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This course provides a mathematical
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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 analysis, the description of rigid
body motions, kinematics of open and
closed chains, and the basics of robot
control.

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This course presents an overview of
robotics in practice and research with
topics including vision, motion planning,
mobile mechanisms, 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.
For senior-year or first-year graduate
level robotics courses generally taught
from the mechanical engineering,
electrical engineering, or computer
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