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5. Let  $B, P_1 = B, P_0 + 5 B V_0 = [9.5 \ 1.00 - 1.50]^T$ . The object's position in  $\{A\}$  is  $T B A P_1 = A B T P_1 = [-4.89 \ 2.11 \ 3.60]$   
6. (2.1)  $R = \text{rot}(\hat{Y}, \varphi) \text{rot}(\hat{Z}, \theta) \begin{bmatrix} c\varphi & 0 & s\varphi \\ 0 & 1 & 0 \\ 0 & 0 & -s\varphi \end{bmatrix} \dots$

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on-line path planning and control of a few industrial robots, and the use of a simulation environment for off-line programming of robots. In courses stressing kinematic issues, we often replace material from Chapter 4 (Robot Dynamics) with selected topics from Chapter 5 (Multifingered Hand Kinematics). We have also covered

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