Components of Visual Servoing	842
34.2	Image-Based Visual Servo	843
34.3	Pose-Based Visual Servo	851
34.4	Advanced Approaches	854
34.5	Performance Optimization and Planning	856
34.6	Estimation of 3-D Parameters	858
34.7	Determining s^* and Matching Issues	859
34.8	Target Tracking	859

34.9 Eye-in-Hand and Eye-to-Hand Systems Controlled in the Joint Space	860
34.10 Under Actuated Robots	861
34.11 Applications	863
34.12 Conclusions	863
Video-References	863
References	863
35 Multisensor Data Fusion	
<i>Hugh Durrant-Whyte, Thomas C. Henderson</i>	867
35.1 Multisensor Data Fusion Methods	867
35.2 Multisensor Fusion Architectures	880
35.3 Applications	885
35.4 Conclusions	889
Video-References	889
References	890
Part D Manipulation and Interfaces	
36 Motion for Manipulation Tasks	
<i>James Kuffner, Jing Xiao</i>	897
36.1 Overview	898
36.2 Task-Level Control	900
36.3 Manipulation Planning	904
36.4 Assembly Motion	911
36.5 Unifying Feedback Control and Planning	918
36.6 Conclusions and Further Reading	920
Video-References	923
References	923
37 Contact Modeling and Manipulation	
<i>Imin Kao, Kevin M. Lynch, Joel W. Burdick</i>	931
37.1 Overview	931
37.2 Kinematics of Rigid-Body Contact	932
37.3 Forces and Friction	936
37.4 Rigid-Body Mechanics with Friction	939
37.5 Pushing Manipulation	942
37.6 Contact Interfaces and Modeling	943
37.7 Friction Limit Surface	946
37.8 Contacts in Grasping and Fixture Designs	949
37.9 Conclusions and Further Reading	950
Video-References	951
References	951
38 Grasping	
<i>Domenico Prattichizzo, Jeffrey C. Trinkle</i>	955
38.1 Models and Definitions	956
38.2 Controllable Twists and Wrenches	961
38.3 Compliant Grasps	965
38.4 Restraint Analysis	967

38.5 Examples	975
38.6 Conclusion and Further Reading	985
Video-References	986
References	986
39 Cooperative Manipulation	
<i>Fabrizio Caccavale, Masaru Uchiyama</i>	989
39.1 Historical Overview	990
39.2 Kinematics and Statics	991
39.3 Cooperative Task Space	995
39.4 Dynamics and Load Distribution	996
39.5 Task-Space Analysis	998
39.6 Control	999
39.7 Conclusions and Further Reading	1003
Video-References	1004
References	1004
40 Mobility and Manipulation	
<i>Oliver Brock, Jaeheung Park, Marc Toussaint</i>	1007
40.1 Grasping and Manipulation	1009
40.2 Control	1013
40.3 Motion Generation	1017
40.4 Learning	1021
40.5 Perception	1025
40.6 Conclusions and Further Reading	1029
Video-References	1029
References	1030
41 Active Manipulation for Perception	
<i>Anna Petrovskaya, Kaijen Hsiao</i>	1037
41.1 Perception via Manipulation	1037
41.2 Object Localization	1038
41.3 Learning About an Object	1049
41.4 Recognition	1054
41.5 Conclusions	1057
Video-References	1058
References	1058
42 Haptics	
<i>Blake Hannaford, Allison M. Okamura</i>	1063
42.1 Overview	1064
42.2 Haptic Device Design	1068
42.3 Haptic Rendering	1071
42.4 Control and Stability of Force Feedback Interfaces	1073
42.5 Other Types of Haptic Interfaces	1075
42.6 Conclusions and Further Reading	1079
References	1079
43 Telerobotics	
<i>Günter Niemeyer, Carsten Preusche, Stefano Stramigloli, Dongjun Lee</i>	1085
43.1 Overview and Terminology	1085

43.2 Telerobotic Systems and Applications	1087
43.3 Control Architectures	1090
43.4 Bilateral Control and Force Feedback	1095
43.5 Emerging Applications of Telerobotics	1101
43.6 Conclusions and Further Reading	1104
Video-References	1104
References	1105
44 Networked Robots	
<i>Dezhen Song, Ken Goldberg, Nak-Young Chong</i>	1109
44.1 Overview and Background	1109
44.2 A Brief History	1110
44.3 Communications and Networking	1112
44.4 Properties of Networked Robots	1115
44.5 Cloud Robotics	1121
44.6 Conclusion and Future Directions	1125
Video-References	1126
References	1126
Part E Moving in the Environment	
45 World Modeling	
<i>Wolfram Burgard, Martial Hebert, Maren Bennewitz</i>	1135
45.1 Historical Overview	1136
45.2 Models for Indoors and Structured Environments	1137
45.3 World and Terrain Models for Natural Environments	1141
45.4 Dynamic Environments	1149
45.5 Summary and Further Reading	1149
Video-References	1150
References	1150
46 Simultaneous Localization and Mapping	
<i>Cyrill Stachniss, John J. Leonard, Sebastian Thrun</i>	1153
46.1 SLAM: Problem Definition	1154
46.2 The Three Main SLAM Paradigms	1157
46.3 Visual and RGB-D SLAM	1166
46.4 Conclusion and Future Challenges	1169
Video-References	1170
References	1171
47 Motion Planning and Obstacle Avoidance	
<i>Javier Minguez, Florant Lamiraux, Jean-Paul Laumond</i>	1177
47.1 Nonholonomic Mobile Robots: Where Motion Planning Meets Control Theory	1178
47.2 Kinematic Constraints and Controllability	1179
47.3 Motion Planning and Small-Time Controllability	1180
47.4 Local Steering Methods and Small-Time Controllability	1181
47.5 Robots and Trailers	1184
47.6 Approximate Methods	1186
47.7 From Motion Planning to Obstacle Avoidance	1187