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4.5. Inverse geometric model of general robots; 4.6. Conclusion;
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5.8. Velocity transmission between joint space and task space
5.9. Static
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associated with the task coordinate representation; 5.12. Conclusion;
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6.5. Inverse kinematic model of redundant robots; 6.6. Numerical
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calculation of qp and qc in terms of qa ; 7.10. Number of degrees of
freedom of robots with closed chains
7.11. Classification of singular positions

Sommario/riassunto

Written by two of Europe's leading robotics experts, this book provides
the tools for a unified approach to the modelling of robotic
manipulators, whatever their mechanical structure. No other
publication covers the three fundamental issues of robotics: modelling,
identification and control. It covers the development of various
mathematical models required for the control and simulation of robots.
·World class authority·Unique range of coverage not available in any
other book·Provides a complete course on robotic control at an
undergraduate and graduate level
