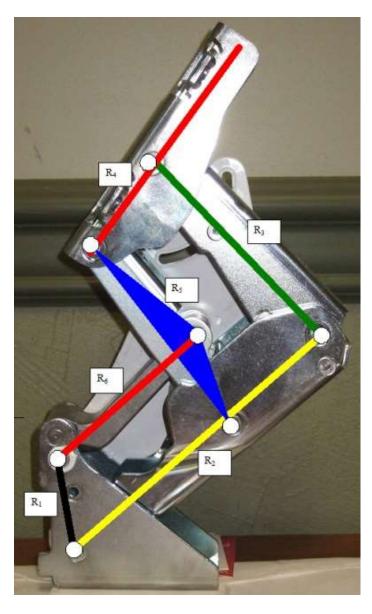
An Atlas of Structures, Mechanisms, and Robots

Dr. Bob Williams, williar4@ohio.edu

Mechanical Engineering, Ohio University

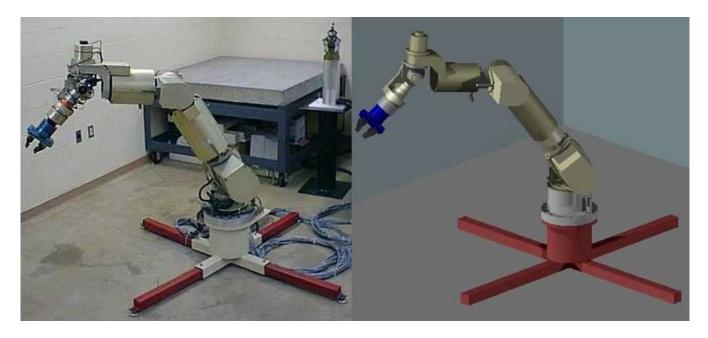
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Hettich Hinge Watt I 6-bar Mechanism

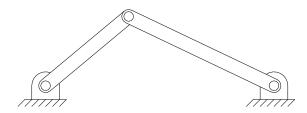
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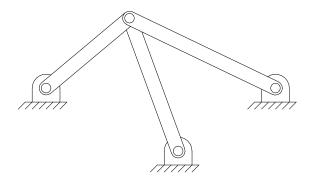


NASA 8-dof ARMII Robot

Zero-dof (or less) Structures

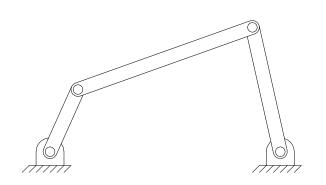


Statically Determinate Structure

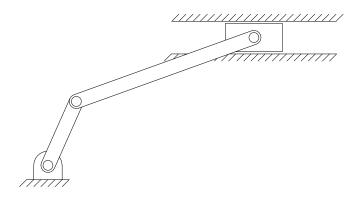


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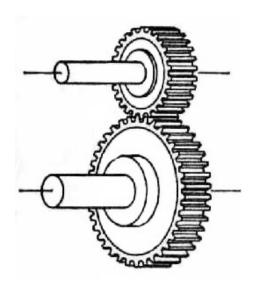
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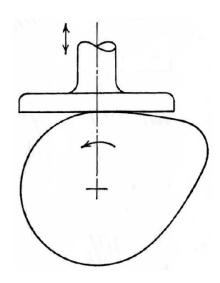
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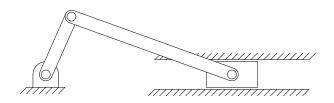


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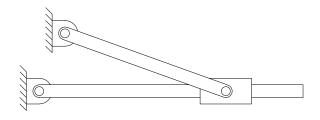


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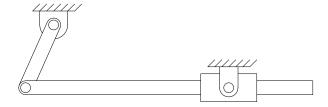
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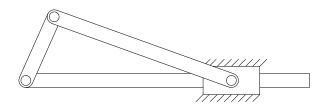
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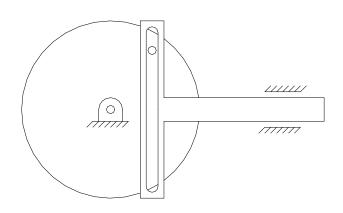


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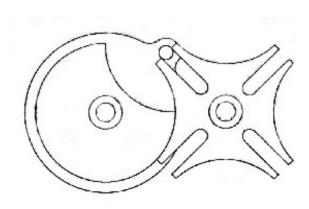


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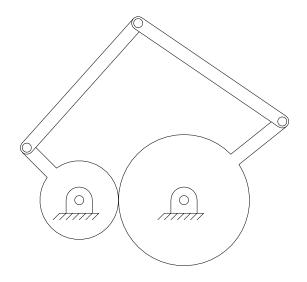


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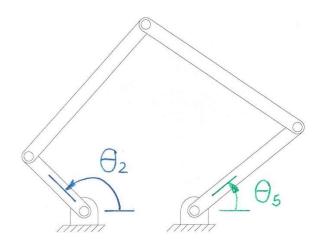


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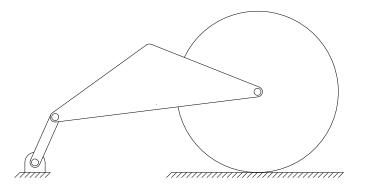
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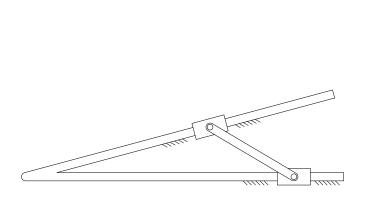
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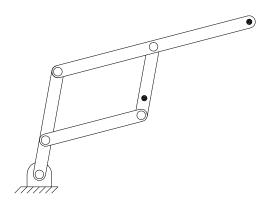
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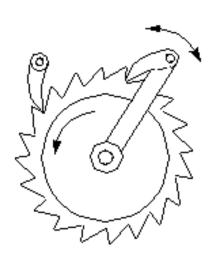
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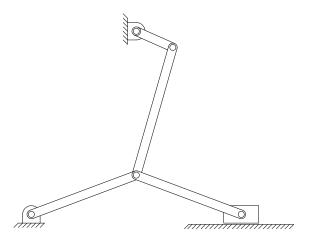
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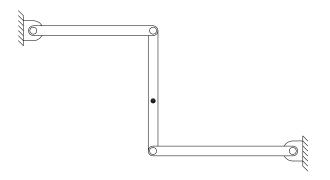


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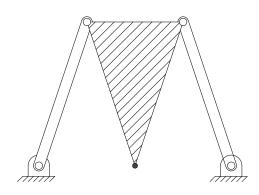


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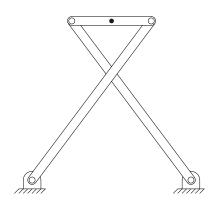
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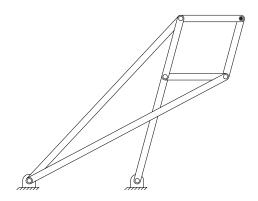
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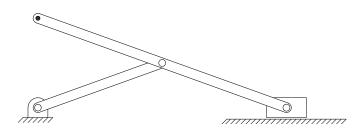
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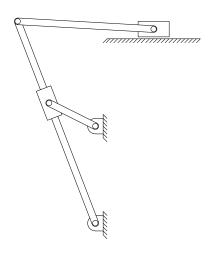


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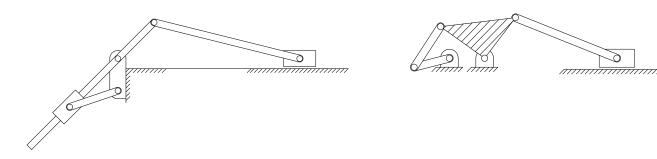


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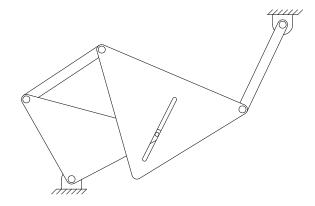


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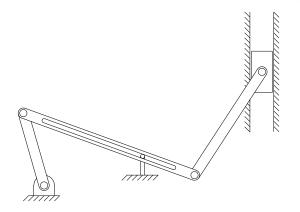


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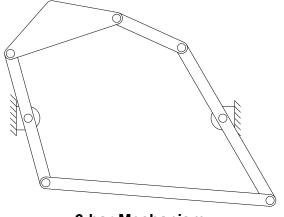
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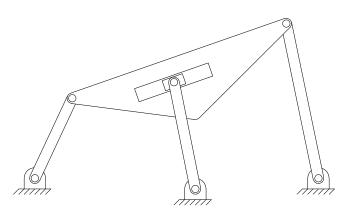
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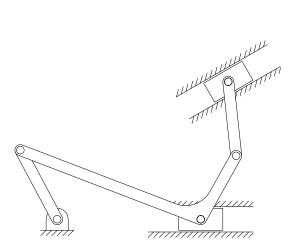
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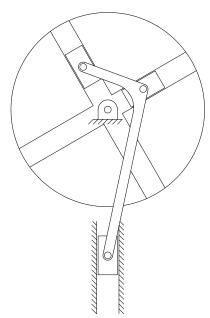
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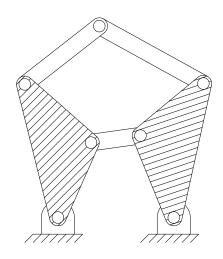


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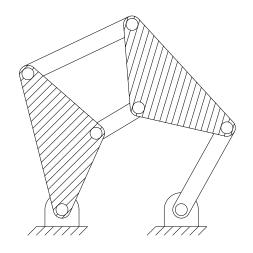


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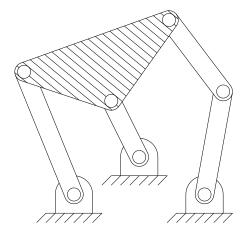
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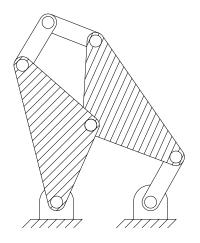
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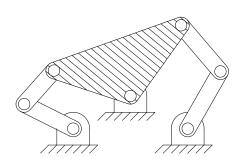
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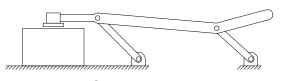


Watt I 6-Bar Mechanism

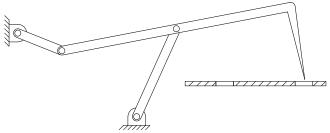


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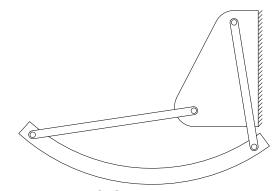
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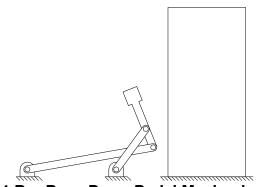
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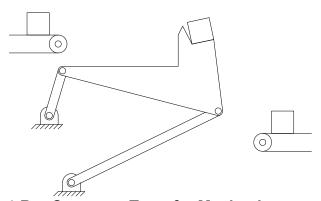
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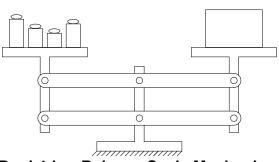
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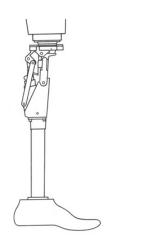
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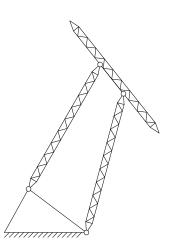
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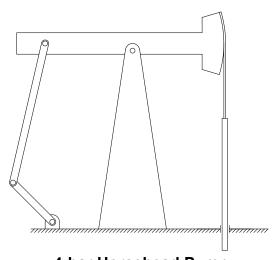
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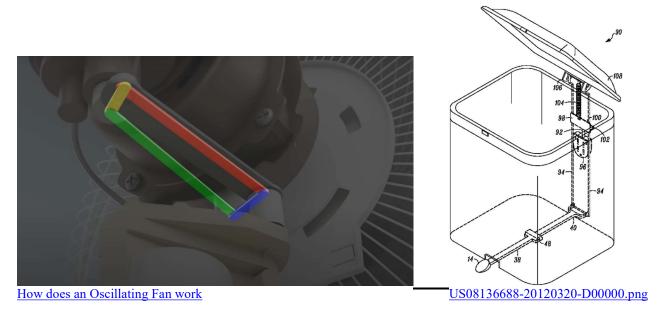


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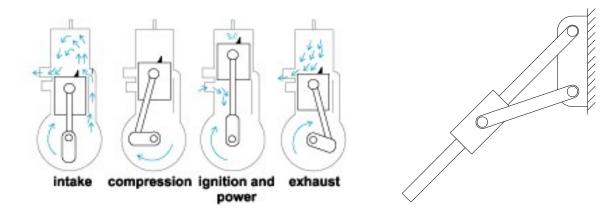
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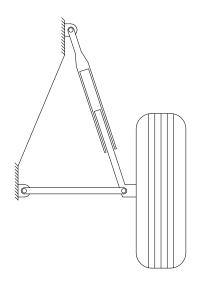


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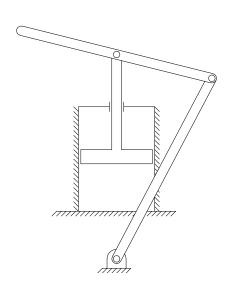
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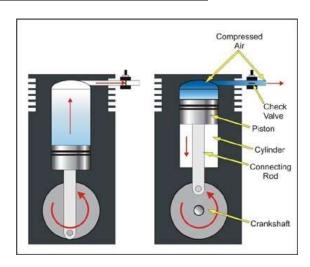


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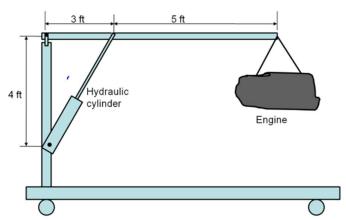


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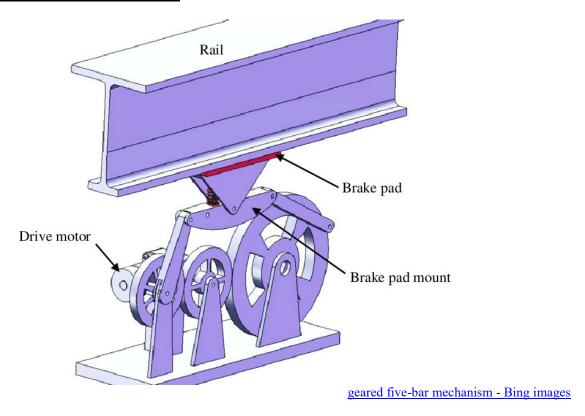
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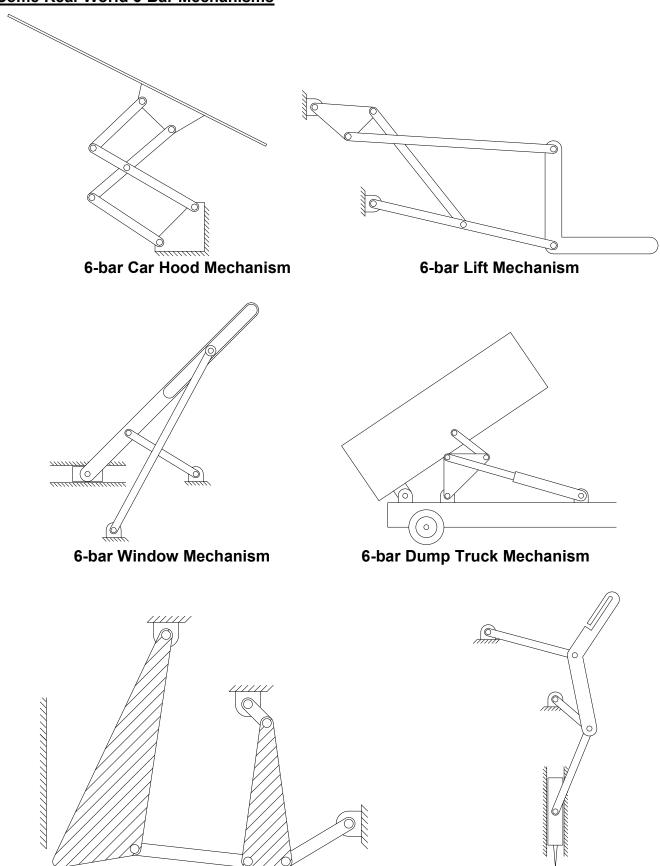
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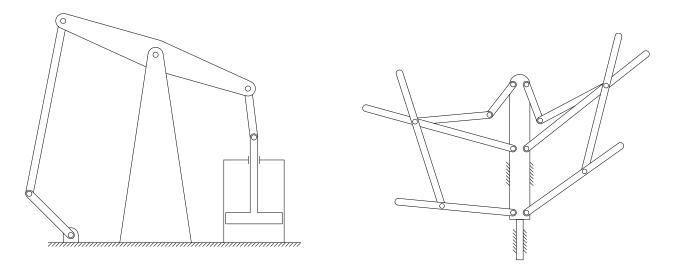
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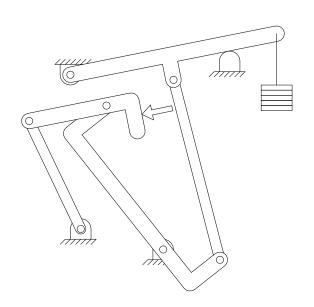
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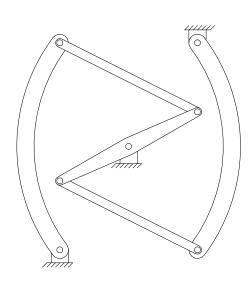


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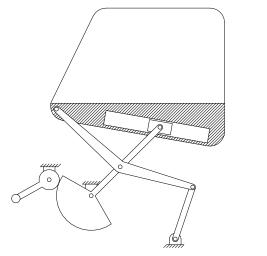


6-bar Leg Press Mechanism

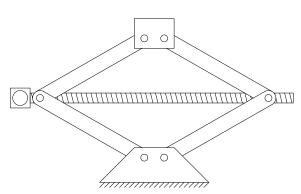


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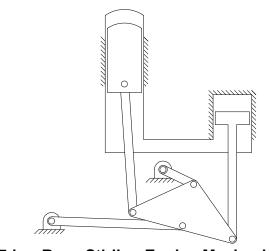
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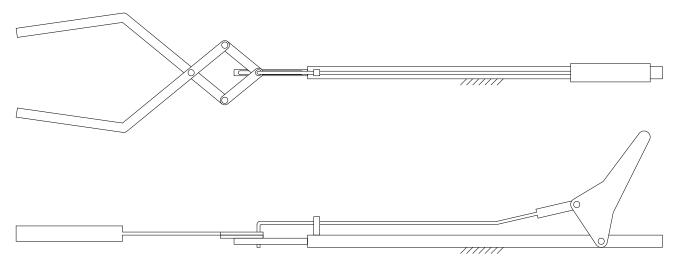
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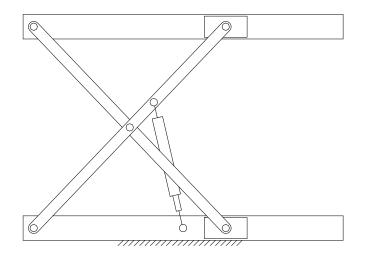


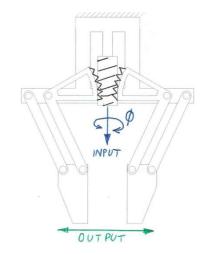
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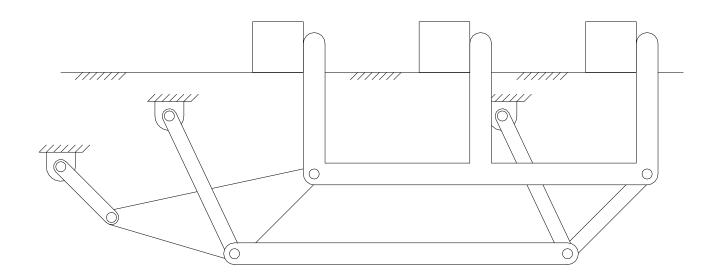
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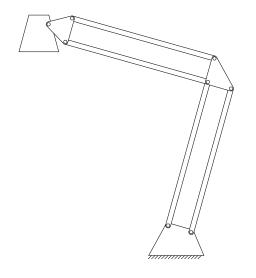
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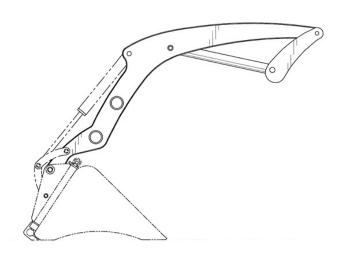


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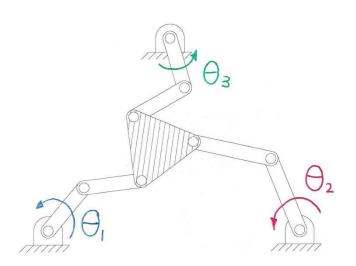
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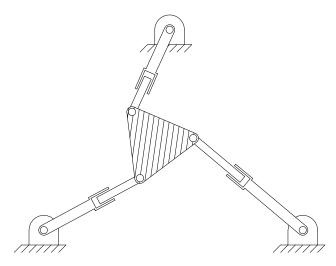
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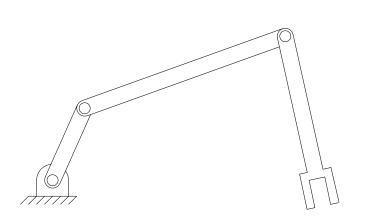
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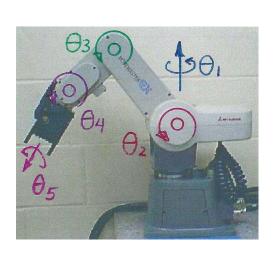
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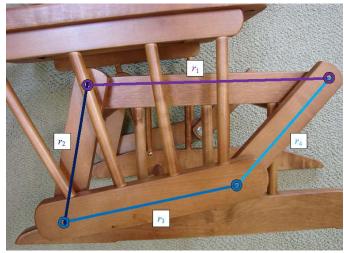


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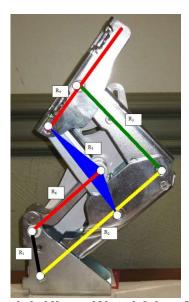
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Bicycle/Human Leg 4-bar Mechanism (lock ankle)



Hettich Hinge Watt I 6-bar Mechanism

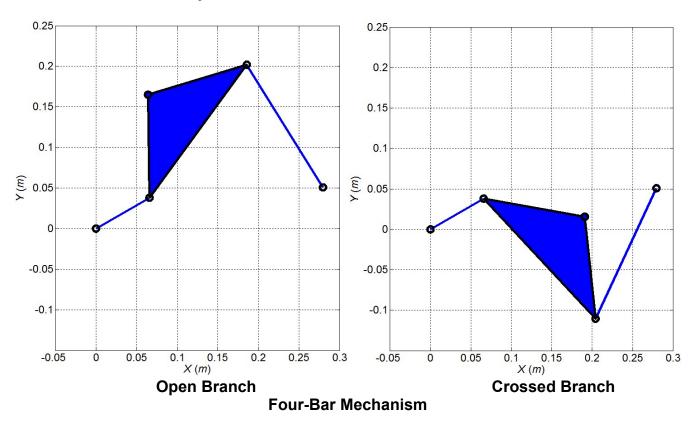


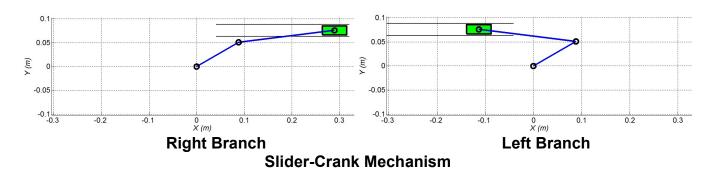
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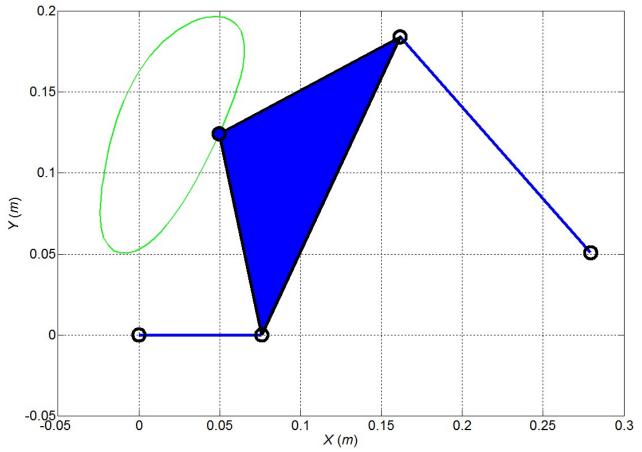
MATLAB Simulation/Animation Gallery

All of the following MATLAB graphics/animations were created by Dr. Bob at Ohio University. These are presented according to the Ohio University course they support.

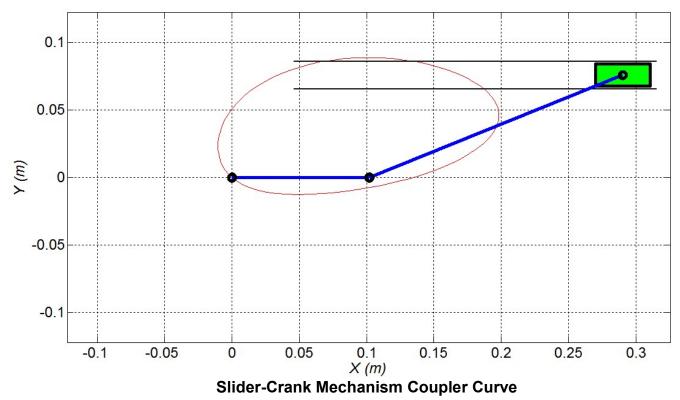
ME 3011 Kinematics & Dynamics of Machines and Introduction to Vibrations

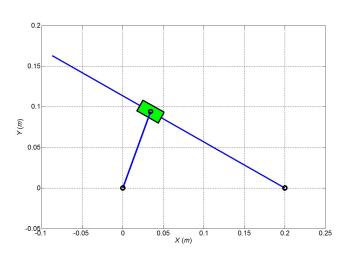


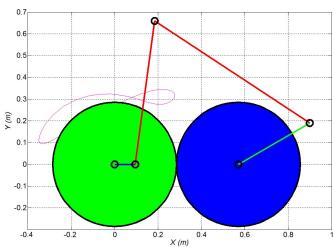






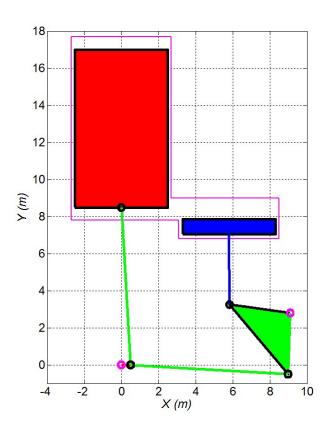


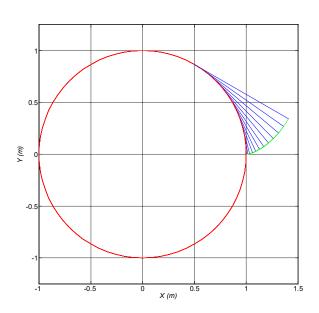




Slider-Crank Mechanism, Inversion 2

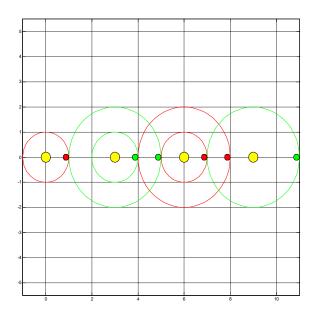
Geared Five-Bar Mechanism

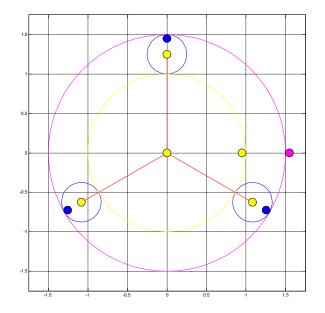




Ross-Yoke Stirling Engine Mechanism

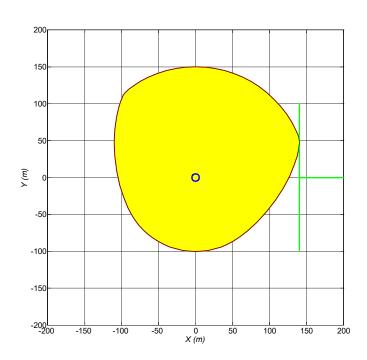
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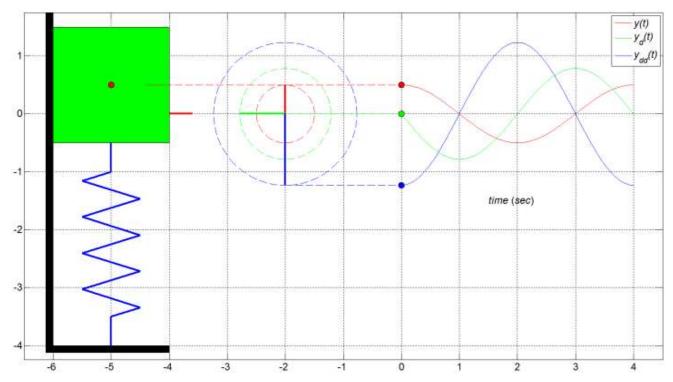
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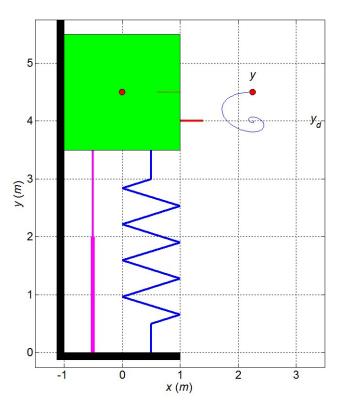


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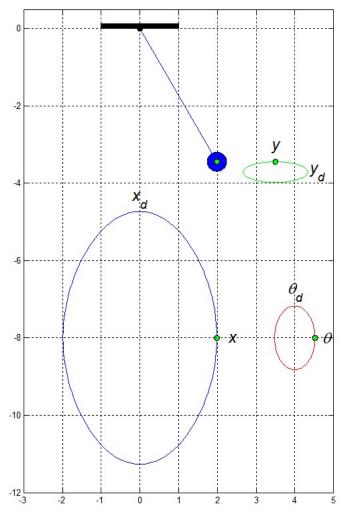
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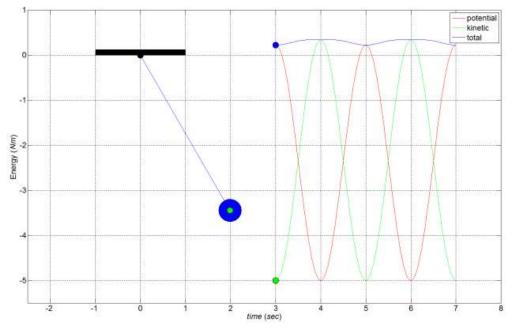
1-dof m-k Vibrational System, Undamped Simple Harmonic Motion, Rotating Phasors



1-dof m-k Vibrational System, Underdamped Response with Phase Plot

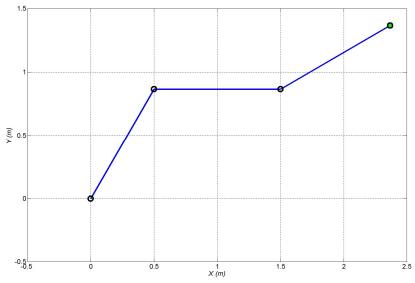


1-dof Pendulum Vibrational System, Simple Harmonic Motion with Phase Plots

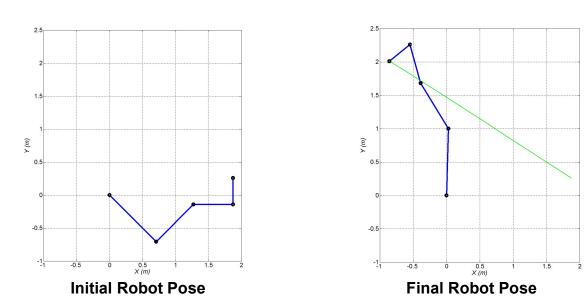


1-dof Pendulum Vibrational System, Simple Harmonic Motion with Energy Plot

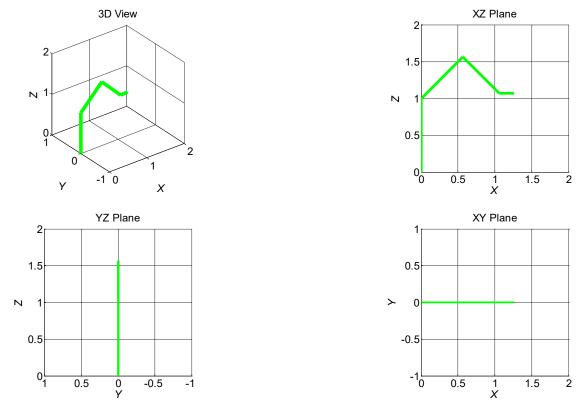
ME 4290/5290 Mechanics of Robotic Manipulators



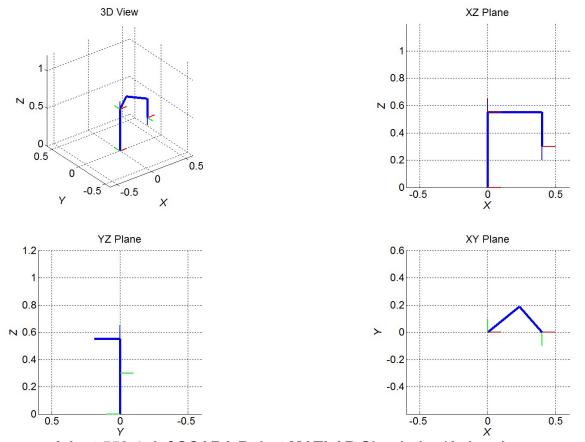
Planar 3R robot snapshot



Planar 4R Kinematically-Redundant Robot Resolved-Rate Control Simulation

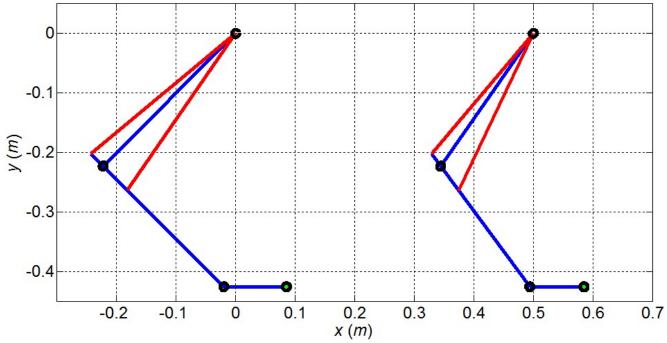


Spatial 4R Kinematically-Redundant Robot Resolved-Rate Control Simulation

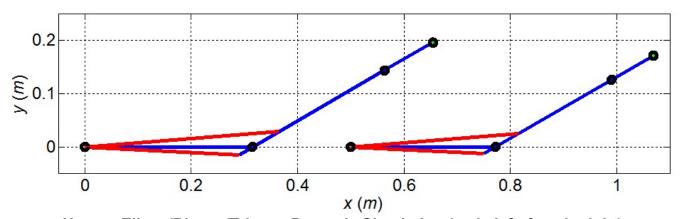


Adept 550 4-dof SCARA Robot MATLAB Simulation/Animation

ME 4670 / BME 5670 Biomechanics of Human Motion



Inverse Pose Kinematics Snapshot (male left, female right)



Human Elbow/Biceps/Triceps Dynamic Simulation (male left, female right)