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; 1.3.1. Block method ; 1.3.2. General design approach ; 1.3.3. Finite element model
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2.2.1. Overview of state controllability and observability

Sommario/riassunto

The objective of this book is to provide those interested in the field of flexible robotics with an overview of several scientific and technological advances in the practical field of robotic manipulation. The different chapters examine various stages that involve a number of robotic devices, particularly those designed for manipulation tasks characterized by mechanical flexibility. Chapter 1 deals with the general context surrounding the design of functionally integrated microgripping systems. Chapter 2 focuses on the dual notations of modal commandability and observability, which play a sig