

參考文獻

- [1] Lung-Wen Tsai, Robot Analysis : The Mechanics of Serial and Parallel Manipulators, Department of Mechanical Engineering and Institute for Systems Research University of Maryland, 1999.
- [2] 晉茂林，機器人學，國立編譯館，台北，中華民國八十九年二月。
- [3] Chia-Yu E. Wang, Wojciech K. Timoszyk, and James E. Bobrow, “Payload Maximization for Open Chained Manipulators : Finding Weightlifting Motions for a Puma 762 Robot,” IEEE Transactions on Robotics and Automation, vol.17, No. 2, April 2001.
- [4] Michael T. Rosenstein and Andrew G. Barto, “Robot Weightlifting By Direct Policy Search”, Department of Computer Science University of Massachusetts Amherst, 2003.
- [5] Michael T. Rosenstein, “learning to exploit dynamics for robot motor coordination”, the Graduate School of the University of Massachusetts Amherst, May 2003.
- [6] E. W. Dijkstra, “A note on two problems in connection with graphs”, Numerische Mathematik, 1:269-271, 1959.
- [7] Stuart Russell and Peter Norvig, Artificial Intelligence: A Modern Approach, Department of Electrical Engineering and Computer Sciences University of California Berkeley, 2002.
- [8] <http://theory.stanford.edu/~amitp/GameProgramming/>
- [9] Pi-Ying Cheng, Der-Chin Liu, “The Shortest Path Planning for Robot on a 3D Obstacle”, Proceedings of International Conference of the Automation, 2003.
- [10] Kunwoo Lee, Principles of CAD/CAM/CAE systems, Seoul National University, 1999.
- [11] 李明威，「無人車之B-樣條曲線路徑規劃與控制」，碩士論文，國立台灣大學應用力學所，中華民國九十一年六月。
- [12] Richard S. Wright, Jr. and Michael Sweet, OpenGL SuperBible Second Edition, GOTOP Information Inc., September 1999.
- [13] James E. Bobrow & Garrett A. Sohl, “On the Reliable Computation of Optimal Motions for Underactuated Manipulators,” Department of Mechanical and Aerospace Engineering University of California, Irvine, CA 92697.
- [14] Jun Morimoto and Kenji Doya, “Reinforcement learning of dynamic motor sequence: Learning to stand up”, Proceedings of the 1998 IEEE/RSJ, pp.1721-1726, Intl Conference on Intelligent Robots and Systems Victoria, B.C.,Canada, October 1998.

- [15] Gavin Simmons and Yiannis Demiris. "Biologically Inspired Optimal Robot Arm Control with Signal-Dependent Noise", Department of Electrical and Electronic Engineering, Imperial College London, 2003.
- [16] Masaki Ogino, Koh Hosoda and Minoru Asada. "Learning Energy Efficient Walking with Ballistic Walking", Dept. of Adaptive Machine Systems, Graduate School of Engineering, Osaka University, Suita, Osaka, Japan, 2002.
- [17] Jasbir S. Arora, Introduction to Optimum Design, McGraw Hill, Inc. 1989.
- [18] 戴汝為、黃英哲，科技大浪潮-人工智慧，五南圖書出版公司，台北，西元2003年1月。
- [19] Elaine Rich著，人工智慧，張怡婷譯，全欣書局，台北，民國七十七年。
- [20] Steven C. Chapra and Raymond P. Canale著，工程數值方法，鄭明哲譯，全華書局，台北市，民國八十一年。
- [21] Conte, S. D. and Boor, Carl de著，初等數值分析，李基禎譯，東華書局，台北市，民國八十一年。
- [22] 位元文化，C/C++入門進階，文魁資訊，台北，西元2003年5月。
- [23] 查厚錦，「機器手臂之運動軌跡規劃與力量控制研究」，碩士論文，私立中原大學機械工程學系，中華民國八十九年七月。
- [24] 吳政昌，「結合力及視覺回授之機械手臂姿態控制」，碩士論文，國立東華大學電機工程學系，中華民國九十年七月。
- [25] 吳建興，「3D網格圖最短路徑規劃」，碩士論文，國立海洋大學電機工程學系，中華民國八十八年六月。
- [26] 劉惟信，機械最佳化設計，二版，全華科技圖書股份有限公司，台北，中華民國八十五年九月。