

INDEX TO AUTHORS OF PAPERS TO VOLUME 14

- Anderson, J.** See Eldridge, Gruben, LaRose, Funda, Gomory, Karidis, McVicker, Taylor and Anderson
- Arai, K. I. and Honda, T.** Micromagnetic actuators, 477–481
- Asfour, S.** See Ata, Elkhoga, Shalaby and Asfour
- Ata, A., Elkhoga, S., Shalaby, M. and Asfour, S.** Casual inverse dynamics of a flexible hub-arm system through Liapunov's second method, 381–389
- Ataka, M.** See Fujita, Ataka and Konishi
- Azad, A. K. M.** See Tokhi and Azad
- Bhotia, P., Harnick, H. and Ghosh, A.** A configuration space based approach for robotic assembly sequencing, 633–646
- Bitó, J. F.** See Rudas, Bitó and Tar
- Boddy, C.** See Hopper, Boddy and Reilly
- Bolzern, P., DeSantis, R., Locatelli, A. and Togno, S.** Dynamic model of a two-trailer articulated vehicle subject to nonholonomic constraints, 445–450
- Bradshaw, A. and Shao, J.** Swing-up control of inverted pendulum systems, 397–405
- Bradshaw, A.** See Seward, Bradshaw and Margrave
- Breguet, J. -M. and Renaud, P.** A 4-degrees-of-freedom microbot with nanometer resolution, 199–203
- Burg, T.** See de Queiroz, Dawson and Burg
- Byun, J-E. and Nagata, T.** Active visual sensing of the 3-D pose of a flexible object, 173–188
- Cao, B., Dodds, G. I. and Irwin, G. W.** An approach to time-optimal, smooth and collision-free path planning in a two robot arm environment, 61–70
- Ceccarelli, M., Valero, F., Mata, V., and Cuadrado, I.** Generation of adjacent configurations for a collision-free path planning of manipulators, 391–396
- Cheng, M. -Y. and Lin, C. -S.** Measurement of robustness for biped locomotion using a linearized Poincaré map, 253–259
- Cho, D. W.** See Lim and Cho
- Cho, J-K. and Park Y-s.** Experimental evaluation of time-varying shaping with a two-link flexible manipulator, 339–345
- Chung, J-M. and Nagata, T.** Binocular vision planning with anthropomorphic features for grasping parts by robots, 269–279
- Cloutier, G. M.** See Gourdeau, Cloutier and Laflamme
- Coiffet, P.** See Slutski and Coiffet
- Corke, P. I.** *In situ* measurement of motor electrical constants, 433–436
- Cuadrado, I.** See Ceccarelli, Valero, Mata and Cuadrado
- Dawson, D.** See de Queiroz, Dawson and Burg
- de Queiroz, M. S., Dawson, D. and Burg, T.** Reexamination of the DCAL controller for rigid link robots, 41–49
- DeSantis, R.** See Bolzern, DeSantis, Locatelli and Togno
- Dodds, G. I.** See Cao, Dodds and Irwin
- Drouin, M.** See Perdereau and Drouin
- Dutkiewicz, P.** See Kozlowski and Dutkiewicz
- Ebihara, K., Otari, T. and Kume, E.** Position localization for mobile robots using a colour image of equipment at nuclear plants, 677–686

- Ekalo Y.** See Vukobratović and Ekalo
- Eldridge, B., Gruben, K., LaRose, D., Funda, J., Gomory, S., Karidis, J., McVicker, G., Taylor, R. and Anderson, J.** A remote center of motion robotic arm for computer assisted surgery, 103–109
- Elkhoga, S.** See Ata, Elkhoga, Shalaby and Asfour
- Ellis, R. E., Ismaeil, O. M. and Lipsett, M. G.** Design and evaluation of high-performance haptic interface, 321–327
- Esashi, M.** See Lim, Minami, Yamamoto, Sugihara, Uchiyama and Esashi
- Ezura, Y.** See Shimoyama, Yasuda, Miura, Fujisawa and Ezura
- Fujisawa, Y. K.** See Shimoyama, Yasuda, Miura, Fujisawa and Ezura
- Fujita, H., Ataka, M. and Konishi, S.** Group work of distributed microactuators, 487–492
- Funda, J.** See Eldridge, Gruben, LaRose, Funda, Gomory, Karidis, McVicker, Taylor and Anderson
- Ghosh, A.** See Bhotia, Karnick and Ghosh
- Gomory, S.** See Eldridge, Gruben, LaRose, Funda, Gomory, Karidis, McVicker, Taylor and Anderson
- González, J. S. and Jones, D. I.** Parallel computation of configuration space, 205–212
- Gotlih, K., Troch, I. and Jezernik, K.** Global optimal control of redundant robot, 131–140
- Gourdeau, R., Cloutier, G. M. and Laffamme, J.** Parameter identification of a semi-flexible kinematic model for serial manipulators, 311–319
- Gruben, K.** See Eldridge, Gruben, LaRose, Funda, Gomory, Karidis, McVicker, Taylor and Anderson
- Haneda, R.** See Suzumori, Koga, Kondo and Haneda
- Hattori, T.** See Tominaga, Senda, Ohya, Idogaki and Hattori
- Honda, T.** See Arai and Honda
- Hopper, D., Boddy, C. and Reilly, D.** Advanced teleoperation testbed—A system you can see through, 457–461
- Howard, D.** See Zhang, Howard and Sanger
- Howard, D.** See Zhang, Sanger and Howard
- Hsia, T. C.** See Jung and Hsia
- Hsia, T. C.** See Strenn, Hsia and Wilhelmsen
- Hyeung-Sik, C.** Modeling of robot manipulators working under the sea and the design of a robot controller, 213–218
- Idogaki, T.** See Tominaga, Senda, Ohya, Idogaki and Hattori
- Irwin, G. W.** See Cao, Dodds and Irwin
- Ismaeil, O. M.** See Ellis, Ismaeil and Lipsett
- Jezernik, K.** See Gotlih, Troch and Jezernik
- Jezernik, K.** See Šabanović, Jezernik and Wada
- Jones, D. I.** See González and Jones
- Jung, S. and Hsia, T. C.** A study of neural network control of robot manipulators, 7–15
- Karidis, J.** See Eldridge, Gruben, LaRose, Funda, Gomory, Karidis, McVicker, Taylor and Anderson
- Karnick, H.** See Bhotia, Karnick and Ghosh
- Kastenmeier, T. and Vesely, F. J.** Numerical robot kinematics based on stochastic and molecular simulation methods, 329–337
- Kawamura, S.** See Pandian and Kawamura
- Khoshzaban, M., Sassani, F. and Lawrence, P. D.** Kinematic Calibration of Industrial Hydraulic Manipulators, 541–551
- Knight, J.** See Qiao, Moore and Knight
- Koga, A.** See Suzumori, Koga, Kondo and Haneda
- Kondo, F.** See Suzumori, Koga, Kondo and Haneda

- Konishi, S.** See Fujita, Ataka and Konishi
- Kozlowski, K. R. and Dutkiewicz, P.** Experimental identification of dynamic parameters for a class of geared robots, 561–574
- Kume, E.** See Ebihara, Otari and Kume
- Laflamme, J.** See Gourdeau, Cloutier and Laflamme
- LaRose, D.** See Eldridge, Gruben, LaRose, Funda, Gomory, Karidis, McVicker, Taylor and Anderson
- Lawrence, P. D.** See Khoshzaban, Sassani and Lawrence
- Lee, M. C.** See Yang, Lee, Lee and Arimoto
- Lee, M. H.** See Yang, Lee, Lee and Arimoto
- Lehtinen, H.** Force control for walking on soft terrains, 165–172
- Leung, A. and Payandeh, S.** Application of adaptive neural network to localization of objects using pressure array transducer, 407–414
- Li, X. S. Y.** See Sun and Liu
- Lim, G., Minami, K., Yamamoto, K., Sugihara, M., Uchiyama, M. and Esashi, M.** Multi-link active catheter snake-like motion, 499–506
- Lim, J. H. and Cho, D. W.** Multipath Bayesian Map Construction Model from Sonar Data, 527–540
- Lin, C. -S.** See Cheng and Lin
- Lin, Y.-J. and Yu, A.** Linear robust trajectory control of flexible joint manipulators, 375–380
- Lipsett, M. G.** See Ellis, Ismaeil and Lipsett
- Liu, J.** Towards a virtual work-bench for robotics training, 575–582
- Locatelli, A.,** See Bolzern, DeSantis, Locatelli and Togno
- Ma, S. and Nenchev, D. N.** Local torque minimization for redundant manipulators: a correct formulation, 235–239
- Madani, A.** See Morris and Madani
- Margrave, F.** See Seward, Bradshaw and Margrave
- Mata, V.** See Ceccarelli, Valero, Mata and Cuadrado
- Meghdari, A.** Conceptual design and dynamics modeling of a cooperative dual-arm cam-lock manipulator, 301–309
- Meguid, S. A.** See Shagal and Meguid
- McVicker, G.** See Eldridge, Gruben, LaRose, Funda, Gomory, Karidis, McVicker, Taylor and Anderson
- Miljakovic-Jevtic, I. and Potkonjak, V.** Secondary school specialization in robotics and FMS: A practical experience (a viewpoint), 451–455
- Minami, K.** See Lim, Minami, Yamamoto, Sugihara, Uchiyama and Esashi
- Miura, H.** See Shimoyama, Yasuda, Miura, Fujisawa and Ezura
- Monkman, G. J.** Sensory integrated fabric ply separation, 119–125
- Moore, P.** See Qiao, Moore and Knight
- Morris, A. S. and Madani, A.** Static and dynamic modelling of a two-flexible-link robot manipulator, 289–300
- Morris, A. S.** See Sun, Morris and Zalzal
- Nagata, T.** See Byun and Nagata
- Nagata, T.** See Chung and Nagata
- Nenchev, D. N.** See Ma and Nenchev
- Ng, S. and Wang, D.** Modelling and Control of a Flexible Spherical Wrist, 155–163
- Novaković, B.** See Paar, Pavin, Paar and Novaković
- Ohya, N.** See Tominaga, Senda, Ohya, Idogaki and Hattori
- Okamura, K. and Park, F. C.** Kinematic calibration using the product of exponentials formula, 415–421

- Otari, T.** See Ebihara, Otari and Kume
- Ovseevitch, A. I.** See Selig and Ovseevitch
- Paar, N.** See Paar, Pavin, Paar and Novaković
- Paar, V., Pavin, N., Paar, N. and Novaković, B.** Nonlinear regular dynamics of a single-degree robot model, 423–431
- Pandian, S. R. and Kawamura, S.** Hybrid force/position control for robot manipulators based on a D-type learning law, 51–59
- Park, F. C.** See Okamura and Park
- Park, Y-s.** See Cho and Park
- Payandeh, S.** A method for controlling robotic contact tasks, 281–288
- Payandeh, S.** See Leung and Payandeh
- Pavin, N.** See Paar, Pavin, Paar and Novaković
- Perdereau, V. and Drouin, M.** Hybrid external control for two robot coordinated motion, 141–153
- Potkonjak, V.** See Miljakovic-Jevtic and Potkonjak
- Qiao, H., Moore, P. and Knight, J.** A model and strategy analysis of the peg-hole system in the search process associated with robotic assembly operations without chamfers, 647–658
- Rahmanian-Shahri, N. and Troch, I.** A new on-line method to avoid collisions with links of redundant articulated robots, 619–620
- Rambeaud, P.** See Zeghloul and Rambeaud
- Rana, A. S. and Zalzal, A. M. S.** Near time-optimal collision-free motion planning of robotic manipulators using an evolutionary algorithm, 621–632
- Reilly, D.** See Hopper, Boddy and Reilly
- Renaud, P.** See Breguet and Renaud
- Ricker, S. L., Sarkar, N. and Rudie, K.** A discrete-event systems approach to modeling dextrous manipulation, 515–525
- Rudas, I. J., Bitó, J. F. and Tar, J. K.** An Advanced Robot Control Scheme Using ANN and Fuzzy Theory Based Solutions, 189–198
- Rudie, K.** See Ricker, Sarkar and Rudie
- Šabanović, A., Jezernik, K. and Wada, K.** Chattering-free sliding modes in robotic manipulators control, 17–29
- Sanger, D. J.** See Zhang, Howard and Sanger
- Sanger, D. J.** See Zhang, Sanger and Howard
- Sarkar, N.** See Ricker, Sarkar and Rudie
- Sassani, F.** See Khoshzaban, Sassani and Lawrence
- Selig, J. M. and Ovseevitch, A. I.** Manipulating robots along helical trajectories, 261–267
- Senda, K.** See Tominaga, Senda, Ohya, Idogaki and Hattori
- Seward, D. W., Bradshaw, A. and Margrave, F.** The anatomy of a humanoid robot, 437–443
- Shagal, G. and Meguid, S. A.** Effect of payloads contact upon the coupled dynamic response of two cooperating robots, 659–666
- Shalaby, M.** See Ata, Elkhoga, Shalaby and Asfour
- Shao, J.** See Bradshaw and Shao
- Shimoyama, I., Yasuda, T., Miura, H., Fujisawa, Y. K. and Ezura Y.** Mobile microbots, 469–476
- Slutski, L. and Coiffet, P.** Man-adaptive control of teleoperators, 111–117
- Strenn, S., Hsia, T. C. and Wilhelmsen, K.** A segmentation algorithm for collision avoidance in telerobotics Applications, 603–618
- Sugihara, M.** See Lim, Minami, Yamamoto, Sugihara, Uchiyama and Esashi
- Sun, D. and Liu, X. S. Y.** Adaptive Learning Control for Cooperation of Two Robots Manipulating a Rigid Object with Model Uncertainties, 365–373
- Sun, S., Morris, A. S. and Zalzal, A. M. S.** Trajectory planning of multiple coordinating robots using genetic algorithms, 227–234

- Suzumori, K., Koga, A., Kondo, F. and Haneda, R.** Integrated flexible microactuator systems, 493–498
- Tar, J. K.** See Rudas, Bitó and Tar
- Taylor, R.** See Eldridge, Gruben, LaRose, Funda, Gomory, Karidis, McVicker, Taylor and Anderson
- Togno, S.** See Bolzern, DeSantis, Locatelli and Togno
- Tokhi, M. O. and Azad, A. K. M.** Modelling of a single-link flexible manipulator system: theoretical and practical investigations, 91–102
- Tominaga, T., Senda, K., Ohya, N., Idogaki, T. and Hattori, T.** A bending and expanding motion actuator, 483–486
- Troch, I.** See Gotlih, Troch and Jezernik
- Uchiyama, M.** See Lim, Minami, Yamamoto, Sugihara, Uchiyama and Esashi
- Valavanis, K. P.** See Zhang and Valavanis
- Valero, F.** See Ceccarelli, Valero, Mata and Cuadrado
- Vesely, F. J.** See Kastenmeier and Vesely
- Vukobratović, M. K. and Ekalo, Y.** New approach to control of robotic manipulators interacting with dynamic environment, 31–39
- Wada, K.** See Šabanović, Jezernik and Wada
- Wang, D.** See Ng and Wang
- Webber, R. E.** See Zhang and Webber
- Wilhelmsen, K.** See Strenn, Hsia and Wilhelmsen
- Xi, F.** Inverse kinematics of free-floating space robotics with minimum dynamic disturbance, 667–676
- Yamamoto, K.** See Lim, Minami, Yamamoto, Sugihara, Uchiyama and Esashi
- Yang, S. Y., Lee, M. C., Lee, M. H. and Arimoto, S.** Development of digital stroke cylinder and its performance evaluation, 687–694
- Yasuda, T.** See Shimoyama, Yasuda, Miura, Fujisawa and Ezura
- Yu, A.** See Lin and Yu
- Zalzala, A. M. S.** See Rana and Zalzala
- Zalzala, A. M. S.** See Sun, Morris and Zalzala
- Zegloul, S. and Rambeaud, P.** A fast algorithm for distance calculation between convex objects using the optimization approach, 355–363
- Zhang, S. J., Howard, D. and Sanger, D. J.** Workspaces of a walking machine and their graphical representation. Part II: static workspaces, 219–226
- Zhang, S. J., Sanger, D. J. and Howard, D.** Workspaces of a walking machine and their graphical representation. Part I: kinematic workspaces, 71–79
- Zhang, Y. and Valavanis, K. P.** Sensor-based 2-D Potential Panel Method for Robot Motion Planning, 81–89
- Zhang, Y. and Webber, R. E.** Dynamic world modeling for a mobile robot among moving objects, 553–560

INDEX TO BOOKS REVIEWED IN VOLUME 14

The name of the reviewer of the book is given in parentheses

- Bekey, G. A. and Goldberg, K. Y.** *Neural Networks in Robotics*, (A. M. Andrew), 585
- Bode, M. F.** *Robotic Observatories*, (F. Margrave), 587
- Brown, C. M. and Terzopoulos, D.** *Real-Time Computer Vision*, (I. A. Craig), 349–350
- Colombo, C. and Crowley, J. L.** *Proceedings of the 3rd International Symposium on Intelligent Robotic Systems*, (A. M. Andrew), 588–589
- Crangle, C. and Suppes, P.** *Language and Learning for Robots*, (I. Craig), 588
- Crowcroft, J.** *Open Distributed Systems*, (J. A. Rose), 349
- Crowder, R. M.** *Electric Drives and Their Controls*, (A. M. Andrew), 588
- Crowley, J. L.** See Colombo and Crowley
- Goldberg, K. Y.** See Bekey and Goldberg
- Hashimoto, K.** *Visual Serving: Real-Time Control of Robot Manipulators Based on Visual Sensory Feedback*, (A. M. Andrew), 585–586
- Karlsson, J.** *World Industrial Robots 1995*, (F. Margrave), 589–590
- Pomerleau, D. A.** *Neural Network Perception for Mobile Robot Guidance*, (A. M. Andrew), 586–587
- Rampersad, H. K.** *Integrated and Simultaneous Design for Robotic Assembly*, (D. Bradley), 349
- Rosheim, M. E.** *Robot Evolution - The Development of Anthrobotics*, (F. Margrave), 589
- Shapiro, L. S.** *Affine Analysis of Image Sequences*, (F. Margrave), 587–588
- Suppes, P.** See Crangle and Suppes
- Terzopoulos, D.** See Brown and Terzopoulos
- Thomas, P. J.** *The Social and Interactional Dimensions of Human-Computer Interfaces*, (I. A. Craig), 350

INDEX TO AUTHORS OF PAPERS TO VOLUME 13

- Adli, M. A. and Hanafusa, H.** Contribution of internal forces to the dynamics of closed chain mechanisms, 507–514
- Arimoto, S.** Fundamental problems of robot control: Part I, Innovations in the realm of robot servo-loops, 19–27
- Arimoto, S.** Fundamental problems of robot control: Part II A nonlinear circuit theory towards an understanding of dexterous motions, 111–122
- Armstrong-Hélouvy, B.** See Corke and Armstrong-Hélouvy
- Balakrishnan, S.** See Singh, Zghal, Sepehri, Balakrishnan and Lawrence
- Baz, A.** See Gumusel and Baz
- Beaufre, B. and Zegloul, S.** A mobile robot navigation method using a fuzzy logic approach, 437–448
- Beiner, L.** A min-max problems of optimal actuator placement for lifting, 619–622
- Benhadj, R. and Dawson, B.** Air jets imaging tactile sensing device for automation applications, 521–529
- Beom, H. R. and Cho, H. S.** Mobile robot localization using a single rotating sonar and two passive cylindrical beacons, 243–252
- Bessonnet, G.** See Gaudin and Bessonnet
- Bhattacharya, S., Hatwal, H. and Ghosh, A.** On the optimum design of Stewart platform type parallel manipulators, 133–140
- Billatos, S. B.** A novel approach to flexible robotic assembly systems, 583–589
- Bobrow, J. E. and Desai, J.** A high torque to weight ratio robot actuator, 201–208
- Bridges, M. M., Cai, J., Dawson, D. M. and Grabbe, M. T.** Experimental results for a robust position and force controller implemented on a direct robot, 11–18
- Brown, A.** See Kalaycioglu and Brown
- Cai, J.** See Bridges, Cai, Dawson and Grabbe
- Chiacchio, P. and Chiaverini, S.** Coping with joint velocity limits in first-order inverse kinematics algorithms: analysis and real-time implementation, 515–519
- Chiaverini, S.** See Chiacchio and Chiaverini
- Cheng, R. M. H.** See Mehrabi, Cheng and Hemami
- Cherchas, D. B.** See Kotzev, Cherchas and Lawrence
- Cho, D. J., Kim, J. H. and Gweon, D. G.** Optimal turning gait of a quadruped walking robot, 559–564
- Cho, D. K., Choi, B. W. and Chung, M. J.** Optimal conditions for inverse kinematics of a robot manipulator with redundancy, 95–101
- Cho, H.-K., Lee, B.-H. and Ko, M.-S.** Path constrained time-optimal motion of a cooperative two robot system, 363–374
- Cho, H. S.** See Beom and Cho
- Cho, H. S.** See Kang and Cho
- Cho, J.-K. and Park, Y.-S.** Vibration reduction in flexible systems using a time-varying impulse sequence, 305–313
- Choi, B. W.** See Cho, Choi and Chung
- Choi, D.** See Chong, Choi and Suh
- Choi, H. R., Chung, W. K. and Youm Y.** Control of grasp stiffness using a multifingered robot hand with redundant joints, 351–362
- Choi, P. J. and Rice, J. A.** Spline-based micro accuracy joint interpolation, 37–44

- Chong, N. Y., Choi, D. and Suh, I. H.** A motion planning strategy for multifingered hands considering sliding and rolling contacts, 149–158
- Christiansen, A. D. and Goldberg, K. Y.** Comparing two algorithms for automatic planning by robots in stochastic environments, 565–573
- Chung, M. J.** See Cho, Choi and Chung
- Chung, W. K.** See Choi, Chung and Youm
- Cl  roux, L., Gourdeau, R. and Cloutier, G. M.** A semi-flexible kinematic model for serial manipulators, 385–395
- Cloutier, G. M.** See Cl  roux, Gourdeau and Cloutier
- Colbaugh, R. and Glass, K.** Decentralized adaptive compliance control of robot manipulators, 485–498
- Corke, P. I. and Armstrong-H  louvry, B.** A meta-study of PUMA 560 dynamics: A critical appraisal of literature data, 253–258
- Cosmi, F.** See Rovetta, Sala, Wen, Cosmi, Togno and Milanese
- Dalay, B. S.** See Qiao, Dalay and Parkin
- Davidovic, T.** See Kircanski, Davidovic and Vukobratovic
- Dawson, B.** See Benhadj and Dawson
- Dawson, D. M.** See Bridges, Cai, Dawson and Grabbe
- Dawson, D. M.** See Qu, Dawson, Dorsey and Duffie
- DeSantis, R. M.** Modeling and path-tracking control of a mobile wheeled robot with a differential drive, 401–410
- Denizhan, Y.** A compliant control method for disassembly of non-elastic parts using realised motion, 591–598
- Desai, J.** See Bobrow and Desai
- Dissanayake, M. W. M. G.** See Lee and Dissanayake
- Dorsey, J. F.** See Qu, Dawson, Dorsey and Duffie
- Duffie, J. D.** See Qu, Dawson, Dorsey and Duffie
- Dul  ba, I.** The method of minimal neighborhood: a new and most effective iterative method for minimum cost trajectory planning in robot manipulators, 297–304
- Gaudin, H. and Bessonnet, G.** From identification to motion optimization of a planar manipulator, 123–132
- Ghosh, A.** See Bhattacharya, Hatwal and Ghosh
- Glass, K.** See Colbaugh and Glass
- Goldberg, K. Y.** See Christiansen and Goldberg
- Gorbet, R. B. and Russell, R. A.** A novel differential shape memory alloy actuator for position control, 423–430
- Gourdeau, R.** See Cl  roux, Gourdeau and Cloutier
- Grabbe, M. T.** See Bridges, Cai, Dawson and Grabbe
- Gumusel, L. and Baz, A.** Experimental and theoretical evaluation of the buoyancy and gravity driven underwater robots, 273–286
- Gupta, K. and Xu, Z.** Complete 3D boundary representation from multiple range images: exploiting geometric constraints, 339–349
- Gweon, D. G.** See Cho, Kim and Gweon
- Hamavand, Z. and Schwartz, H. M.** Trajectory control of robotic manipulators by using a feedback-error-learning neural network, 449–459
- Hanafusa, H.** See Adli and Hanafusa
- Hatwal, H.** See Bhattacharya, Hatwal and Ghosh
- Hemami, A.** See Mehrabi, Cheng and Hemami
- Hsia, T. C.** See Jung and Hsia
- Hsia, T. C.** See Preising and Hsia
- Jumarie, G.** Stochastic Hamilton's principle and noisy sliding surfaces in the tracking control of manipulators, 209–213

- Jung, S. and Hsia, T. C.** A new neural network control technique for robot manipulators, 477–484
- Kalaycioglu, S. and Brown, A.** Adaptive hybrid force/position control for the Space Station Alpha robotic operations, 549–557
- Kang, E. S. and Cho, H. S.** Vibratory assembly of prismatic parts using neural network-based positioning error estimation, 185–193
- Kazerounian, K.** See Vahidi and Kazerounian
- Kelly, R.** A tuning procedure for stable PID control of robot manipulators, 141–148
- Kim, J. H.** See Cho, Kim and Gweon
- Kircanski, N., Davidovic, T. and Vukobratovic, M.** A contribution to parallelization of symbolic robot models, 411–421
- Kleeman, L.** A three dimensional localiser for autonomous robot vehicles, 87–94
- Ko, M.-S.** See Cho, Lee and Ko
- Ko, M.-S.** See Lee, Lee and Ko
- Kostamovaara, J.** See Nissil and Kostamovaara
- Kotzev, A., Cherchas, D. B. and Lawrence, P. D.** Performance of generalized predictive control with on-line model order determination for a hydraulic robotic manipulator, 55–64
- Krishnamurthy, K. and Yang, L.** Dynamic modeling and simulation of two cooperating structurally-flexible robotic manipulators, 375–384
- Lawrence, P. D.** See Kotzev, Cherchas and Lawrence
- Lawrence, P. D.** See Singh, Zghal, Sepehri, Balakrishnan and Lawrence
- Lee, B.-H.** See Cho, Lee and Ko
- Lee, B. H.** See Lee, Lee and Ko
- Lee, K. D., Lee, B. H. and Ko, M. S.** A comparative model-based analysis and design for multi-robot systems, 65–76
- Lee, K. Y. and Dissanayake, M. W. M. G.** Near minimum-time trajectory for two coordinated manipulators, 177–184
- Lee, M. H.** See Rodrigues, Li, Lee and Rowland
- Li, Y. F.** See Rodrigues, Li, Lee and Rowland
- Malowany, A. S.** See Noorhosseini and Malowany
- Matuszok, A.** See Tchofi and Matuszok
- Mehdian, M. and Thomas, D.** Tactile recognition of solid objects, 169–175
- Mehrabi, M. G., Cheng, R. M. H. and Hemami, A.** Parametric study and sensitivity analysis of automated vehicles, 469–475
- Milanesi, S.** See Rovetta, Sala, Wen, Cosmi, Togno and Milanesi
- Nicholls, H. R.** See Rowland and Nicholls
- Nissil, S. and Kostamovaara, J.** On the use of optical fibres in a pulsed time-of-flight laser rangefinder, 45–53
- Noorhosseini, S. M. and Malowany, A. S.** State Matrix Representation of Assembly and Robot Planning, 259–272
- Parkin, R. M.** See Qiao, Dalay and Parkin
- Preising, B. and Hsia, T. C.** Robot performance measurement and calibration using a 3D computer vision system, 327–337
- Qiao, H., Dalay, B. S. and Parkin, R. M.** A novel and practical strategy for the precise chamferless robotic peg hole insertion, 29–35
- Qu, Z., Dawson, D. M., Dorsey, J. F. and Duffie, J. D.** Robust estimation and control of robotic manipulators, 223–231
- Park, Y.-S.** See Cho and Park
- Pham, D. T. and Sagioglu, S.** Three methods of training multi-layer perceptrons to model a robot sensor, 531–538
- Pham, D. T.** See Rowlands and Pham

- Rahmanian-Shahri, N. and Troch, I.** Collision-avoidance control for redundant articulated robots, 159–168
- Rice, J. A.** See Choi and Rice
- Rodrigues, M. A., Li, Y. F., Lee, M. H. and Rowland, J. J.** Robotic grasping of complex shapes: is full geometrical knowledge of the shape really necessary?, 499–506
- Rovetta, A., Sala, Remo, Wen, X., Cosmi, F., Togno, A. and Milanese, S.** Telerobotic surgery project for laparoscopy, 397–400
- Rowland, J. J. and Nicholls, H. R.** A virtual sensor implementation for a flexible assembly machine, 195–199
- Rowland, J. J.** See Rodrigues, Li, Lee and Rowland
- Rowlands, H. and Pham, D. T.** Application of the Taguchi method to the design of a robot sensor, 607–617
- Russell, R. A.** See Gorbet and Russell
- Sagiroglu, S.** See Pham and Sagiroglu
- Sala, R.** See Rovetta, Sala, Wen, Cosmi, Togno and Milanese
- Sanders, D. A.** The modification of pre-planned manipulator paths to improve the gross motions associated with the pick and place task, 77–85
- Sasaki, S.** Feasibility studies of kinematics problems in the case of a class of redundant manipulators, 233–241
- Seo, Y.-J. and Yoon, Y.-S.** Design of a robust dynamic gait of the biped using the concept of dynamic stability margin, 461–468
- Sepehri, N.** See Singh, Zghal, Sepehri, Balakrishnan and Lawrence
- Schwartz, H. M.** See Hamavand and Schwartz
- Singh, N., Zghal, H., Sepehri, N., Balakrishnan, S. and Lawrence, P. D.** Coordinated-motion control of heavy-duty industrial machines with redundancy, 623–633
- Suh, I. H.** See Chong, Choi and Suh
- Tasch, U.** See Varma and Tasch
- Tchoń, K. and Matuszok, A.** On avoiding singularities in redundant robot kinematics, 599–606
- Thomas, D.** See Mehdian and Thomas
- Togno, A.** See Rovetta, Sala, Wen, Cosmi, Togno and Milanese
- Troch, I.** See Rahmanian-Shahri and Troch
- Vahidi, S. and Kazerounian, K.** On the sensitivity analysis of the computational kinematics of the robotic manipulators, 575–581
- Varma, V. K. and Tasch, U.** A new representation for a robot grasping quality measure, 287–295
- Vukobratovic, M.** See Kircanski, Davidovic and Vukobratovic
- Wen, X.** See Rovetta, Sala, Wen, Cosmi, Togno and Milanese
- Xu, Z.** See Gupta and Xu
- Yang, L.** See Krishnamurthy and Yang
- Yoon, Y.-S.** See Seo and Yoon
- Youm, Y.** See Choi, Chung and Youm
- Zeghloul, S.** See Beaufreere and Zeghloul
- Zghal, H.** See Singh, Zghal, Sepehri, Balakrishnan and Lawrence

INDEX TO BOOKS REVIEWED IN VOLUME 13

The name of the reviewer of the book is given in parentheses

- Brown, R. A.** *Machines That Learn: Based on the Principles of Empirical Control*, (A. M. Andrew), 105–106
- Crowley, J. L. and Christensen, H. I.** *Vision as Process*, (I. Craig), 540
- Dumoulin, E. and Trystram, G.** *Automated Control of Food and Biological Processes*, (T. Owen), 539
- Fisher, R. B. (ed.)** *Design and Application of Curves and Surfaces*, (H. G. Fox), 320
- Harris, L. and Jenkin, M.** *Spatial Vision in Humans and Robots*, (I. Craig), 106
- Hartmanis, J. and Lin, H. (eds.)** *Computing: The Future a Broader Agenda for Computer Science and Engineering*, (I. Craig), 319–320
- Hoeschele, D. F.** *Analog-to-Digital and Digital-to-Analog Conversion Techniques (2nd edn)*, (I. Craig), 321
- Honderd, G. and Grant, E.** *Intelligent Systems: Safety, Reliability and Maintainability Issues*, (A. M. Andrew), 107–108
- McMahon, W. W.** *An Efficiency-Based Management Information System*, (A. M. Andrew), 105
- Nicholls, H. R.** *Advanced Tactile Sensing for Robotics*, (A. M. Andrew), 106–107
- Rao, M., Xia, Q. and Ying, Y.** *Modeling and Advanced Control for Process Industries: Applications to the Paper Making Process*, (T. Owen), 320–321
- Robothkaydistystry, S.** *Scandinavian Symposium on Robotics*, (T. Owen), 539
- Schilling, J. and White, R. B.** *Robotic Manipulation: Programming and Simulation Studies with Software*, (I. Craig), 319
- Szafarczyk, M. (ed.)** *Automatic Supervision in Manufacturing*, (T. Owen), 321
- Tebbutt, C.** *Expert Aided Control System Design*, (T. Owen), 320
- United Nations** *World Industrial Robots 1994*, (T. Owen), 539
- Wiendahl, H.-P.** *Load-Orientated Manufacturing Control*, (T. Owen), 539