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predominantly with
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section devoted to computational considerations. This book evolved from class notes used to teach "Introduction to Robotics" at Stanford University during the autunms of 1983 through 1985. The first and second editions have been used at many institutions from Page 22/35

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kinematics inverse kinematics, and sensors. In course projects, students construct robots which are driven by a microcontroller, with each project reinforcing the basic principles developed in lectures.

to Robotics This course provides a mathematical introduction to the mechanics and control of robots that can be modeled as kinematic chains. Topics covered include the concept of a robot 's configuration space and degrees of freedom, static grasp Page 25/35

analysis, the description of rigid body motions, kinematics of open and closed chains, and the basics of robot control.

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