

Table of Contents

Preface	xi
Chapter 1. Mechatronics Systems Based on CAD/CAM	1
Fusaomi NAGATA, Yukihiro KUSUMOTO, Keigo WATANABE and Maki K. HABIB	
1.1. Introduction.	1
1.2. Five-axis NC machine tool with a tilting head	1
1.3. Three-axis NC machine tool with a rotary unit.	4
1.3.1. Introduction	4
1.3.2. Post-processor for a three-axis NC machine tool with a rotary unit	5
1.3.3. Experiment.	7
1.4. Articulated-type industrial robot	8
1.4.1. Introduction	8
1.4.2. For sanding a wooden workpiece	9
1.4.3. For mold finishing	16
1.5. Desktop Cartesian-type robot	21
1.5.1. Background	21
1.5.2. Cartesian-type robot	22
1.5.3. Design of weak coupling control between force feedback loop and position feedback loop	23
1.5.4. Frequency characteristic of force control system	24
1.5.5. Finishing experiment of an LED lens mold	25
1.6. Conclusions.	26
1.7. Bibliography	27

Chapter 2. Modeling and Control of Ionic Polymer–Metal Composite Actuators for Mechatronics Applications	29
Andrew McDAID, Kean AW and Sheng Q. XIE	
2.1. Introduction.	29
2.2. Electromechanical IPMC model	33
2.2.1. Nonlinear electric circuit	35
2.2.2. Electromechanical coupling.	38
2.2.3. Mechanical beam model.	39
2.2.4. Parameter identification and results	40
2.3. IPMC stepper motor.	44
2.3.1. Mechanical design	45
2.3.2. Model integration and simulation	46
2.3.3. Experimental validation	46
2.3.4. Extension to four IPMCs	48
2.4. Robotic rotary joint	49
2.4.1. Mechanical design	50
2.4.2. Control system	50
2.4.3. System parameter tuning	51
2.4.4. Experimental tuning results	55
2.4.5. Gain schedule nonlinear controller.	58
2.4.6. Gain schedule vs. PID controller	60
2.5. Discussions	63
2.6. Concluding remarks.	63
2.7. Bibliography	64
Chapter 3. Modeling and Simulation of Analog Angular Sensors for Manufacturing Purposes	69
João FIGUEIREDO	
3.1. Introduction.	69
3.2. Pancake resolver model.	73
3.2.1. Description.	73
3.2.2. Mathematical model	75
3.3. Simulation and experimental results	94
3.3.1. Performance of the overall model	94
3.3.2. Manufacturer correction tools	95
3.4. Conclusions.	99
3.5. Acknowledgment	99
3.6. Bibliography	99
Chapter 4. Robust Control of Atomic Force Microscopy	103
Bilin AKSUN GÜVENÇ, Serkan NECİPOĞLU, Burak DEMİREL and Levent GÜVENÇ	
4.1. Introduction.	103

4.2. Repetitive control of the vertical direction motion	104
4.2.1. Tapping mode AFM system model	106
4.2.2. Repetitive control basics.	108
4.2.3. Mapping mixed sensitivity specifications into controller parameter space.	110
4.2.4. Repetitive control features of COMES	111
4.2.5. Robust repetitive controller design using the COMES toolbox	113
4.2.6. Simulation results for the vertical direction	115
4.3. MIMO disturbance observer control of the lateral directions.	117
4.3.1. The piezotube and the experimental setup	119
4.3.2. MIMO disturbance observer	122
4.3.3. Disturbance observer design for the piezotube and experimental results	124
4.4. Concluding remarks.	128
4.5. Acknowledgments.	129
4.6. Bibliography	130
Chapter 5. Automated Identification	133
Hiroo WAKAUMI	
5.1. Introduction.	133
5.2. Serial binary barcode	134
5.2.1. Identification technology for serial binary barcodes	136
5.2.2. Requirements for serial binary barcode identification	139
5.2.3. Decoding for identification	139
5.3. Two-dimensional binary barcode	140
5.3.1. Scanning technology of the 2D barcode	142
5.3.2. Multi-line scan based on time-sharing laser light emission	144
5.4. Ternary barcode	149
5.4.1. Dual-threshold method.	150
5.4.2. Envelope differential composite method	155
5.4.3. Fixed-period delay method	158
5.5. RFID.	160
5.5.1. Electromagnetic induction technology	161
5.5.2. Microwave transmission technology	162
5.6. Application examples	163
5.7. Concluding remarks.	164
5.8. Acknowledgments.	164
5.9. Bibliography	165
Chapter 6. An Active Orthosis for Gait Rehabilitation	169
Shahid HUSSAIN and Sheng Q. XIE	
6.1. Introduction.	169

6.1.1. Gait rehabilitation.	169
6.1.2. Rehabilitation robotics.	170
6.1.3. Biomechanics of gait.	172
6.1.4. Robot-assisted gait rehabilitation: a review	174
6.1.5. Gait training strategies: a review.	176
6.2. Compliant active orthosis design	178
6.2.1. Design criteria.	179
6.2.2. Active orthosis components.	179
6.3. Modeling	182
6.3.1. PMA dynamic modeling.	182
6.3.2. Interaction force estimation	184
6.4. Control	184
6.5. Simulation results	187
6.6. Conclusions.	189
6.7. Acknowledgment	189
6.8. Bibliography	190
Chapter 7. Intelligent Assistive Knee Exoskeleton	195
Mervin CHANDRAPAL, Xiaoqi CHEN and Wenhui WANG	
7.1. Introduction.	195
7.1.1. Background on assistive devices	195
7.1.2. Lower extremity AR devices	197
7.2. Overview of knee exoskeleton system	202
7.3. Modeling and control of pneumatic artificial muscle (PAM).	205
7.3.1. Background	205
7.3.2. Characteristic of the PAM.	206
7.3.3. Models from literature	207
7.3.4. Model used.	209
7.4. Modeling of high-speed on/off solenoid valve	211
7.4.1. Experimental validation of high-speed valve flow rate.	213
7.5. Self-organizing fuzzy control	214
7.5.1. Introduction to fuzzy control	214
7.5.2. Fuzzy control system for PAM.	215
7.5.3. Introduction to self-organizing fuzzy controllers	220
7.5.4. Practical implementation	221
7.6. Surface electromyography	224
7.6.1. Origins of surface electromyography (sEMG) signals	224
7.6.2. sEMG signal acquisition and conditioning	225
7.6.3. Relating sEMG to muscle force	227
7.7. Hardware implementation	229
7.8. Concluding remarks.	231

7.9. Acknowledgment	232
7.10. Bibliography	232
List of Authors	239
Index	241