

advanced robotics redundancy and pdf

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This paper presents the design of an underactuated robotic arm for capturing moving targets with an impact-absorbing capability. The arm consists of three joints (a base joint (BJ), a medial joint (MJ), and a distal joint (DJ)) that are driven by two actuators.

An Underactuated Robotic Arm Based on Differential Gears

A robot is a machine—especially one programmable by a computer—capable of carrying out a complex series of actions automatically. Robots can be guided by an external control device or the control may be embedded within. Robots may be constructed to take on human form but most robots are machines designed to perform a task with no regard to how they look.

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Fig. 1. Increasing system dexterity can be accomplished by adding arm kinematic redundancy or hand complexity Abstract—This paper presents a high-level discussion of dexterity in robotic systems, focusing particularly on

On Dexterity and Dexterous Manipulation

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Stieltjes, Perron, and Markov in analysis of the moment problem, for absolutely continuous measures, constructed the underlying measure as the discontinuity across the cut of a Cauchy representation of an otherwise real-analytic function.

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