A. Related grants

1) EPSRC and Royal Society grants

EPSRC Stiffness-based dynamic modelling & motion control of a multi-fingered hand with passive joints

EPSRC Synthesis of orientation capability of serial robot manipulators using rotability of Grashof type equivalent mechanisms.

EPSRC Manipulation Planning for Handling and Manipulating Complex Cartons

EPSRC A Feasibility Study into Robotic Ironing

EPSRC Investigation and development of a new class of mechanisms: metamorphic mechanisms and reconfigurability

EPSRC Creating Physical Structure from Disarray

Royal Society, Methodology Study of Spatial Compliant Systems Based on Lie Algebra and Screw System Theory and Its Applications

Government KTP
(Knowledge Transfer Partnership) Grant TCS4294: Manufacturing Modelling & production optimisation

Teaching Company Directorate
Programme to develop a computer integrated scheduling and process planning system with subsystems to improve the efficiency and productivity of manufacturing

Government Link Program Grant (CEMLAKR)
Department for Environment, Food and Rural Affairs (DEFRA) award: Automatic Reconfigurable Confectionery Handling and Packaging System (ARCHAPS)

Nuffield Foundation,
Orientation and Dexterity of Robot Manipulators and their kinematics transformation

2) Related European Research Projects

LEAPFROG	Leadership for European Apparel Production From Research along robotic garment manufacturing and handling
DEXDEB	Application of DEXterous hands for DEBoning operation:
V-FEATHER	Innovative Flexible Electric Transport
COSMOS	Cost-driven Adaptive Factory based on Modular Self-Contained Factory Units
TOMSY	Topology-based Motion Synthesis for Dexterous Manipulation
SQUIRREL	Clearing Clutter Bit by Bit

B. PUBLICATIONS

Books

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2. Dai, J.S., 2014, *Screw Algebra and Lie Groups and Lie Algebra*, (in Chinese) Higher Education Press, Beijing, China, ISBN: 9787040318456.
3. Rodriguez Leal, E., and Dai, J.S., 2010, *Evolutionary Design of Parallel Mechanisms: Kinematics of a Family of Parallel Mechanisms with Centralized Motion*, Lambert Academic Publishing, Saarbruecken, Germany, ISBN: 3838378768.

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