

## Robot Welding Trajectory Planning Using Screw Theory

Comprehensive Materials Processing provides students and professionals with a one-stop resource consolidating and enhancing the literature of the materials processing and manufacturing universe. It provides authoritative analysis of all processes, technologies, and techniques for converting industrial materials from a raw state into finished parts or products. Assisting scientists and engineers in the selection, design, and use of materials, whether in the lab or in industry, it matches the adaptive complexity of emergent materials and processing technologies. Extensive traditional article-level academic discussion of core theories and applications is supplemented by applied case studies and advanced multimedia features. Coverage encompasses the general categories of solidification, powder, deposition, and deformation processing, and includes discussion on plant and tool design, analysis and characterization of processing techniques, high-temperatures studies, and the influence of process scale on component characteristics and behavior. Authored and reviewed by world-class academic and industrial specialists in each subject field Practical tools such as integrated case studies, user-defined process schemata, and multimedia modeling and functionality Maximizes research efficiency by collating the most important and established information in one place with integrated applets linking to relevant outside sources

After a long period, in which the research focused mainly on industrial robotics, nowadays scientists aim to build machines able to act autonomously in unstructured domains, and to interface friendly with humans, while performing intelligently their assigned tasks. Such intelligent autonomous systems are now being intensively developed, and are ready to be applied to every field, from social life to modern enterprises. We believe the following years will be increasingly characterised by their extensive use. This is dramatically changing the whole scenario of human society.

This book features state-of-the-art contributions from two well-established conferences: Changeable, Agile, Reconfigurable and Virtual Production Conference (CARV2020) and Mass Customization and Personalization Conference (MCPC2020). Together, they focus on the joint design, development, and management of products, production systems, and business for sustainable customization and personalization. The book covers a large range of topics within this domain, ranging from industrial success factors to original contributions within the field.

Mobile robotics is a challenging field with great potential. It covers disciplines including electrical engineering, mechanical engineering, computer science, cognitive science, and social science. It is essential to the design of automated robots, in combination with artificial intelligence, vision, and sensor technologies. Mobile robots are widely used for surveillance, guidance, transportation and entertainment tasks, as well as medical applications. This Special Issue intends to concentrate on recent developments concerning mobile robots and the research surrounding them to enhance studies on the fundamental problems observed in the robots. Various multidisciplinary approaches and integrative contributions including navigation, learning and adaptation, networked system, biologically inspired robots and cognitive methods are welcome contributions to this Special Issue,

both from a research and an application perspective.

The inverse dynamics problem was developed in order to provide researchers with the state of the art in inverse problems for dynamic and vibrational systems. Contrasted with a forward problem, which solves for the system output in a straightforward manner, an inverse problem searches for the system input through a procedure contaminated with errors and uncertainties. An inverse problem, with a focus on structural dynamics, determines the changes made to the system and estimates the inputs, including forces and moments, to the system, utilizing measurements of structural vibration responses only. With its complex mathematical structure and need for more reliable input estimations, the inverse problem is still a fundamental subject of research among mathematicians and engineering scientists. This book contains 11 articles that touch upon various aspects of inverse dynamic problems.

This master's thesis presents a novel approach to finding trajectories with minimal end time for kinematically redundant manipulators. Emphasis is given to a general applicability of the developed method to industrial tasks such as gluing or welding. Minimum-time trajectories may yield economic advantages as a shorter trajectory duration results in a lower task cycle time. Whereas kinematically redundant manipulators possess increased dexterity, compared to conventional non-redundant manipulators, their inverse kinematics is not unique and requires further treatment. In this work a joint space decomposition approach is introduced that takes advantage of the closed form inverse kinematics solution of non-redundant robots. Kinematic redundancy can be fully exploited to achieve minimum-time trajectories for prescribed end-effector paths.

This book highlights the latest innovations and applications in robotics, as presented by leading international researchers and engineers at the ROMANSY 2020, the 23rd CISM IFToMM Symposium on Theory and Practice of Robots and Manipulators. The ROMANSY symposium is the first established conference that focuses on robotics theory and research, rather than industrial aspects. Bringing together researchers from a broad range of countries, the symposium is held bi-annually and plays a vital role in the development of the theory and practice of robotics, as well as the mechanical sciences. ROMANSY 2020 marks the 23rd installment in a series that began in 1973. The event was also the first topic-specific conference of the IFToMM, though not exclusively intended for the IFToMM community.

Practical Motion Planning in Robotics Current Approaches and Future Directions Edited by Kamal Gupta Simon Fraser University, Burnaby, Canada Angel P. del Pobil Jaume-I University, Castellon, Spain Designed to bridge the gap between research and industry, Practical Motion Planning in Robotics brings theoretical advances to bear on real-world applications. Capitalizing on recent progress, this comprehensive study emphasizes the practical aspects of techniques for collision detection, obstacle avoidance, path planning and manipulation planning. The broad approach spans both model- and sensor-based motion planning, collision detection and geometric complexity, and future directions. Features include: - Review of state-of-the-art techniques and coverage of the main issues to be considered in the development of motion planners for use in real applications - Focus on gross motion planning for articulated arms enabling robots to perform non-contact tasks with relatively high tolerances plus brief consideration of mobile robots - The use of efficient algorithms to tackle incremental changes in the environment - Illustration of robot motion planning applications in virtual prototyping and the shipbuilding industry - Demonstration of

efficient path planners combining both local and global planning approaches in conjunction with efficient techniques for collision detection and distance computations - International contributions from academia and industry Combining theory and practice, this timely book will appeal to academic researchers and practising engineers in the fields of robotic systems, mechatronics and computer science.

Collection of selected, peer reviewed papers from the 2013 International Conference on Mechanical, Material Engineering (MME 2013), November 23-24, 2013, Shiyan, Hubei, China. Volume is indexed by Thomson Reuters CPCI-S (WoS). The 142 papers are grouped as follows: Chapter 1: Mechanical Engineering and Manufacturing Technology; Chapter 2: Materials Science and Chemical Engineering; Chapter 3: Industrial Engineering and Other Related Topics

The three volume set LNAI 10462, LNAI 10463, and LNAI 10464 constitutes the refereed proceedings of the 10th International Conference on Intelligent Robotics and Applications, ICIRA 2017, held in Wuhan, China, in August 2017. The 235 papers presented in the three volumes were carefully reviewed and selected from 310 submissions. The papers in this third volume of the set are organized in topical sections on sensors and actuators; mobile robotics and path planning; virtual reality and artificial intelligence; aerial and space robotics; mechatronics and intelligent manufacturing.

This volume is based on the proceedings of the 28th International Conference on CAD/CAM, Robotics and Factories of the Future. This book specially focuses on the positive changes made in the field of robotics, CAD/CAM and future outlook for emerging manufacturing units. Some of the important topics discussed in the conference are product development and sustainability, modeling and simulation, automation, robotics and handling systems, supply chain management and logistics, advanced manufacturing processes, human aspects in engineering activities, emerging scenarios in engineering education and training. The contents of this set of proceedings will prove useful to both researchers and practitioners.

The present surge of interest in robotics can be expected to continue through the 1980s. Major research efforts are springing up throughout industry and in the universities. Senior and graduate level courses are being developed or planned in many places to prepare students to contribute to the development of the field and its industrial applications. Robot Motion will serve this emerging audience as a single source of information on current research in the field. The book brings together nineteen papers of fundamental importance to the development of a science of robotics. These are grouped in five sections: Dynamics; Trajectory Planning; Compliance and Force Control; Feedback Control; and Spatial Planning. Each section is introduced by a substantial analytical survey that lays out the problems that arise in that area of robotics and the approaches and solutions that have been tried, with an evaluation of their strengths and shortcomings. In addition, there is an overall introduction that relates robotics research to general trends in the development of artificial intelligence. Individual papers are the work of H. Hanafusa, H. Asada, N. Hogan, M. T. Mason, R. Paul, B. Shimano, M. H. Raibert, J. J. Craig, R. H. Taylor, D. E. Whitney, J. M. Hollerbach, J. Luh, M. Walker, R. J. Popplestone, A. P. Ambler, I. M. Bellos, T. Lozano Perez, E. Freund, D. F. Golla, S. C. Garg, P. C. Hughes, and K. D. Young. The editors are all research scientists at MIT's Artificial Intelligence Laboratory and in addition, Michael Brady is coeditor with Richard Paul of The International Journal of Robotics Research. Robot Motion is included in the MIT Press Artificial Intelligence Series.

ECWAC2012 is an integrated conference devoted to Electronic Commerce, Web Application and Communication. In this proceedings you can find the carefully reviewed scientific outcome of the second International Conference on Electronic Commerce, Web Application and Communication (ECWAC 2012) held at March 17-18, 2012 in Wuhan, China, bringing together researchers from all around the world in the field.

The three-volume set CCIS 761, CCIS 762, and CCIS 763 constitutes the thoroughly refereed proceedings of the International Conference on Life System Modeling and Simulation, LSMS 2017, and of the International Conference on Intelligent Computing for Sustainable Energy and Environment, ICSEE 2017, held in Nanjing, China, in September 2017. The 208 revised full papers presented were carefully reviewed and selected from over 625 submissions. The papers of this volume are organized in topical sections on: Biomedical Signal Processing; Computational Methods in Organism Modeling; Medical Apparatus and Clinical Applications; Bionics Control Methods, Algorithms and Apparatus; Modeling and Simulation of Life Systems; Data Driven Analysis; Image and Video Processing; Advanced Fuzzy and Neural Network Theory and Algorithms; Advanced Evolutionary Methods and Applications; Advanced Machine Learning Methods and Applications; Intelligent Modeling, Monitoring, and Control of Complex Nonlinear Systems; Advanced Methods for Networked Systems; Control and Analysis of Transportation Systems; Advanced Sliding Mode Control and Applications; Advanced Analysis of New Materials and Devices; Computational Intelligence in Utilization of Clean and Renewable Energy Resources; Intelligent Methods for Energy Saving and Pollution Reduction; Intelligent Methods in Developing Electric Vehicles, Engines and Equipment; Intelligent Computing and Control in Power Systems; Modeling, Simulation and Control in Smart Grid and Microgrid; Optimization Methods; Computational Methods for Sustainable Environment. These are the Proceedings of the 6th International Symposium on Multibody Systems and Mechatronics (MUSME 2017) which was held in Florianópolis, Brazil, October 24-28, 2017. Topics addressed include analysis and synthesis of mechanisms; dynamics of multibody systems; design algorithms for mechatronic systems; simulation procedures and results; prototypes and their performance; robots and micromachines; experimental validations; theory of mechatronic simulation; mechatronic systems; and control of mechatronic systems. The MUSME 2017 Symposium was one of the activities of the FEIbIM Commission for Mechatronics and IFToMM technical Committees for Multibody Dynamics, Robotics and Mechatronics.

Robot Systems for Rail Transit Applications presents the latest advances in robotics and artificial intelligence for railway systems, giving foundational principles and running through special problems in robot systems for rail transit. State-of-the art research in robotics and railway systems is presented alongside a series of real-world examples. Eight chapters give definitions and characteristics of rail transit robot systems, describe assembly and collaborative robots in manufacturing, introduce automated guided vehicles and autonomous rail rapid transit, demonstrate inspection robots, cover trench robots, and explain unmanned aerial vehicles. This book offers an integrated and highly-practical way to approach robotics and artificial intelligence in rail-transit.

Introduces robot and artificial intelligence (AI) systems for rail transit applications Presents research alongside step-by-step coverage of real-world cases Gives the theoretical foundations underlying practical application Offers solutions for high-speed railways from the latest work in robotics Shows how robotics and AI systems afford new and efficient methods in rail transit This book contains papers presented at the International Conference on Cognitive based Information Processing and Applications (CIPA) held during August 21, 2021, online conference (since COVID 19), which is divided into a 2-volume book. The papers in the first volume represent the various technological advancements in network information processing, graphics and image processing, medical care, machine learning, smart cities. It caters to postgraduate students, researchers, and practitioners specializing and working in the area of cognitive-inspired computing and information processing.

This book includes the volume 1 of the proceedings of the 2012 International Conference on Mechanical and Electronic Engineering(ICMEE2012), held at June 23-24,2012 in Hefei, China. The conference provided a rare opportunity to bring together worldwide researchers who are working in the fields. This volume 1 is focusing on Mechanical Engineering and Automation as well as Vehicle Engineering and Technology.

Robotic welding systems have been used in different types of manufacturing. They can provide several benefits in welding applications. The most prominent advantages of robotic welding are precision and productivity. Another benefit is that labor costs can be reduced. Robotic welding also reduces risk by moving the human welder/operator away from hazardous fumes and molten metal close to the welding arc. The robotic welding system usually involves measuring and identifying the component to be welded, we- ing it in position, controlling the welding parameters and documenting the produced welds. However, traditional robotic welding systems rely heavily upon human interv- tion. It does not seem that the traditional robotic welding techniques by themselves can cope well with uncertainties in the welding surroundings and conditions, e. g. variation of weld pool dynamics, fluxion, solid, weld torch, and etc. On the other hand, the advent of intelligent techniques provides us with a powerful tool for solving demanding re- world problems with uncertain and unpredictable environments. Therefore, it is intere- ing to gather current trends and to provide a high quality forum for engineers and researchers working in the filed of intelligent techniques for robotic welding systems. This volume brings together a broad range of invited and contributed papers that describe recent progress in this field.

The volume set LNAI 11740 until LNAI 11745 constitutes the proceedings of the 12th International Conference on Intelligent Robotics and Applications, ICIRA 2019, held in Shenyang, China, in August 2019. The total of 378 full and 25 short papers presented in these proceedings was carefully reviewed and selected from 522 submissions. The papers are organized in topical sections as follows: Part I: collective and social robots; human biomechanics and human-centered robotics; robotics for cell manipulation and characterization; field robots; compliant mechanisms; robotic grasping and manipulation with incomplete information and strong disturbance; human-centered robotics; development of high-performance joint drive for robots; modular robots and other mechatronic systems; compliant manipulation learning and control for lightweight robot. Part II: power-assisted system and control; bio-inspired wall climbing robot; underwater acoustic and optical signal processing for environmental cognition; piezoelectric actuators and micro-nano manipulations; robot vision and scene understanding; visual and motional learning in robotics; signal processing and underwater bionic robots; soft locomotion robot; teleoperation robot; autonomous control of unmanned aircraft systems. Part III: marine bio-inspired robotics and soft robotics: materials, mechanisms, modelling, and control; robot intelligence technologies and system integration; continuum mechanisms and robots; unmanned underwater vehicles; intelligent robots for environment detection or fine manipulation; parallel robotics; human-robot collaboration; swarm intelligence and multi-robot cooperation; adaptive and learning control system; wearable and assistive devices and robots for healthcare; nonlinear systems and control. Part IV: swarm intelligence unmanned system; computational intelligence inspired robot

navigation and SLAM; fuzzy modelling for automation, control, and robotics; development of ultra-thin-film, flexible sensors, and tactile sensation; robotic technology for deep space exploration; wearable sensing based limb motor function rehabilitation; pattern recognition and machine learning; navigation/localization. Part V: robot legged locomotion; advanced measurement and machine vision system; man-machine interactions; fault detection, testing and diagnosis; estimation and identification; mobile robots and intelligent autonomous systems; robotic vision, recognition and reconstruction; robot mechanism and design. Part VI: robot motion analysis and planning; robot design, development and control; medical robot; robot intelligence, learning and linguistics; motion control; computer integrated manufacturing; robot cooperation; virtual and augmented reality; education in mechatronics engineering; robotic drilling and sampling technology; automotive systems; mechatronics in energy systems; human-robot interaction.

Proceedings of the 2015 Chinese Intelligent Automation Conference presents selected research papers from the CIAC'15, held in Fuzhou, China. The topics include adaptive control, fuzzy control, neural network based control, knowledge based control, hybrid intelligent control, learning control, evolutionary mechanism based control, multi-sensor integration, failure diagnosis, reconfigurable control, etc. Engineers and researchers from academia, industry and the government can gain valuable insights into interdisciplinary solutions in the field of intelligent automation.

This book presents the most recent research advances in robot manipulators. It offers a complete survey to the kinematic and dynamic modelling, simulation, computer vision, software engineering, optimization and design of control algorithms applied for robotic systems. It is devoted for a large scale of applications, such as manufacturing, manipulation, medicine and automation. Several control methods are included such as optimal, adaptive, robust, force, fuzzy and neural network control strategies. The trajectory planning is discussed in details for point-to-point and path motions control. The results in obtained in this book are expected to be of great interest for researchers, engineers, scientists and students, in engineering studies and industrial sectors related to robot modelling, design, control, and application. The book also details theoretical, mathematical and practical requirements for mathematicians and control engineers. It surveys recent techniques in modelling, computer simulation and implementation of advanced and intelligent controllers.

The two volume sets LNCS 8033 and 8034 constitutes the refereed proceedings of the 9th International Symposium on Visual Computing, ISVC 2013, held in Rethymnon, Crete, Greece, in July 2013. The 63 revised full papers and 35 poster papers presented together with 32 special track papers were carefully reviewed and selected from more than 220 submissions. The papers are organized in topical sections: Part I (LNCS 8033) comprises computational bioimaging; computer graphics; motion, tracking and recognition; segmentation; visualization; 3D mapping, modeling and surface reconstruction; feature extraction, matching and recognition; sparse methods for computer vision, graphics and medical imaging; face processing and recognition. Part II (LNCS 8034) comprises topics such as visualization; visual computing with multimodal data streams; visual computing in digital cultural heritage; intelligent environments: algorithms and applications; applications; virtual reality.

This book comprises select proceedings of the International Conference on Recent Innovations and Developments in Mechanical Engineering (IC-RIDME 2018). The book contains peer reviewed articles covering thematic areas such as fluid mechanics, renewable

energy, materials and manufacturing, thermal engineering, vibration and acoustics, experimental aerodynamics, turbo machinery, and robotics and mechatronics. Algorithms and methodologies of real-time problems are described in this book. The contents of this book will be useful for both academics and industry professionals.

This volume contains the proceedings of MeTrApp 2017, the 4th Conference on Mechanisms, Transmissions and Applications, that was held in Trabzon, Turkey, July 3-5, 2017. The topics treated in this volume are Mechanism Design, Parallel Manipulators, Control Applications, Mechanical Transmissions, Cam Mechanisms, and Dynamics of Machinery. The conference was organised by the IFToMM Technical Committees for “Linkages and Mechanical Controls” and “Gearing and Transmissions” under the patronage of the IFToMM and sponsorship of Karadeniz Technical University, Izmir Institute of Technology and IFToMM Turkey (MAKTED). The aim of the conference was to bring together researchers, scientists, industry experts and students to provide, in a friendly and stimulating environment, the opportunity to exchange know-how and promote collaboration in the field of Mechanism and Machine Science.

Currently, the modelling and control of mechatronic and robotic systems is an open and challenging field of investigation in both industry and academia. The book encompasses the kinematic and dynamic modelling, analysis, design, and control of mechatronic and robotic systems, with the scope of improving their performance, as well as simulating and testing novel devices and control architectures. A broad range of disciplines and topics are included, such as robotic manipulation, mobile systems, cable-driven robots, wearable and rehabilitation devices, variable stiffness safety-oriented mechanisms, optimization of robot performance, and energy-saving systems.

Nowadays robotics is one of the most dynamic fields of scientific researches. The shift of robotics researches from manufacturing to services applications is clear. During the last decades interest in studying climbing and walking robots has been increased. This increasing interest has been in many areas that most important ones of them are: mechanics, electronics, medical engineering, cybernetics, controls, and computers. Today's climbing and walking robots are a combination of manipulative, perceptive, communicative, and cognitive abilities and they are capable of performing many tasks in industrial and non-industrial environments. Surveillance, planetary exploration, emergence rescue operations, reconnaissance, petrochemical applications, construction, entertainment, personal services, intervention in severe environments, transportation, medical and etc are some applications from a very diverse application fields of climbing and walking robots. By great progress in this area of robotics it is anticipated that next generation climbing and walking robots will enhance lives and will change the way the human works, thinks and makes decisions. This book presents the state of the art achievements, recent developments, applications and future challenges of climbing and walking robots. These are presented in 24 chapters by authors throughout the world. The book serves as a reference especially for the researchers who are interested in mobile robots. It also is useful for industrial engineers and graduate students in advanced study.

This volume provides a unique collection of mathematical tools and industrial case studies in digital manufacturing. It addresses various topics, ranging from models of single production technologies, production lines, logistics and workflows to models and optimization strategies for energy consumption in production. The digital factory represents a network of digital models and simulation and 3D visualization methods for the holistic planning, realization, control and ongoing improvement of all factory processes related to a specific product. In the past ten years, all industrialized countries have launched initiatives to realize this vision, sometimes also referred to as Industry 4.0 (in Europe) or Smart Manufacturing (in the United States). Its main goals are • reconfigurable, adaptive and evolving factories capable of small-scale production • high-performance production, combining flexibility, productivity, precision and zero defects • energy and resource efficiency in

manufacturing None of these goals can be achieved without a thorough modeling of all aspects of manufacturing together with a multi-scale simulation and optimization of process chains; in other words, without mathematics. To foster collaboration between mathematics and industry in this area the European Consortium for Mathematics in Industry (ECMI) founded a special interest group on Math for the Digital Factory (M4DiFa). This book compiles a selection of review papers from the M4DiFa kick-off meeting held at the Weierstrass Institute for Applied Analysis and Stochastics in Berlin, Germany, in May 2014. The workshop aimed at bringing together mathematicians working on modeling, simulation and optimization with researchers and practitioners from the manufacturing industry to develop a holistic mathematical view on digital manufacturing. This book is of interest to practitioners from industry who want to learn about important mathematical concepts, as well as to scientists who want to find out about an exciting new area of application that is of vital importance for today's highly industrialized and high-wage countries.

This book addresses optimization in robotics, in terms of both the configuration space and the metal structure of the robot arm itself; and discusses, describes and builds different types of heuristics and algorithms in MATLAB. In addition, the book includes a wealth of examples and exercises. In particular, it enables the reader to write a MATLAB code for all the related problems in robotics. The book also offers detailed descriptions of and builds from scratch several types of optimization algorithms using MATLAB and simplified methods, especially for inverse problems and avoiding singularities. Each chapter features examples and exercises to enhance the reader's comprehension. Accordingly, the book offers the reader a better understanding of robot analysis from an optimization standpoint.

These proceedings collect the latest research results in mechanism and machine science, intended to reinforce and improve the role of mechanical systems in a variety of applications in daily life and industry. Gathering more than 120 academic papers, it addresses topics including: Computational kinematics, Machine elements, Actuators, Gearing and transmissions, Linkages and cams, Mechanism design, Dynamics of machinery, Tribology, Vehicle mechanisms, dynamics and design, Reliability, Experimental methods in mechanisms, Robotics and mechatronics, Biomechanics, Micro/nano mechanisms and machines, Medical/welfare devices, Nature and machines, Design methodology, Reconfigurable mechanisms and reconfigurable manipulators, and Origami mechanisms. This is the fourth installment in the IFToMM Asian conference series on Mechanism and Machine Science (ASIAN MMS 2016). The ASIAN MMS conference initiative was launched to provide a forum mainly for the Asian community working in Mechanism and Machine Science, in order to facilitate collaboration and improve the visibility of activities in the field. The series started in 2010 and the previous ASIAN MMS events were successfully held in Taipei, China (2010), Tokyo, Japan (2012), and Tianjin, China (2014). ASIAN MMS 2016 was held in Guangzhou, China, from 15 to 17 December 2016, and was organized by the South China University under the patronage of the IFToMM and the Chinese Mechanical Engineering Society (CMES). The aim of the Conference was to bring together researchers, industry professionals and students from the broad range of disciplines connected to Mechanism Science in a collegial and stimulating environment. The ASIAN MMS 2016 Conference provided a platform allowing scientists to exchange notes on their scientific achievements and establish new national and international collaborations concerning the mechanism science field and its applications, mainly but not exclusively in Asian contexts.

This book constitutes the full research papers and short monographs developed on the base of the refereed proceedings of the International Conference: Information and Communication Technologies for Research and Industry (ICIT 2020). The book brings accepted research papers which present mathematical modelling, innovative approaches and methods of solving problems in the sphere of control engineering and decision making for the various fields of studies: industry and research, energy efficiency and sustainability, ontology-based data

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simulation, theory and use of digital signal processing, cognitive systems, robotics, cybernetics, automation control theory, image and sound processing, image recognition, technologies, and computer vision. The book contains also several analytical reviews on using smart city technologies in Russia. The central audience of the book are researchers, industrial practitioners and students from the following areas: Adaptive Systems, Human–Robot Interaction, Artificial Intelligence, Smart City and Internet of Things, Information Systems, Mathematical Modelling, and the Information Sciences.

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