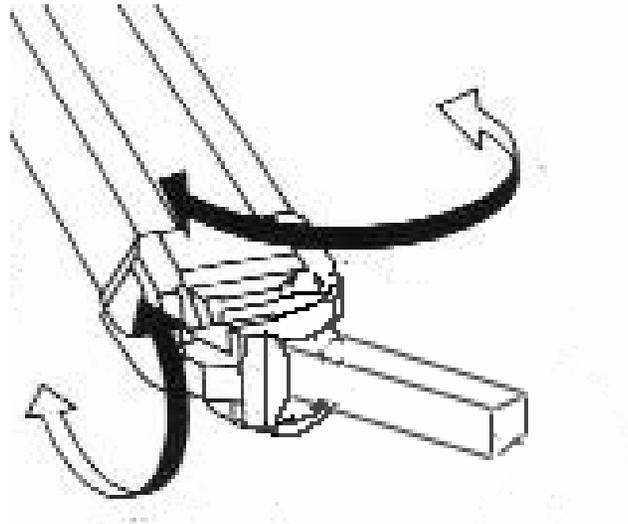


Tipi di polso robotico – 2 gdl

I polsi possono avere 2 o 3 giunti = 2/3 gdl

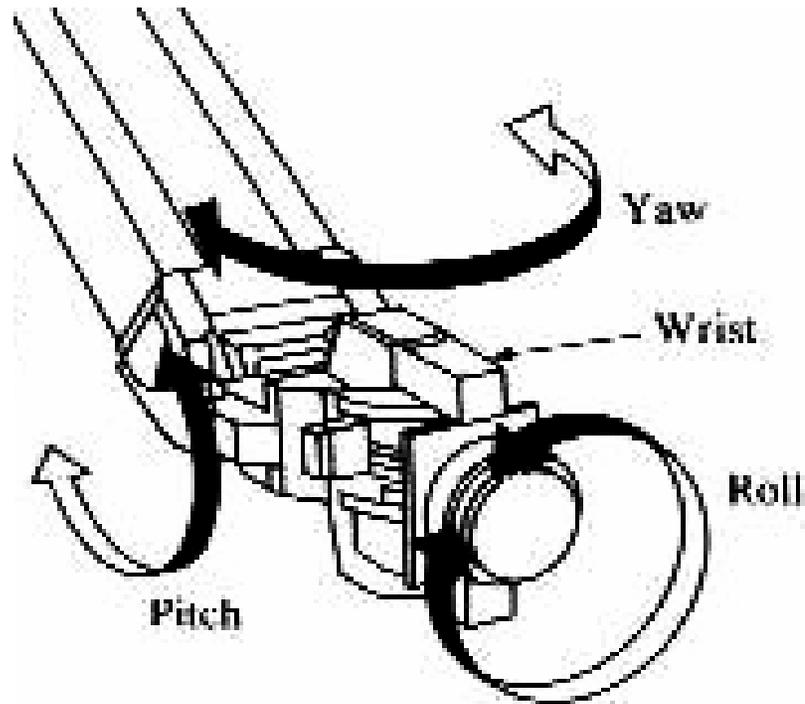
I polsi sono tutti R, ma con caratteristiche diverse

Per alcuni compiti bastano polsi 2R



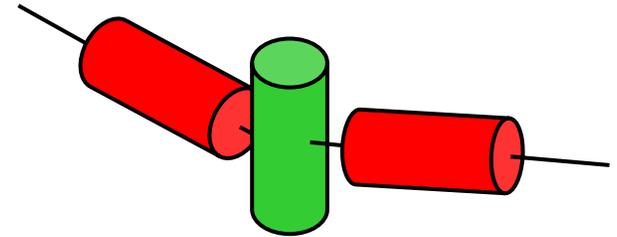
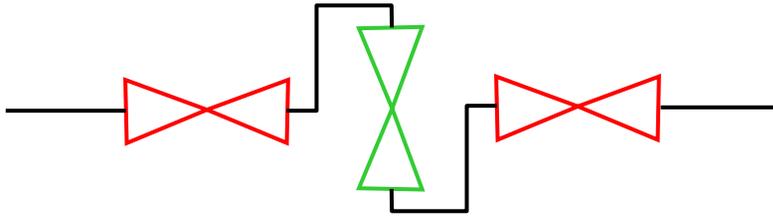
Tipi di polso robotico – 3 gdl

Per altri compiti sono necessari polsi 3R

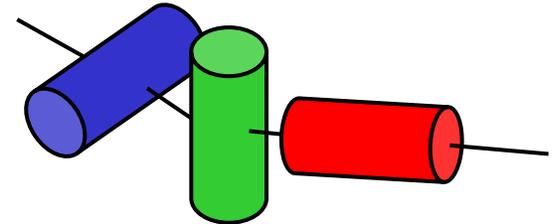
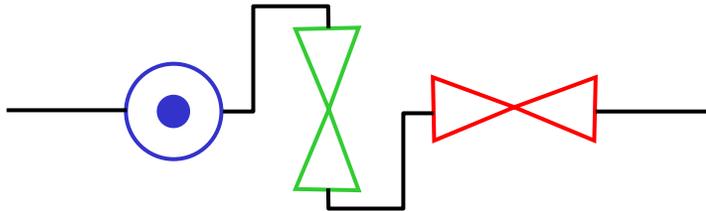


Cinematica dei Polsi

- Polso "euleriano" 3R

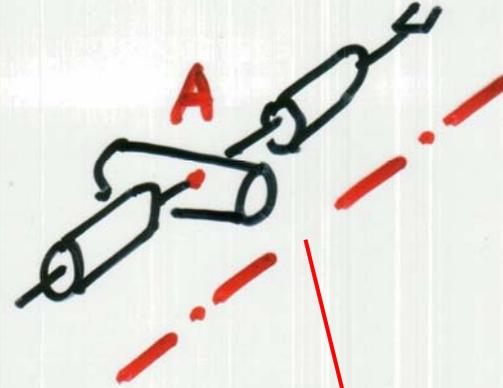
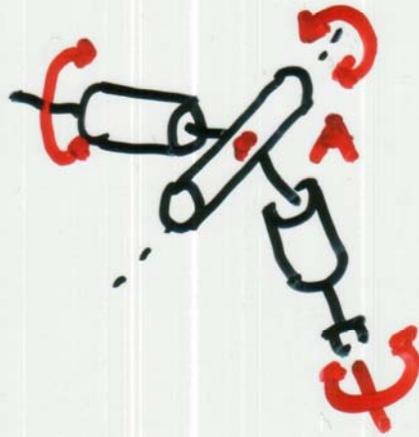


- Polso "roll-pitch-yaw" 3R



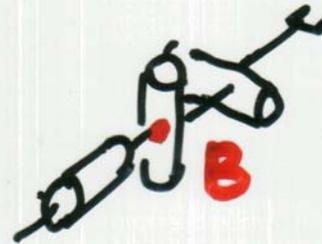
Cinematica dei Polsi

EULERIANO

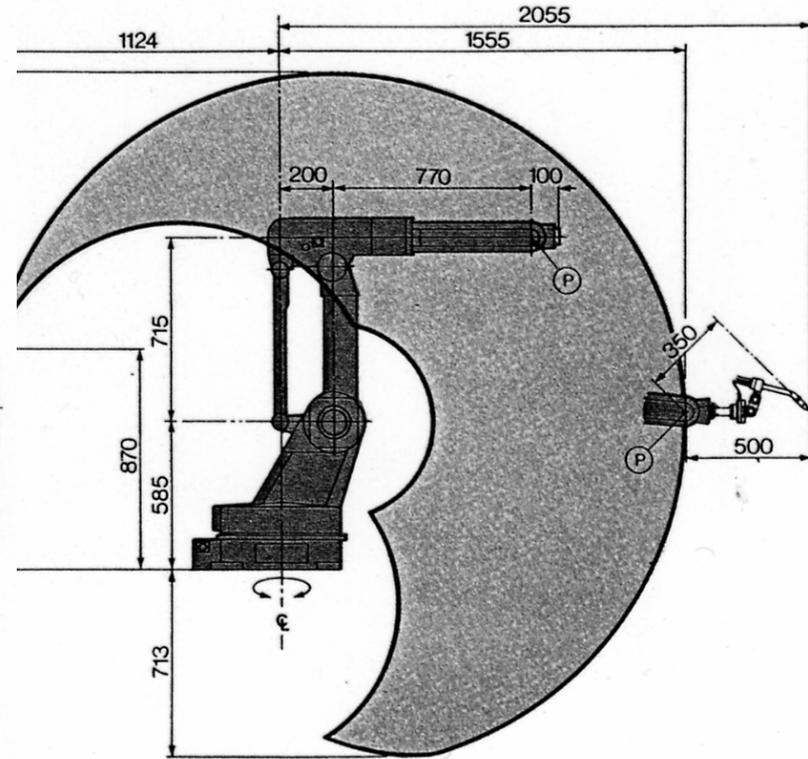
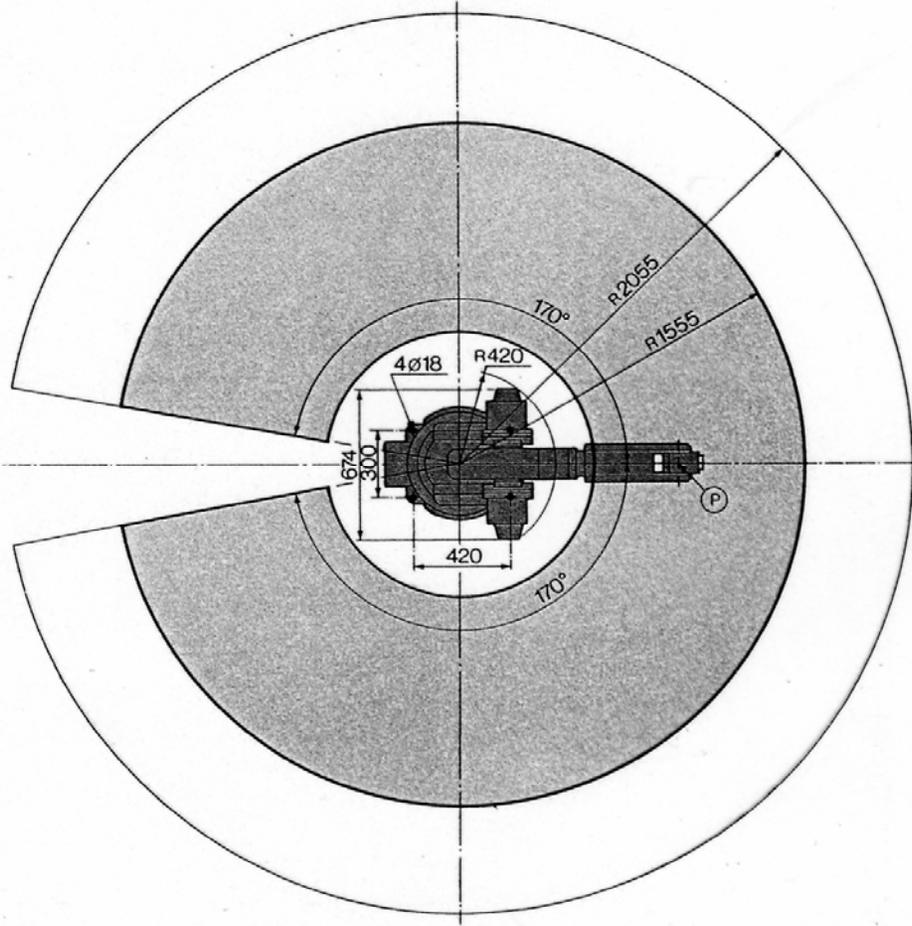


Condizione di
singolarità
Allineamento
degli assi

ROLL - PITCH - YAW



Spazio di lavoro o "operativo"



Un robot reale è mosso dai giunti

