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The links of a robot mechanism can be arranged in serial fashion, like the familiar open chain arm shown in Figure 1.1(a). Robot mechanisms can also have closed loops, such as the Stewart-Gough platform shown in Figure 1.1(b). In the case of an open chain, all of its joints are actuated, while in the case of mechanisms with closed loops only a subset of its joints may be actuated.

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A Mathematical Introduction to Robotic Manipulation

Errors are described by the variations of a specific set of parameters used to define the mechanism's structure, such as link lengths, joint axes inclination and joint coordinates offsets.

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ulation concerns itself with moving objects (parts, tools, the robot itself) around in space. We need ways to describe these actions in a way that is easily understood and is as intuitive as possible. have adopted the same scale as in The Art of Computer Programming by D. Knuth (Addison-Wesley).

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In this course the kinematics, dynamics analysis and control of robot manipulators is studied in detail. A review of kinematics analysis of serial manipulators, which is detailed in the

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