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Place~"on Top Of The Weld And Moved Along Its Length, Fig. A-g. B. For Welds Not Ground Smooth The Transducer Is Placed Alongside And Not Quite Parallel To The Weld And Moved Along The Length, Fig. A-10. The Entire Weld And Heat Affected Zone Should Be Scanned. The Weld Should Be Inspected From Both Sides Of One Surface. 3th, 2024

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The Driving Mechanism Of A Five-fingered Robot Hand With Twenty DOF Is Stated In This Paragraph. The Index Finger, Middle Finger, Ring Finger And Little Finger Are Designed With The Identical Driving Mechanism, Which Is Shown In Fig. 2(a). The Placement And Appellation Of Each Joint Correspond To Those Of A Human Finger. With The 4th, 2024

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