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Japan. 1981 ANALYSIS AND CONTROL OF ARTICULATED ROBOT ARMS WITH REDUNDANCY  
H. Hanafusa, T. Yoshikawa and Y. Nakamura Automation Research

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Laboratory, Kyoto University,  
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Abstract. Industrial robot applications have seen remarkable growth in numbers and in diversity of uses.

Analysis and Control of Articulated  
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Haruhiko Asada is Ford Professor of Engineering; Director, d'Arbeloff Laboratory for Information Systems and Technology; Head, Control, Instrumentation, and Robotics, at MIT. J.-J. E. Slotine is the author of Robot Analysis and Control, published by Wiley.



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From the control viewpoint, the primary control task formulation of a force controlled robot is identical in redundant and non-redundant case. The difference is in the secondary task formulation. For the force controlled

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redundant robot collision avoidance is of extreme importance, since robot interacts with the environment.

Force Control of Redundant Robots - ScienceDirect

robots actively communicate with each other, sensors, or other computational

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agents using some form of wireless communication. This chapter provides an overview on technical properties of wireless communication, algorithms for networked robot systems, and their modeling and analysis.

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