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 1.5.1.5. Taking into account the inertia of the actuator's rotor
 1.5.1.6. Taking into consideration the forces and moments exerted by the end-effector on its environment; 1.5.2. Newton-Euler formalism; 1.5.2.1. Newton-Euler equations linear in the inertial parameters; 1.5.2.2. Practical form of Newton-Euler equations; 1.5.3. Determining the base inertial parameters; 1.6. Identification of dynamic parameters; 1.6.1. Introduction; 1.6.2. Identification principle of dynamic parameters; 1.6.2.1. Solving method; 1.6.2.2. Identifiable parameters; 1.6.2.3. Choice of identification trajectories
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 2.2. Machine types

Sommario/riassunto

This book presents the most recent research results on modeling and control of robot manipulators. Chapter 1 gives unified tools to derive direct and inverse geometric, kinematic and dynamic models of serial robots and addresses the issue of identification of the geometric and dynamic parameters of these models. Chapter 2 describes the main features of serial robots, the different architectures and the methods used to obtain direct and inverse geometric, kinematic and dynamic models, paying special attention to singularity analysis. Chapter 3 introduces global