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parametrize the robot's configuration space. Often the coordinates of choice are the joint variables, and the configuration space can be parametrized either explicitly or implicitly in terms of these joint variables. Also, to grasp and manipulate objects, a robot is typically equipped with an end-effector, e.g., a mechanical hand or gripper.

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Text Saeed B. Niku, Introduction to Robotics - Analysis, Systems, Applications, Prentice Hall 2001  
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References 1.

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5 Isaac Asimov coined and popularized the term robotics through many science-fiction novels and short stories. Asimov was a visionary who envisioned in the 1930s a positronic brain for controlling robots; this pre-dated digital computers by a couple of decades.

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Introduction to Robotics, H. Harry Asada 2 to the base coordinate frame O-xyz, which is an inertial reference frame. The inertial force is then given by  $\mathbf{F}_i = -m_i \ddot{\mathbf{r}}_i$ , where  $m_i$  is the mass of the link and  $\ddot{\mathbf{r}}_i$  is the time derivative of  $\dot{\mathbf{r}}_i$ . Based on D'Alembert's principle, the equation of motion is then obtained by adding the inertial force to

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Chapter 8 Robotic Systems Architectures and Programming Robot software systems tend to be complex. This complexity is due, in large part, to the need to control

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