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Materias:

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Publicaciones:

Editor asociado:

Mathematical Problems in Engineering

Advances in Robotics Research

Libro:

Gallardo-Alvarado, J., 2016, *Kinematic Analysis of Parallel Manipulators by Algebraic Screw Theory*. Springer International Publishing Switzerland, ebook ISBN: 978-3-319-31124-1, hardcover ISBN: 978-3-319-31126-5, ISBN10 : 3319311263 , ISBN13 : 9783319311265, páginas 377, doi: 10.1007/978-3-319-31126-5

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Gallardo-Alvarado, J., 2020, A Gough-Stewart parallel manipulator with configurable platform and multiple end-effectors, *Meccanica* 55(3), 597-613, doi: 10.1007/s11012-020-01136-y

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Capítulos de libro:

J. Gallardo-Alvarado, M.H. Abedinnasab, R. Rodríguez-Castro, C.R. Aguilar-Nájera, Kinematics of a Series-parallel Manipulator with Constrained Rotations by Means of the Theory of Screws, in: *Advances in Engineering Research*, Volume 15, Victoria M. Petrova (ed.), Nova Science Publishers, 2017, pp. 71-106, ISBN: 978-1-53610-071-6 (eBook), ISSN: 2163-3932, ISBN: 978-1-53610-057-0 (Chapter 4)

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J. Gallardo-Alvarado, M.A. García-Murillo, Rigid Body Hyper-jerk Analysis Using Screw Theory, in: *Multibody Mechatronic Systems, Mechanisms and Machine Science*, Vol. 25, M. Ceccarelli and E.E. Hernández-Martínez (eds.), Springer, 2015, pp. 411-422, ISBN: 978-3-319-09857-9, doi: [10.1007/978-3-319-09858-6_39](https://doi.org/10.1007/978-3-319-09858-6_39)

M.A. Garcia-Murillo, Y. Takeda, E. Castillo-Casataneda, D. Matsuura, S. Kawasumi, J. Gallardo-Alvarado, Kinematics and Dynamics of a 3-RPSR Parallel Robot Used as a Pipe-Bending Machine, in: *Advances in Robot Kinematics 2014*, J. Lenarcic and O. Khatib (eds.), Springer, 2014, pp. 307-316, ISBN: 978-3-319-06697-4, doi: [10.1007/978-3-319-06698-1_32](https://doi.org/10.1007/978-3-319-06698-1_32)

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