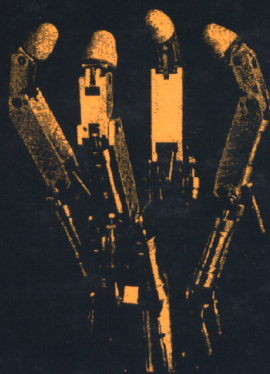


ROBOTIC AND MANUFACTURING SYSTEMS

**Recent Results in Research, Development,
and Applications**

Volume 3



EDITORS:

**Mohammad Jamshidi
François Pin**

ROBOTIC AND

MANUFACTURING SYSTEMS

RECENT RESULTS IN RESEARCH, DEVELOPMENT, AND APPLICATIONS

VOLUME 3

TSI PRESS SERIES: *Proceedings of the World Automation Congress*

Mohammad Jamshidi, *Series Editor*

VOLUME 3

Volume 1, *Intelligent Automation and Soft Computing: Trends in Research, Development, and Applications*, edited by M. Jamshidi, C. Nguyen, R. Lumia, and J. Yuh, 1994.

Volume 2, *Intelligent Automation and Soft Computing: Trends in Research, Development, and Applications*, edited by M. Jamshidi, J. Yuh, C. Nguyen, and R. Lumia, 1994.

Volume 3, *Robotic and Manufacturing Systems: Recent Results in Research, Development, and Applications*, edited by M. Jamshidi, F. Pin, and F. Pierrot, 1996.

Volume 4, *Intelligent Automation and Control: Recent Trends in Development and Applications*, edited by M. Jamshidi, J. Yuh, and P. Dauchez, 1996.

Volume 5, *Soft Computing with Industrial Applications: Recent Trends in Research and Development*, edited by M. Jamshidi, M. Fathi, and F. Pierrot, 1996.

157 2558

TSI PRESS SERIES

ROBOTIC AND MANUFACTURING SYSTEMS

RECENT RESULTS IN RESEARCH, DEVELOPMENT, AND APPLICATIONS

VOLUME 3

Proceedings of the World Automation Congress (WAC '96)
May 28-30, 1996
Montpellier, France

EDITORS

Mohammad Jamshidi
NASA ACE Center, University of New Mexico, USA

François Pin
Oak Ridge National Laboratory, USA

François Pierrot
LIRMM, France



ALBUQUERQUE



TSI PRESS



1996

BIBLIOTHEQUE DU CERIST

Cover Design: The cover of this volume incorporates Figure 3, "The TUM-Hydraulic Hand," of Friedrich Pfeiffer's paper entitled "Cooperating Fingers—A Special Form of Cooperating Robots," which begins on page 639.

Copyright © 1996 TSI Press, Division of TSI Enterprises, Inc.
P.O. Box 14126, Albuquerque, NM 87191-4126
Fax: (505) 291-0013

ISBN 1-889335-00-2

7323

THIS VOLUME IS DEDICATED TO:

Professor Mohamed Mansour

*for his pioneering works on continuous and discrete-time control systems
and his dedicated services to the international control community*

Mohamed Mansour was born in Damietta, Egypt, on August 30, 1928. He received the B.Sc. and M.Sc. degree in electrical engineering from the University of Alexandria, Egypt, in 1951 and 1953, respectively, and the Dr. Sc. Techn. degree in electrical engineering from ETH Zurich, Switzerland, in 1965. He was Assistant Professor in Electrical Engineering at Queen's University, Canada, from 1967-1968. He has been Professor and Head of the Department of Automatic Control at ETH Zürich since 1968, he was Dean of Electrical Engineering from 1976-1978 and Head of the Institute of Automatic Control and Industrial Electronics, ETH Zürich, during 1976-1978, 1980-1982, 1984-1986, and 1989-1990. He was Visiting Professor at IBM Research Lab., San Jose, California, from September to December 1974; at the University of Florida, Gainesville, from January to March 1975; at the University of Illinois, Urbana, from August to December 1981; at the University of California, Berkeley, from January to March 1983; at the Australian National University, from October to November 1989 and from February to March 1992; at the Tokyo Institute of Technology, from October to November 1992; at the University of Miami, from January to April 1994; at the Australian National University, from January to March 1995; at the Tokyo Institute of Technology, Nippon Steel Chair of Intelligent Control, from July to September 1995. He was President of the Swiss Society of Automatic Control from 1979-1985; Member of the Council and Treasurer of IFAC (International Federation of Automatic Control) from 1981-1993; President of the 4th IFAC/IFIP Conference on "Digital Computer Applications for Process Control" in 1974; Chairman of the International Program Committee of the IFAC Symposium on "Computer Aided Design of Control Systems" in 1979; Chairman of the International Program Committee of the 4th IFAC/IFORS Symposium on Large-Scale Systems "Theory and Applications" in 1986; Co-Chairman of the IOTA/IFAC Symposium on "Dynamics of Controlled Mechanical Systems" in 1988; Vice-Chairman of International Program Committee of the IFAC/IFORS/IMACS Symposium on Large Scale Systems "Theory and Applications" in 1989; Co-Chairman of the International Program Committee of the first IFAC Symposium on "Design Methods of Control Systems" in 1991; Chairman of the "International Workshop on Robust Control", Ascona, in 1992; Chairman of the International Program Committee of "Fundamentals of Sampled-Data Systems" in 1992; Chairman of the Meeting of Professors of Automatic Control in Western Europe "WEPAC '92" in 1992; Vice-Chairman of the IFAC Education Committee from 1978-1981; Member of the Senate of the Swiss Academy of Natural Sciences from 1979-1985; Member of the Scientific Committee of INTERKAMA from 1980-1989; Member of the Evaluation Committee of the Research Program "Control of Complex Systems" of the German Research Council from 1986-1989; Member of the Scientific Committee on Fuzzy Control of the Government of North Rhein Westfalia from 1991-present; Delegate of IFAC to the United Nations in Geneva from 1982-1990; Chairman of the Committee of "Awards and Nominations" of the IEEE Control Systems Society from 1989-1990; Chairman of the Committee for Eng. Sciences of Third World Academy of Sciences (TWAS) from 1991-present; Delegate of TWAS to the United Nations from 1991-present. His awards include Silver Medal of ETH Zurich, Switzerland 1965, Fellow IEEE 1985, Honorary Professor of the Gansu University of Technology, PR China 1986, Honorary Professor of the Guangxi University, PR China 1987, Associate Fellowship of the Third World Academy of Science 1989, IFAC Outstanding Service Award 1990, Gulleming-Cauer Award IEEE CAS Society 1992 IFAC Advisor Award 1993, Honorary Membership of the Swiss Society of Automatic Control 1994. His fields of interest are: control systems—especially stability theory and digital control—stability of power systems, and digital filters, Main Research Results are Stability Criteria, Mansour-Matrix for Discrete Systems (Applications: Stability, Identification, Model Reduction, Lattice Filters for one & multidimensional Systems), and Strong Theorem for Robust Stability. His hobbies are Languages, Philosophy and Religions, Ping Pong, and Tennis.

TABLE OF CONTENTS

Specify, Validate and Implement Missions for Autonomous Vehicles S. Abdou, M. Parent and B. Espiau	1
Walking Robots for Planetary Exploration Missions A. Martin-Alvarez, J. Hillebrand, W. De Peuter, P. Putz, A. Matthyssen, and J.F. de Weerd	7
Task Level Position Control of Robots, and Static Errors Compensation M. Aicarde, G. Cannata, and G. Casalino	15
Distributed Task Processing by a Multiple Autonomous Robot System Using an Intelligent Data Carrier System H. Asama, T. Fujii, H. Kaetsu, I. Endo, and T. Futjita	23
Neuromate: First Clinical Results and Future Developments F. Badano, F. Danel, A. Benabid, and D. Hoffman	29
Principles and Applications of Analogical Gates in the Control of a Non-holonomic Autonomous Mobile Robot E. Badreddin	37
Conceptual Design of an Aircraft Automated Coating Removal System J.E. Baker, J.V. Draper, F.G. Pin, A.H. Primm, and S. Shekhar	43
The Fuzzy Horizons Obstacle Avoidance Method for Mobile Robots M. Balzarotti and G. Ulivi	51
Optimal Range Sensor Positioning for 3-D Model Reconstruction J.E. Banta and M.A. Abidi	57
Hybrid Force Position Control of Constrained Manipulators by Means of Unchattering VSC G. Bartolini and A. Ferrara	63
State Feedback and Linearization for a Pneumatic Servosystem G. Belforte and C. Ferraresi	71
Motion Planning of Industrial Robots with Technological Constraints P. Pledel and Y. Bestaoui	77
Working-Out of a Documentation Authoring System inside a Manufacturing-Specific Software Engineering Framework M. Le Bissonnais and F. Prunet	83
Generation of Optimized Collision Free Robot Move Statements Based on Genetic Algorithms C. Blume	89
Obstacle Detection for the Ranger Telerobotic Flight Experiment B. Bon and H. Seraji	95

The Effects of Computational Delays in Coordinated Multiple-arm Manipulation using Robust Internal Force-based Impedance Control R.G. Bonitz and T.C. Hsia	103
Robust Internal Force-tracking Impedance Control for Coordinated Multi-arm Manipulation-Theory and Experiments R.G. Bonitz and T.C. Hsia	111
The OmniMate: A Mobile Robot with Omnidirectional Motion, Internal Odometry Error Correction, and Recovery After Actuator Failure J. Borenstein	119
Decentralized Piloting of Transport Systems by Autonomous Vehicles N. Broissin, P. Pujo, J-C. Bertrand	125
On the Workspace Analysis of Spherical Platform Mechanisms F. Bulea, J. Angeles, and P.J. Zsombor-Murray	131
Algorithms of Robust Global Stabilization of Flexible Manipulators I.V. Burkov, A.A. Pervozvanski, and L.B. Freidovich	137
Low-level Stored Waste Inspection Using Mobile Robots J.S. Byrd and R.O. Pettus	143
Contact Force Control in Bilateral Manipulation A. Caiti, G. Cannata, G. Casalino, and S. Reto	149
Manufacturing Engineering Curricula at Drexel University S. Carmi	155
A Study of Feasibility for a New Wrist M. Ceccarelli	161
Robust Segmentation of 3D Laser Range Finder Data L. Charbonnier, J.D. Tardos, and O. Strauss	167
Calibration of Scanning Laser Range Cameras B.L. Chase, G.A. Armstrong, and M.A. Abidi	173
Applying Random Sampling and Histogram Analysis for Mobile Robot Localization B-Y. Chee and S.Y.T. Lang	179
Neural Network Learning Control for Position and Force Regulation of Multi-Manipulator Systems P.C.Y. Chen, J.K. Mills, and K.C. Smith	185
Operational Motions of a Manipulator Robot from a Singularity C. Chevallereau	191
Ballistic Motions for a Quadrupled Robot C. Chevallereau, F. Gosselin, B. Perrin, and A. Formal'sky	197

Modelling Constrained Robotics Systems: A Differential-Algebraic Equations Approach R. Costa-Castelló, R. Griñó, and L. Basañez	203
Virtual Collaborative Robotics C.C. Crane, R. Pinheiro, P. Adsit, C. Will, D. Haddox, R. Dalton, and J.S. Tulenko	209
Implementation of a Package of Software for Communication Between a PC and a ABB Robot M. Crisóstomo, C. Mendes, and A.T. de Almeida	215
Intelligent Control of Robotic Fish Processing C.W. de Silva	223
Efficient Motion Planning for Cooperating Multi-arm Robotics G. Dodds and B. McCarragher	229
Medical Robotics T. Dohi	235
Platooning for Vehicles and Automatic Parking by Scheduling Robotic Actions P. Daviet, S. Abdou, and M. Parent	241
Minimum Energy Torque Tracking of Induction Motors with Parameter Uncertainty L.C. de Souza Marques and S. I. Seleme, Jr.	247
Towards a Specification Method for an Automated System: The Third Phase of the Method L. Jacquet, G. Doriry, and R. Soenen	253
Kinematic Analysis of Cuspidal Positioning Manipulators in the Presence of Obstacles J. El Omri and P. Wenger	259
Gain Adaptation in Sliding Mode Control of Robotic Manipulators M. Ertugrul, F. Keresteciogulu, and O. Kaynak	265
Formal Mission Specification in an Open Architecture B. Espiau, K. Kapellos, E. Coste-Manière, and N. Turro	271
A Completely Wireless Development System for Mobile Robots L. Feng, J. Borenstein, and D. Wehe	277
NC++, A New Paradigm in CNC-Technology B. Ferroni, D. Baggi, M. Milan, and N. Pelloni	283
Hierarchical Petri Nets for Manufacturing Systems P. Finotto and D. Crestani	293
Soft Control of an Effector Path for a Mobile Manipulator C. Fischer, M. Buss, and G. Schmidt	299
Position, Orientation Detection and Control of Mobile Robots through Real Time Colour Processing J. Forest, R. García-Campos, and J. Salvi	307

A Dynamic Resource Allocation System for Computer Integrated Manufacturing Systems D. Gracanin, K.P. Valavanis, S.A. Smith, Jr., T. Williams, II, and A. Steward	313
Fault Handling in Flexible Machining Cells P. Gullander, A. Adlemo, and S-A. Andréasson	319
Robot-Mountable Dosimeter: A Protection for Machines in Nuclear Plants Against Radiation Failure A. Holmes-Siedle	327
Decision Making Software for Dual-Arm Operations in Nuclear Facility Decontamination and Dismantlement R. Hooper, C. Kapoor, and D. Tesar	333
On the Workspace of Planar Three-Legged Platforms M.L. Husty	339
Piezoelectric Force Sensors and Actuators: Modeling and Control M. Indri and A. Tornambè	345
Cooperative Cleaning: An Experiment with Multiple Autonomous Robots D. Jung and A. Zelinsky	351
Blanket Maintenance Development for ITER S. Kakudate, K. Oka, M. Nakahira, K. Obara, K. Taguchi, S. Fukatsu, E. Tada, K. Shibanuma, K. Ioki, N. Matsuhira, A. Tesini, R. Hager, and R. Haange	357
Design of an Autonomous Underwater Robot: ODIN II K. Kawaguchi, C. Ikehara, S.K. Choi, M.S. Fujita, W.C. Lee, and J. Yuh	363
A New Iterative Controller Refinement Technique for Amplitude Constrained Control Action L. Keviczky and C.S. Bányász	369
A Mobile Robot Control, Avoiding Uncertain, High Energy Disturbances S. Khanmohammadi, S. Moaddab, P. Jabbedare-Maralani	377
Autonomous Calibration of Robots Using Planar Points W. Khalil, Ph. Lemoine, and M. Gauthier	383
Design of Teleoperated Robot System for Nozzle Dam Installation/Removal in Steam Generator C-H. Kim, S-Y. Hwang, and S. Kim	389
Position Error Prediction Using Neural Networks for Remote Nuclear Fuel Cask Handling Device K. Kim and J.S. Yoon	395
Design of an AGV-Based Material Handling System Satisfying Throughput Constraint Y-S. Kim, G-H. Kim, and J.G. Lee	401
Design of a Robotic Gripper System for Automated Deformable Material Manipulation R. Kolluri, K.P. Valavanis, T. Hebert, A. Steward, and M. Sonnier	407
A Local Path Generation Method using Obstacle Vectors and Via Points Y.D. Kwon and J.S. Lee	415

Optimizing Drill Tapes for Printed Circuit Boards O. Lahyani, E. Oertli, and H. Eberle	421
Cooperation Between a Visual Sensor and Omnidirectional Telemeter for Localization D. Laurent, M. El Mustapha, and P. Claude	427
Cooperative Robot Problem Solving M. Li	433
Rapid World Modelling for Robotics C.Q. Little and C.W. Wilson	441
A Novel 2-DOF Robotic Positioning Device with Force/Torque Sensing J. Liu and X. Zhao	447
The Hierarchical System of Mathematical Simulation of Technological Objects V.A. Lounev	453
Methods of Artificial Intelligence for Computer-Aided Process Planning V.A. Lounev	459
Underwater Navigation by Terrain Matching L. Lucido, V. Rigaud, J. Opderbecke, R. Deriche, and Z. Zhang	465
Methods for Determining the Reliability of Robotic Systems for Use in Radiation Environments K. Lauridsen, H.E. Kongsø, and P. Christensen	471
Distributing Real-Time Control Tasks Among Multi-Agent Robot Systems T.C. Lueth, J. Hellqvist, and T. Laengle	477
Low-Cost Virtual Collaborative Environment Through Open System Technology R. Lumia, M. Todacheeney, and S. Quintana	483
Divertor Remote Handling Test Facilities D. Maisonnier, C. Damiani, and E. Martin	489
Vision-Based Control Law using 3-D Visual Features P. Martinet, J. Gallice, and D. Khadraoui	497
First Results of a H_{∞} Control Structure Applied to the Second Link of the Puma 560 Robot F.P. Maselli, M. Innocenti, and E. Degoulange	503
Enhancing CIMOSA with Exception Handling S. Messina and P. Pleinevaux	511
Generating Dimensionally Accurate 3-D CAD Models S. Motavalli, J. Valenzuela, and B. Bidanda	519
Open Architecture Controller Activities in TEAM H. K. McCue	525
Safe Guidance in Robotic Travel Aid—Danger Estimation at Intersection H. Mori, K. Kaneko, and S. Kotani	531

Localizing Mobile Robots with a Single Camera in Structured Environments A. J. Muñoz and J. Gonzalez	539
Knowledge Based Control of a Fruit Picking Robot G. Muscato, G. Nunnari, and N. Abbate	545
VULCAIN: An Hardened Amplifier for DC Motor M. Marceau	551
Path Planning Using Linear Parametric Curve Based on Geometry Mapping of Obstacles I. Namgung and J-G. Kim	557
Minimum Time Search for a Class of Shortest Collision-Free Path Based on Linear Parametric Curve I. Namgung and J-G. Kim	563
Simulation and Test of a Flight-Type Wall-Climbing Robot A. Nishi and H. Miyagi	569
Manufacturing Integration for Naturally Varying Products H.R. Nicholls and M.G. Taylor	577
Hybrid Auction-based Control System Results in Cooperative Manufacturing S. Nahavandi	583
Intelligent Adhesive Tape Handling and Application System S. Nahavandi	589
A Development of Autonomous Tractor for Agricultural Field—Positioning System and its Experiment T. Nishizawa, A. Ohya, S. Yuta, and T. Takigawa	595
Opening Door Behavior of an Autonomous Mobile Manipulator by Combination of Action Primitives K. Nagatani and S. Yuta	603
A Practical Method of Two Phase Switching Receding Horizon Control H.A. Palizban, M.J. McGarity, and N.W. Rees	611
Cyclic Genetic Algorithms for the Locomotion of Hexapod Robots G.B. Parker and G.J.E. Rawlins	617
Improved Tri-aural Perception through Robot Motion H. Peremans and P. Veelaert	623
Validation of Software Components for Intelligent Actuation and Measurement J.F. Petin, D. Mery, H. Panetto, and B. Jung	631
Cooperating Fingers—A Special Form of Cooperating Robots F. Pfeiffer	639
Adding Memory Processing Behaviors to the Fuzzy Behaviorist-Based Navigation of Mobile Robots F.G. Pini and S.K. Bender	647

Path Planning for Autonomous Vehicles C. Potter	653
Validation of Standard Interfaces for Machine Control F. Proctor, J. Michaloski, W. Shackleford, and S. Szabo	659
Design of a Telerobotic Cleaning and Inspection Robotic System for Large Oil Storage Tanks Y. Qin, J. Rastegar, F. Khorrami, and H. Melkote	665
Enhancing the Fault Tolerance of a Robotic System Through Kinematic Redundancy R.G. Roberts	671
Optimization of Production Systems Using Genetic Algorithms D-I. U. Roßgoderer	677
Simulation and Control of a Pipe Crawling Robot T. Roßmann and F. Pfeiffer	683
Flexible Automation of High-Speed Machining of Unstructured Leather Components M. Saadat, C. Preece, and J.E.L. Simmons	691
Remote Handling in ITER K. Shibamura, T. Burgess, R. Haange, R. Hager, C. Holloway, N. Matsuhira, A. Tesini, E. Martin, J. Herndon, D. Maisonnier, and E. Tada	697
Automated High-Frequency Sealing in Measuring Instruments R.-D. Schraft, J.C. Spingler, and J.F. Woessner	705
Force Control in Locomotion of Legged Vehicle and for Service Operations A. Schneider, U. Schmucker, T. Ihme, E. Devjanin, and K. Savitsky	711
A Model of the Future Enterprise—Multifunctions Integrated Factory L. Si and P. H. Osanna	717
Development of a K3A Robot for Deployment in Radioactive Environments F.R. Sias, Jr.	723
Environment for Manufacturing Systems Configuration Management A.V. Smirnov	729
Programmable Mechanisms for Low-Cost Robots E.W. Smith, S. Nahavandi, and R.V. Ellis	735
An Innovative Approach to Robot-Assisted Preparation of the Femoral Cavity in Total Hip Replacement P. Skittides, R. Marsh, S. Gratsias, W. Witvrouw, J. De Schutter, and J. Vandersloten	741
Sensing Under Uncertainty for Mobile Robots T.M. Sobh, M. Dekhil, and A.A. Efros	747

A Very Fast Parallel Robot to be Applied to Dexterous Motion M. Uchiyama, T. Miwa, and D.N. Nenchev	753
Cooperative Multiple Robots to be Applied to Industries M. Uchiyama, T. Kitano, and Y. Tanno	759
Self-Adjusting Active Compliance Controller for Two Cooperating Robots Handling A Flexible Object C. von Albrichsfeld	765
Path Generation for Kinematic Redundant Manipulators with Multi-Criteria by Weight-Tuning D. Wang	771
Cooperation of Inertial and Visual Sensing for Underwater Vehicle Localization S. Wasielewski, and M.J. Aldon	777
Head-Eye Coordination: A Closed-Form Solution M. Xie	783
A Robust Controller Design Approach for Robot Manipulators S.J. Xu, M. Darouach, and M. Zasadzinski	791
Fuzzy Abduction and its Application to Diagnosis of Thermal Storage System K. Yamada and K. Kamimura	797
Indoor Environment Recognition for a Mobile Robot Using Ultrasonic Sensors—Measuring the Direction and Distance of Multiple Objects T. Yata, A. Ohya, and S. Yuta	803
Genetic Algorithms for Advanced Robotics and Manufacturing Systems A.M.S. Zalzal, N. Morad, and A.S. Rana	809
Dynamics of a Six-Degree-of-Freedom Parallel Manipulator with Revolute Legs K.E. Zanganeh, R. Sinatra, and J. Angeles	817
IAM Model and Robotic Car Assembly S.W. Zeng	823
Author Index	831
Subject Index	835