PART B

NOVEL MECHANISMS, ROBOTS AND APPLICATIONS

DETC2012-70064 ................................................................. 977
Reconfiguration and Unified Kinematics Analysis of a Metamorphic Parallel Mechanism
With Bifurcated Motion
   Dongming Gan, Jian S. Dai, and Lakmal D. Seneviratne

DETC2012-70147 ................................................................. 987
The Single-Track Three Legged Mobile Robot
   John R. Goulding
<table>
<thead>
<tr>
<th>DETC2012-70265</th>
<th>DARwIn-OP Humanoid Robot Kinematics</th>
<th>1187</th>
</tr>
</thead>
<tbody>
<tr>
<td>Robert L. Williams II</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-70371</th>
<th>Kinematical Model and Topology Patterns of a New 6-Parallel-Legged Walking Robot</th>
<th>1197</th>
</tr>
</thead>
<tbody>
<tr>
<td>Pan Yang and Feng Gao</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-70526</th>
<th>A Frame-Independent Vector Expression of the Singularity Locus of the Gough-Stewart Platform</th>
<th>1207</th>
</tr>
</thead>
<tbody>
<tr>
<td>Karine Doyon, Philippe Cardou, and Clément Gosselin</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-70588</th>
<th>A New Discrete Event System Model for Supervising and Controlling Robotic Arm Path Tacking Tasks Based on Adaptive Masking</th>
<th>1217</th>
</tr>
</thead>
<tbody>
<tr>
<td>Soheil Arastehfar, Ying Liu, and Wen Feng Lu</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-70600</th>
<th>Optimal Base Placement and Motion Planning for Mobile Manipulators</th>
<th>1227</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bin Du, Jing Zhao, and Chunyu Song</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-70636</th>
<th>Classification of Screw Systems Composed of Three Planar Pencils of Lines</th>
<th>1235</th>
</tr>
</thead>
<tbody>
<tr>
<td>Xianwen Kong and Andrew Johnson</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-70662</th>
<th>Non-Singular Assembly Mode Changing Trajectories of a 6-dof Parallel Robot</th>
<th>1245</th>
</tr>
</thead>
<tbody>
<tr>
<td>Stéphane Caro, Philippe Wenger, and Damien Chablat</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-70716</th>
<th>Configuration Workspaces of Series-Parallel Mechanisms</th>
<th>1255</th>
</tr>
</thead>
<tbody>
<tr>
<td>Brian McCarthy, Mikola Lysenko, and Vadim Shapiro</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-70770</th>
<th>Path Planning of Planar Parallel Mechanisms Using Global Workspace Road Maps</th>
<th>1269</th>
</tr>
</thead>
<tbody>
<tr>
<td>Wesley Au, Chao Chen, and Hoam Chung</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-70912</th>
<th>Jerk-Continuous Trajectories for Cyclic Tasks</th>
<th>1277</th>
</tr>
</thead>
<tbody>
<tr>
<td>Paolo Boscariol, Alessandro Gasparetto, and Renato Vidoni</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-70921</th>
<th>On the Numerical Classification of the Singularities of Robot Manipulators</th>
<th>1287</th>
</tr>
</thead>
<tbody>
<tr>
<td>Oriol Bohigas, Dimitar Zlatanov, Montserrat Manubens, and Lluis Ros</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>DETC2012-71239</th>
<th>USV Trajectory Planning for Time Varying Motion Goals in an Environment With Obstacles</th>
<th>1297</th>
</tr>
</thead>
<tbody>
<tr>
<td>Petr Svec, Atul Thakur, Brual C. Shah, and Satyandra K. Gupta</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>
Towards Energy Efficient Follow Behaviors for Unmanned Ground Vehicles Over Rugged Terrains
Madan M. Dabbeeru, Joshua D. Langsfeld, Petr Svec, and Satyandra K. Gupta

The Accessible Region of Space and Workspace for Robots With Intermittent Flight Phases
Michael Kean and Raymond J. Cipra

Planar Trajectory Planning for Hopping and Swinging Along Designated Ground Contacts
Michael Kean and Raymond J. Cipra

Controlled Infeasibility for Physically Feasible Optimal Motion Planning of Manipulators
Joo H. Kim and Chang B. Joo

Robot Task Planning and Trajectory Learning for Flexible Automation
Iraj Mantegh

Suppression of Period-Doubling Bifurcation in Passive Dynamic Walking With Delayed Feedback Control
Yuji Harata, Koji Iwano, Fumihiko Asano, and Takashi Ikeda

Bipedal Walking Robot Driven by Elastic Cables
Elvedin Kljuno, Robert L. Williams II, and Jim Zhu

Estimating the Orientation of a Game Controller Moving in the Vertical Plane Using Inertial Sensors
Peng He, Philippe Cardou, and André Desbiens

Optimal Design of a River Boat Simulator
Juan C. Blanco and Carlos F. Rodriguez

A Systematic Method for Model Parameter Identification of Nonlinear Dynamics Systems Using Trajectory Pattern Method
Jahangir Rastegar and Dake Feng

Design of Reflex Actions for Compensating High Amplitude Disturbances to Digital Controllers
Won Young Kim and Kishore Pochiraju
Design and Quaternion-Based Attitude Control of the Omnicopter MAV Using Feedback Linearization
Yangbo Long, Sean Lyttle, Nicholas Pagano, and David J. Cappelleri

Dynamic Performance With Control of a 2DOF Parallel Robot
Gianmarc Coppola, Dan Zhang, Kefu Liu, and Zhen Gao

Example of Internal Redundancy to Improve the Dynamics Performance of Parallel Manipulators
Soheil S. Parsa, Juan A. Carretero, and Roger Boudreau

Modeling and Simulation of a Novel 16-DOF Humanoid Biped Robot
C. Hernández-Santos, E. Rodríguez-Leal, R. Soto, and J. L. Gordillo

Kinematic and Dynamic Analysis of Flexible-Link Parallel Robots by Means of an ERLS Approach
Renato Vidoni, Paolo Boscariol, Alessandro Gasparetto, and Marco Giovagnoni

A Dynamic Model of a Belt Driven Electromechanical XY Plotter Cutter
Joseph V. Prisco and Philip A. Voglewede

Controller Design and Preliminary Testing of a Powered Below-Knee Prosthetic Device
Jinming Sun and Philip A. Voglewede

Relative Contact Dynamics and Its Application on Manipulator’s Contact Stability Problem
Jianxun Liang, Ou Ma, and Caishan Liu

Global Stability Study of a Compliant Double-Inverted Pendulum Based on Hamiltonian Modeling
Emmanouil Spyrakos-Papastavridis, Gustavo Medrano-Cerda, Jian Dai, and Darwin G. Caldwell

Method for the Creation of a Six Bar Linkage to Simultaneously Carry Two Rigid Bodies Through Four Coordinated Positions
Ronald A. Zimmerman, II
<table>
<thead>
<tr>
<th>Conference Paper ID</th>
<th>Page Number</th>
</tr>
</thead>
<tbody>
<tr>
<td>DETC2012-70175</td>
<td>1497</td>
</tr>
<tr>
<td>Parametric Modeling: A New Paradigm for Mechanisms Education?</td>
<td></td>
</tr>
<tr>
<td>John A. Mirth</td>
<td></td>
</tr>
<tr>
<td>DETC2012-70176</td>
<td>1503</td>
</tr>
<tr>
<td>The Application of Geometric Constraint Programming to the Design of Motion Generating Six-Bar Linkages</td>
<td></td>
</tr>
<tr>
<td>John A. Mirth</td>
<td></td>
</tr>
<tr>
<td>DETC2012-70277</td>
<td>1513</td>
</tr>
<tr>
<td>Mechanism Branches, Turning Curves, and Critical Points</td>
<td></td>
</tr>
<tr>
<td>David H. Myszka, Andrew P. Murray, and Charles W. Wampler</td>
<td></td>
</tr>
<tr>
<td>DETC2012-70544</td>
<td>1527</td>
</tr>
<tr>
<td>A Family of Overconstrained 6R Linkages With the Rotational Symmetry of Order 2</td>
<td></td>
</tr>
<tr>
<td>Ketao Zhang and Jian S. Dai</td>
<td></td>
</tr>
<tr>
<td>DETC2012-70587</td>
<td>1535</td>
</tr>
<tr>
<td>Numerical Solutions of Polynomial Equations for the Eight-Position Synthesis of the Cylindrical-Spherical Dyad</td>
<td></td>
</tr>
<tr>
<td>Chintien Huang, Chenning Hung, and Kuenming Tien</td>
<td></td>
</tr>
<tr>
<td>DETC2012-70649</td>
<td>1543</td>
</tr>
<tr>
<td>A Proposal for a Unified Concept of Kinematic Singularities for Holonomic and Non-Holonomic Mechanisms</td>
<td></td>
</tr>
<tr>
<td>Andreas Mueller</td>
<td></td>
</tr>
<tr>
<td>DETC2012-70737</td>
<td>1553</td>
</tr>
<tr>
<td>An Automated Kinematic Analysis Tool for Computationally Synthesizing Planar Mechanisms</td>
<td></td>
</tr>
<tr>
<td>Pradeep Radhakrishnan and Matthew I. Campbell</td>
<td></td>
</tr>
<tr>
<td>DETC2012-70852</td>
<td>1563</td>
</tr>
<tr>
<td>A Polynomial Approach to Inverse Kinematics of Rolling Contact</td>
<td></td>
</tr>
<tr>
<td>Lei Cui and Jian Dai</td>
<td></td>
</tr>
<tr>
<td>DETC2012-70882</td>
<td>1571</td>
</tr>
<tr>
<td>Polar Decomposition of Unit Dual Quaternions</td>
<td></td>
</tr>
<tr>
<td>Anurag Purwar and Q. J. Ge</td>
<td></td>
</tr>
<tr>
<td>DETC2012-70916</td>
<td>1579</td>
</tr>
<tr>
<td>Dimensional Mobility Criteria of Planar 6T-9R Paradoxical Chains</td>
<td></td>
</tr>
<tr>
<td>Chung-Ching Lee, Jeng-Hsiung Lee, and Po-Chih Lee</td>
<td></td>
</tr>
<tr>
<td>DETC2012-71190</td>
<td>1587</td>
</tr>
<tr>
<td>A Novel Approach to Algebraic Fitting of a Pencil of Quadrics for Planar 4R Motion Synthesis</td>
<td></td>
</tr>
<tr>
<td>Q. J. Ge, Ping Zhao, Anurag Purwar, and Xiangyun Li</td>
<td></td>
</tr>
</tbody>
</table>
DETC2012-71255................................................................. 1597
The Synthesis of the Axodes of Spatial Four-Bar Linkages
  Giorgio Figliolini, Pierluigi Rea, and Jorge Angeles

DETC2012-71282................................................................. 1607
A Line Geometric Approach to Kinematic Acquisition of Geometric Constraints
  Jun Wu, Q. J. Ge, and Feng Gao

DETC2012-71289................................................................. 1615
Mobility Determination of Mechanisms Based on Rigidity Theory
  Michael Slavutin, Offer Shai, and Andreas Müller

DETC2012-71332................................................................. 1629
Higher-Pair Reuleaux-Triangle in Square and its Derived Mechanisms
  Giorgio Figliolini, Pierluigi Rea, and Salvatore Grande

Author Index................................................................. 1639