Robots: Erratum

Chapter 3: Differential Kinematics and Statics

- pag. 109: Replace the phrase “According to the coordinate transformation (3.10), one can write” with the phrase “According to the coordinate transformation (3.12), one can write”.
- pag. 139: In the sentence before Eq. (3.86) replace the phrase “(see Problem 3.19)” with the phrase “(see Problem 3.17)”.
- pag. 160: The correct statement of Problem 3.16 is: “Prove (3.85).”.

Chapter 7: Dynamics

- pag. 265: Replace the phrase “which greatly simplifies computation of the second term in (4.34).” with the phrase “which greatly simplifies computation of the second term in (7.30).”.
- pag. 288: The term $\omega_i \times (\bar{I}_i \omega_i)$ is added two times to the right-hand side of (7.113). One occurrence must be dropped.

Chapter 10: Visual Servoing

- pag. 453: The correct value of the initial camera pose is
  \[ \mathbf{x}_c(0) = [1 \ 1 \ 0.5 \ \pi/4]^T. \]
  Moreover, operational space vectors $\mathbf{x}_c(0)$, $\mathbf{x}_{c,o}(0)$, and $\mathbf{x}_{d,o}(0)$ include both position and orientation coordinates. Therefore the dimension “m” (meters) is incorrect and must be dropped.
- pag. 466: The correct statement of Problem 10.7 is: “Show that the matrix $R$ which minimizes (10.57) is the matrix which maximizes the trace of $R^T K$.”
Robotics
Modelling, Planning and Control
Siciliano, B.; Sciavicco, L.; Villani, L.; Oriolo, G.
2009, XXIV, 632 p. 298 illus. With online files/update.,
Hardcover
ISBN: 978-1-84628-641-4