



Robot Grippers

By Gareth J. Monkman, Stefan Hesse, Ralf Steinmann, Henrik Schunk

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Since robotic prehension is widely used in all sectors of manufacturing industry, this book fills the need for a comprehensive, up-to-date treatment of the topic. As such, this is the first text to address both developers and users, dealing as it does with the function, design and use of industrial robot grippers. The book includes both traditional methods and many more recent developments such as micro grippers for the optoelectronics industry. Written by authors from academia, industry and consulting, it begins by covering the four basic categories of robotic prehension before expanding into sections dealing with endeffector design and control, robotic manipulation and kinematics. Later chapters go on to describe how these various gripping techniques can be used for a common industrial aim, with details of related topics such as: kinematics, part separation, sensors, tool exchange and compliance. The whole is rounded off with specific examples and case studies. With more than 570 figures, this practical book is all set to become the standard for advanced students, researchers and manufacturing engineers, as well as designers and project managers seeking practical descriptions of robot endeffectors and their applications.

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Editorial Review

From the Back Cover

Since robotic prehension is widely used in all sectors of the manufacturing industry, this book fills the need for a comprehensive, up-to-date treatment of the topic. As such, this is the first text to address both developers and users, dealing as it does with the function, design and use of industrial robot grippers. The book includes both traditional methods and many more recent developments such as micro grippers for the optoelectronics industry. Written by authors from academia, industry and consulting, it begins by covering the four basic categories of robotic prehension before expanding into sections dealing with endeffector design and control, robotic manipulation and kinematics. Later chapters go on to describe how these various gripping techniques can be used for a common industrial aim, with details of related topics such as: kinematics, part separation, sensors, tool exchange and compliance. The whole is rounded off with specific examples and case studies. With more than 570 figures, this practical book is all set to become the standard for advanced students, researchers and manufacturing engineers, as well as designers and project managers seeking practical descriptions of robot endeffectors and their applications.

From the contents:

- Introduction to Prehension Technology
- Automatic Prehension
- Impactive Mechanical Grippers
- Ingressive Grippers
- Astrictive Prehension
- Contigutive Prehension
- Miniature Grippers and Microgrippers
- Special Designs
- Hand Axes and Kinematics
- Separation
- Instrumentation and Control
- Tool Exchange and Reconfigurability
- Compliance
- Selected Case Studies

Authors:

Gareth Monkman is Professor of Robotics and Automation at the Fachhochschule Regensburg in Germany. In addition to authoring a large number of academic papers, he also holds numerous patents in the field of gripper technology.

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Gareth Monkman is Professor of Robotics and Automation at the Fachhochschule Regensburg in Germany. Besides authoring a large number of academic papers, he also holds numerous patents in the field of gripper technology.

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Users Review

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