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This text offers a clear presentation of the principles of engineering mechanics: each concept is presented as it relates to the fundamental principles on which all mechanics is based. The text contains a large number of actual engineering problems to develop and encourage the understanding of important concepts. These examples and problems are presented in both SI and Imperial units and the notation is primarily vector with a limited amount of scalar. This edition combines coverage of both statics and dynamics but is also available in two separate volumes.

Plesha, Gray, and Costanzo's "Engineering Mechanics: Dynamics" presents the fundamental concepts clearly, in a modern context, using applications and pedagogical devices that connect with today's students.

Intended as an introduction to robot mechanics for students of mechanical, industrial, electrical, and bio-mechanical engineering, this graduate text presents a wide range of approaches and topics. It avoids formalism and proofs but nonetheless discusses advanced concepts and contemporary applications. It will thus also be of interest to practicing engineers. The book begins with kinematics, emphasizing an approach based on rigid-body displacements instead of coordinate transformations; it then turns to inverse kinematic analysis, presenting the widely used Pieper-Roth and zero-reference-position methods. This is followed by a discussion of workplace characterization and determination. One focus of the discussion is the motion made possible by sperical and other novel wrist designs. The text concludes with a brief discussion of dynamics and control. An extensive bibliography provides access to the current literature.

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