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departments, with different emphases ... and control of robot manipulators.

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Abstract. A new
scheme is

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presented for the accurate tracking control of robot manipulators.

Based on the more general suction control methodology, the scheme addresses the following problem: Given the extent of parametric

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uncertainty (such as imprecisions or inertias, geometry, loads) and the frequency range of unmodeled dynamics (such as unmodeled structural modes, neglected time delays), design a

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nonlinear
feedback
controller to
achieve optimal
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In this paper we show that a robot manipulator with 6 degrees of freedom can be separated into two parts: arm with the first

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three joints for major positioning and wrist with the last three joints for major orienting. We propose 5 arms and 2 wrists as basic construction for commercially robot manipulators.

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Computation of the Jacobian for Robot Manipulators

Dynamics is the

analysis of motion caused by forces. In addition to

geometry, we now require parameters like

mass and inertia to calculate the

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accelerations of bodies. Robot manipulators are often composed of several joints. Joints are composed of revolute (rotating) or prismatic (linear) degrees of freedom (DOF).

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...

Abstract A more efficient method for computing the Jacobian matrix for robot manipulators is developed.

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Compared with the existing methods, the number of required numerical operations is greatly reduced, making the proposed technique the fastest or the least expensive one for any

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general N degree
s-of-freedom
manipulator.

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An Efficient
Computational
Method of the
Jacobian for ...
Summary. The
Inverse
Kinematics (IK)
problem of
manipulators can

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be divided into two distinct steps: (1) Problem formulation, where the problem is developed into a form which can then be solved using various methods. (2) Problem solution, where

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the IK problem is actually solved by producing the values of different joint space variables (joint angles, joint velocities or joint accelerations).

Inverse

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Kinematics of
Redundant
Manipulators
Formulated as

...

We have covered several ways to generate motion trajectories for robot manipulators.

Since trajectories are parametric, they

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give us
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analytical
expressions for
position,
velocity, and
acceleration...

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