

Table of contents

Abstract	I
ACKNOWLEDGMENT	V
NOTATIONS	VI
TERMINOLOGIES	IX
Chapter One	1
1. Introduction.....	1
1.1. Mechanical structures for mobile robots	3
1.1.1. Manipulation system	6
1.1.2. Locomotion system.....	9
1.2. Stability criterion	12
1.2.1. Static stability margin	13
1.2.2. Previous work on static stability	15
1.2.3. Dynamic stability margin.....	18
1.2.4. Previous work on dynamic stability	19
1.3. Computational kinematics and dynamics.....	25
Chapter Two	33
2. Kinematics of the rover.....	33
2.1. Coordinate frames.....	34
2.2. Denavit-Hartenburg parameters	38
2.3. Homogeneous transformation:.....	41
2.4. Forward kinematics	42
2.5. Base frame	45
2.6. Platform frame.....	47
2.7. Wheel kinematics	49
2.8. Platform kinematics	53
2.9. Platform universal frame	57
2.9.1. Attitude angles	62
2.10. Rover transform graph.....	83
2.10.1. Ground universal frame	83
2.10.2. Universal wheel frame.....	86
2.10.3. Surface geometries	91
Chapter Three	94
3. Computational Dynamics	94
3.1. Dynamic equations of motion	94
3.2. Output generalized coordinates.....	96
3.3. Newton-Euler Recursive Relations.....	98

3.3.1.	Forward recursion.....	99
3.3.2.	Backward recursion.....	112
Chapter Four.....		118
4.	System forces and moments.....	118
4.1.1.	System weight.....	118
4.1.2.	Normal force.....	120
4.1.3.	Frictional force.....	123
4.1.4.	Wheeled motor torque.....	124
4.1.5.	Constraints.....	135
Chapter Five.....		137
5.	Results and discussion.....	137
Chapter Six.....		179
6.	Conclusion.....	179
References.....		183
Appendices.....		192
Appendix A: Denavit-Hartenburg Convention.....		192
Appendix B: Inverse kinematics.....		196
Appendix C: Kinematic and dynamic parameters.....		207
Appendix D: Newton-Euler Recursive Formulation.....		216
Appendix E: Free-Body Diagram for four manipulators.....		221
Appendix F: Universal forces and moments.....		227
Matlab Code.....		231