Robot Ysis Tsai

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The two volume set LNAI 7101 and LNAI 7102 constitutes the refereed proceedings of the 4th International Conference on Intelligent Robotics and Applications, ICIRA 2011, held in Aachen, Germany, in November 2011. The 122 revised full papers presented were thoroughly reviewed and selected from numerous submissions. They are organized in topical sections on progress in indoor UAV, robotics intelligence, industrial robots, rehabilitation robotics, mechanisms and their applications, multi robot systems, robot mechanism and design, parallel kinematics, parallel kinematics machines and parallel robotics, handling and manipulation, tangibility in human-machine interaction, navigation and localization of mobile robot, a body for the brain: embodied intelligence in bio-inspired robotics, intelligent visual systems, self-optimising production systems, computational intelligence, robot control systems, human-robot interaction, manipulators and applications, stability, dynamics and interpolation, evolutionary robotics, bio-inspired robotics, and image-processing applications.

Stroke and spinal cord injury often result in paralysis with serious negative consequences to the independence and quality of life of those who sustain them. For these individuals, rehabilitation provides the means to regain lost function. Rehabilitation following neurological injuries has undergone revolutionary changes, enriched by neuroplasticity. Neuroplastic-based interventions enhance the efficacy and continue to guide the development of new rehabilitation strategies. This book presents three important technology-based rehabilitation interventions that follow the concepts of neuroplasticity. The book also discusses clinical results related to their efficacy. These interventions are: functional electrical stimulation therapy, which produces coordinated muscle contractions allowing people with paralysis to perform functional movements with rich sensory feedback; robot-assisted therapy, which uses robots to assist, resist, and guide movements with increased intensity while also reducing the physical burden on therapists; and brain–computer interfaces, which make it possible to verify the presence of motor-related brain activity during rehabilitation. Further, the book presents the combined use of these three technologies to illustrate some of the emerging approaches to the neurorehabilitation of voluntary movement. The authors share their practical experiences obtained during the development and clinical testing of functional electrical stimulation therapy controlled by a brain–computer interface as an intervention to restore reaching and grasping.

Autonomous robot vehicles are vehicles capable of intelligent motion and action without requiring either a guide or teleoperator control. The recent surge of interest in this subject will grow even grow further as their potential applications increase. Autonomous vehicles are currently being studied for use as reconnaissance/exploratory vehicles for planetary exploration, undersea, land and air environments, remote repair and maintenance, material handling systems for offices and factories, and even intelligent wheelchairs for the disabled. This reference is the first to deal directly with the unique and fundamental problems and recent progress associated with autonomous vehicles. The editors have assembled and combined significant material from a multitude of sources, and, in effect, now conviniently provide a coherent organization to a previously scattered and ill-defined field.

Minimally invasive surgery has impacted the outcomes of surgery more than any technology since the development of sterile technique. The hard science has demonstrated that decrease in wound complications and recovery time has created the biggest gap with open approaches to surgery. The total economic benefit may be unfathomable when looked at comprehensively. Integral to the rise of minimal access and therapeutic techniques in surgery has been the growth of technological improvements over time. Beginning with insufflators, videoscopy, and energy devices, that evolution has continued into the development of tele-surgical devices that feature full articulation of instruments, high-resolution 3-D optics, and computer assisted movement. This has come with controversy – as the dominant manufacturer of robotic assisted devices, Intuitive Surgical, and their generations of da Vinci surgical platforms, holds enough market share to spur cries of monopoly and financial excess. However, with over 3000 world-wide systems in use, and over 6000 peer-reviewed research articles, the impact of robotic surgery cannot be ignored. The current state of data suggests equivalency in most procedures with regard to traditional outcome measures, equal or somewhat elevated costs, with specific areas of superiority. The first section of this textbook, Surgical Robots, covers the history, economics, training, and medico-legal aspects of robotic surgery that will be of interest to students, residents, fellows, surgical staff, and administrators or public health specialists who seek to gain a comprehensive background on robotic surgery, or justification

for purchasing a robotic system for their institution. Surgeons will also find this background valuable to their practice, to give context to their procedures so they can better counsel their patients, help with advocating for robotic platform purchases, and proactively prepare themselves for medico-legal issues. The chapter on legal issues will have specific instances of robotic surgery-related lawsuits and their outcomes, a first for robotic surgery texts. The second section of this textbook, Robotic Procedures, will contain a comprehensive catalogue of procedures that have been performed robotically in general surgery, gynecology, urology, plastic surgery, cardiothoracic, and otolaryngology. Each author will cover the existing literature, preoperative planning, room and patient setup, steps of the procedure, and postoperative care. Standardized room maps and port placement will help the student, resident, fellow, surgeon or OR Staff to quickly reference these before cases. Each chapter will also cover the specific equipment needs and expected complexity of the procedures, allowing administrators to better gauge how to prepare for, or ration, use or their robotic resources. The final section, Future of Robotics, will give the entire scope of audience a look into what exciting advancements in the field are on the horizon. This textbook is a complete resource for robotic-assisted minimally invasive surgery, covering the history, current state, technical and clinical aspects, and future considerations that may be of interest to any who has a role, stake, or curiosity regarding robotic surgery.

Parallel robots are closed-loop mechanisms presenting very good performances in terms of accuracy, velocity, rigidity and ability to manipulate large loads. They have been used in a large number of applications ranging from astronomy to flight simulators and are becoming increasingly popular in the field of machine-tool industry. This book presents a complete synthesis of the latest results on the possible mechanical architectures, analysis and synthesis of this type of mechanism. It is intended to be used by students (with over 150 exercises and numerous internet addresses), researchers (with over 650 references and anonymous ftp access to the code of some algorithms presented in this book) and engineers (for which practical results, mistakes to avoid, and applications are presented). Since the publication of the first edition (2000) there has been an impressive increase in terms of study and use of this kind of structure that are reported in this book. This second edition has been completely overhauled. The initial chapter on kinematics has been split into Inverse Kinematics and Direct Kinematics. A new chapter on calibration was added. The other chapters have also been rewritten to a large extent. The reference section has been updated to include around 45% new works that appeared after the first edition.

Mechanical engineering, an engineering discipline borne of the needs of the industrial revolution, is once again asked to do its substantial share in the call for industrial renewal. The general call is urgent as we face profound issues of productivity and competitiveness that require engineering solutions, among others. The Mechanical Engineering Series features graduate texts and research monographs intended to address the need for information in contemporary areas of mechanical engineering. The series is conceived as a comprehensive one that covers a broad range of concentrations important to mechanical engineering graduate education and research. We are fortunate to have a distinguished roster of consulting editors on the advisory board, each an expert in one the areas of concentration. The names of the consulting editors are listed on the next page of this volume. The areas of concentration are: applied mechanics; biome chan ics; computational mechanics; dynamic systems and control; energetics; mechanics of materials; processing; thermal science; and tribology.

The processing of image sequences has a broad spectrum of important applica tions including target tracking, robot navigation, bandwidth compression of TV conferencing video signals, studying the motion of biological cells using microcinematography, cloud tracking, and highway traffic monitoring. Image sequence processing involves a large amount of data. However, because of the progress in computer, LSI, and VLSI technologies, we have now reached a stage when many useful processing tasks can be done in a reasonable amount of time. As a result, research and development activities in image sequence analysis have recently been growing at a rapid pace. An IEEE Computer Society Workshop on Computer Analysis of Time-Varying Imagery was held in Philadelphia, April 5-6, 1979. A related special issue of the IEEE Transactions on Pattern Anal ysis and Machine Intelligence was published in November 1980. The IEEE Com puter magazine has also published a special issue on the subject in 1981. The purpose of this book is to survey the field of image sequence analysis and to discuss in depth a number of important selected topics. The seven chap ters fall into two categories. Chapters 2, 3, and 7 are comprehensive surveys on, respectively, the whole field of image sequence analysis, efficient coding of image sequences, and the processing of medical image sequences. In Chapters 1, 4, 5, and 6 the authors present mainly results of their own research on, respectively, motion estimation, noise reduction in image sequences, moving object extraction, and occlusion.

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