

# Author Index

## A

- Abdel-Malek, K., 76, 79  
Adkins, F.A., 50, 76, 79–81, 83, 96, 98, 100  
Albu-Schäffer, A., 6  
Albus, J., 150, 161  
Allgöwer, E.L., 38, 83  
Altuzarria, O., 51, 108, 113  
Amezua, E., 108  
Angeles, J., 4, 15, 16, 163  
Arakelian, V., 112  
Assima, G.P., 140  
Avilés, R., 108

## B

- Bayo, E., 14, 39  
Benhabib, B., 4  
Berenson, D., 122  
Bhattacharya, S., 112  
Bigras, P., 112, 128, 171, 172  
Blackmore, D., 75  
Bohigas, O., viii, 1, 5, 13, 42, 45, 112, 113, 121, 122, 168, 171  
Bonev, I.A., 4, 6, 20, 50, 53, 57, 60, 65, 76, 94, 98, 100, 112, 127, 129, 139, 150, 154, 163, 171, 172  
Borràs, J., 4  
Bosscher, P., 137  
Bostelman, R.V., 150  
Bourbonnais, F., 112, 128, 171, 172  
Briot, S., 112  
Bruynincx, H., 163  
Burdet, E., 3, 163

## C

- Campos, L., 128, 171  
Canny, J., 17, 22, 24, 112  
Cantó, J., 39  
Cao, Y., 94, 98

- Caro, S., 113  
Castelli, G., 76  
Ceccarelli, M., 76, 150, 152  
Celaya, E., 91  
Chablat, D., 51, 60, 76, 100, 113  
Chen, I., 112, 113  
Chung, W.K., 112  
Cloud, M.J., 89  
Codourey, A., 3, 163  
Corcho, F., 39  
Corke, P., 139  
Coulombe, J., 6, 163, 171  
Cox, D., 38  
Creemers, T., 1, 45, 91

## D

- Dagalakis, N., 150  
Daniel, R.W., 113  
Dasgupta, B., 4, 112, 114  
Dash, A.K., 112, 113  
Dauchez, P., 163  
Davidson, J.K., 42, 139, 162  
De Jalón, J.G., 14  
De Shutter, J., 163  
Donelan, P.S., 5  
Du Plessis, L.J., 171  
Duffy, J., 42, 57, 64, 76

## E

- Ebert-Uphoff, I., 137

## F

- Fang, S., 150, 152  
Fardanesh, B., 75, 76  
Fenton, R.G., 4  
Fournier, A., 163  
Franitz, D., 150, 152

Freudenstein, F., 75

## G

Georg, K., 38, 83

Ghosh, A., 112

Gil, A., 127

Golubitsky, M., 17, 22

Gosselin, C.M., 4, 7, 15, 50, 53, 57, 60, 63, 65, 75, 76, 94, 96, 98, 100, 111, 127, 139, 150, 154, 158, 159

Govaerts, W.J.F., 121

Guillemin, V., 17, 22

Gupta, K.C., 75

## H

Haddadin, S., 5

Hansen, E., 38

Hansen, J.A., 75

Hatwal, H., 112

Haug, E.J., 50, 76, 79, 81, 83, 92, 98, 100, 171

Hay, A.M., 171

Heimann, B., 127

Henderson, M.E., 1, 5, 39, 113, 115, 116, 118, 119, 146, 168

Hernández, A., 108, 113

Hiller, M., 150, 152

Hirzinger, G., 6

Honegger, M., 3, 163

Hu, B., 76

Huang, Z., 94, 98

Hubert, J., 137

Hunt, K.H., 42, 64, 113, 139, 162

Husty, M., 76, 94

Huynh, D.Q., 152

## I

Innocenti, C., 113

## J

Jaillet, L., viii, 1, 5, 112, 121, 122, 171

Ji, W., 94, 98

Jiang, Q., 4, 94, 98, 111

Jo, D.Y., 94

Joy, K., 76

Jui, C., 112

Junkins, J.L., 112

## K

Karmarkar, N.K., 50

Kavraki, L.E., 112

Kazerounian, S.M.K., 75

Kearfott, R.B., 89

Keller, H.B., 116

Khairallah, N., 76

Kim, J.W., 4, 112

Kohli, D., 79

Kotlarski, J., 127

Krantz, S.G., 14, 26, 80, 115, 147

Kuffner, J.J., 122

## L

Lahouar, S., 150, 152

Larachi, F., 140

Latombe, J.-C., 112

LaValle, S.M., 112

Li, H., 4, 63, 65, 150, 158, 159

Li, T.-Y., 38

Little, J., 38

Lu, Y., 76

Luh, C.-M., 50, 76, 80, 81, 83, 92, 96, 98, 100, 171

Lytle, A.M., 161

## M

Ma, O., 4, 16

Macho, E., 51, 108, 113

Mallik, A.K., 4, 112

Manubens, M., viii, 1, 5, 13, 42, 45, 112, 113, 171

Marín, J.M., 127

Marani, G., 112

McAree, P.R., 113

Merlet, J.-P., 4, 53, 57, 61, 75, 94, 98, 150, 158, 164

Mielczarek, S., 150, 152

Molfino, R., 7, 163, 172

Moore, R.E., 89

Morgan, A., 38

Moroz, G., 113

Motamed-Dashliborun, A., 140

Mouly, N., 53, 57, 75, 76

Mruthyunjaya, T.S., 4, 112, 114

Müller, A., 172

## N

Norvig, P., 121

## O

Oblak, D., 79

- Ortmaier, T., 127  
O'Shea, D., 38  
Ott, C., 6  
Ottaviano, E., 76, 150, 152
- P**  
Parenti-Castelli, V., 113  
Park, F.C., 4  
Parks, H.R., 14, 26, 80, 115  
Patrikalakis, N.M., 38  
Payá, L., 127  
Peidró, A., 127  
Pérez, J.J., 39  
Pernkopf, F., 94  
Petuya, V., 113  
Pierrot, F., 163  
Pinto, C., 51, 108, 113  
Pollack, A., 17, 22  
Porta, J.M., viii, 1, 5, 38–40, 45, 50, 55, 89, 91, 112, 113, 121, 122, 169, 171  
Primrose, E.J.F., 75, 113
- Q**  
Qiu, C.C., 94, 171
- R**  
Rajoy, A., 7, 126  
Rastegar, J., 75, 76  
Reinoso, O., 127  
Rheinboldt, W.C., 117  
Richard, M.J., 4, 63, 65, 150, 158–160  
Riechel, A.T., 137  
Rojas, N., 108  
Romdhane, L., 150, 152  
Ros, L., viii, 1, 5, 13, 38–40, 42, 45, 50, 55, 89, 91, 112, 113, 162, 168, 169, 171  
Rosales, C., viii, 1, 5, 112  
Roth, B., 75  
Rouillier, F., 113  
Rull, A., 3  
Russell, S.J., 121  
Ryu, J.-C., 75, 94, 98
- S**  
Sabater, A., 162  
Saidi, K.S., 161  
Schaub, H., 112  
Schulze, B., 169  
Sefrioui, J., 53, 57  
Sen, S., 4, 112
- Servatius, B., 108  
Seward, N., 5  
Shai, O., 108  
Sherbrooke, E.C., 38  
Shi, Y., 76  
Sljoka, A., 108, 169  
Snyman, J.A., 76, 171  
Sommese, A.J., 38, 39  
Soni, A.H., 75  
Srinivasa, S.S., 122  
St-Onge, B.M., 4, 50, 60, 63, 65, 150, 158, 159  
Stemmer, A., 6  
Sturmfels, B., 38  
Sun, Q., 112
- T**  
Thomas, F., 1, 4, 38–40, 44, 50, 55, 89, 91, 108, 162  
Torras, C., 4  
Tsai, L.-W., 64, 65  
Tsai, Y.C., 75
- U**  
Urízar, M., 113
- V**  
Verhoeven, R., 150, 152  
Voglewede, P.A., 137
- W**  
Waldron, K.J., 64, 139  
Walster, G.W., 38  
Wampler, C.W., 38, 39, 91  
Wang, J.-Y., 76, 79–81, 83, 92, 98, 100, 171  
Wenger, P., 51, 60, 76, 100, 113  
Whiteley, W., 108, 169  
Wimbock, T., 6  
Wu, J.K., 171
- X**  
Xu, G., 121
- Y**  
Yang, F.-C., 171  
Yang, G., 112  
Yang, J., 76  
Yeh, H.J., 76, 79  
Yeo, S.H., 112  
Yuh, J., 112

**Z**

Zeghoul, S., 150, 152  
Zein, M., 51, 76, 113  
Zhang, Q., 121  
Zhou, H., 94

Zlatanov, D., 4, 7, 13, 15, 20, 27, 33, 42, 44,  
63, 65, 139, 150, 154, 163, 167, 169,  
171, 172  
Zoppi, M., 7, 163, 172

# Subject Index

## Symbols

- 15-link mechanism, *see* Mechanism, 15-link
- 3-RPR mechanism, *see* Mechanism, 3-RPR
- 3-RRR spherical mechanism, *see* Mechanism, spherical, 3-RRR
- 3-UPS/S spherical mechanism, *see* Mechanism, spherical, 3-UPS/S
- 3-slider mechanism, *see* Mechanism, 3-slider
- 3R arm mechanism, *see* Mechanism, 3R arm
- 4-bar mechanism, *see* Mechanism, 4-bar

## A

- A\* strategy, 120–122, 124, 126, 130, 152, 153, 155, 158, 160
- Accessible output set, 76
- Actuator, 3, 139, 163
  - motion range, 51, 60, 76
  - velocity, *see* Velocity, actuator
- Agile Eye, *see* Mechanism, spherical, Agile Eye
- Aircraft maintenance, 140
- Algebraic variety, 1, 38
- Angles
  - Euler, 65, 99
  - roll-pitch-yaw, 65
  - tilt-and-torsion, 65, 99
- Applications, *see* Mechanism, applications
- Assembly
  - constraint, *see* Constraint, assembly mode, 113
- Assur graph theory, 108
- Atlas, 111, 116–124
  - construction, 117–121
- Avoidance of singularities, *see* Singularity-free, path planning

## B

- Barrier

- analysis, 79–81
- boundary, 51, 79, 84, 89–91
- degenerate, 83, 98–101, 103
- hidden, 83, 92
- interior, 51, 79, 84, 89–91
- singularity, *see* Singularity, barrier
- Bifurcation, 21, 34, 38, 39, 83, 115

## Boundary

- barrier, *see* Barrier, boundary
- identification, 89–91
- value problem, 112
- workspace, *see* Workspace, boundary

## Box

- approximation, 48, 49, 84, 89
- initial bounding, 38, 46, 49, 89
- shrinking, 46–48
- solution, 46–48, 50
- splitting, 46

## Branch-and-prune method, *see* Method, branch-and-prune

## C

- Cable-driven
  - hexapod, *see* Hexapod, cable-driven robot, 138
- Chart, 116–124
  - closed, 119
  - construction, 116–117
  - domain, 116, 119
  - open, 119
- Chmutov surface, 119
- Closed kinematic chain, 4–5, 42, 44, 63, 112
- CNC milling machine, 3, 141
- Codimension of the singularity set, *see* Singularity, set, codimension
- Collision, 5, 76, 122, 156
  - constraint, *see* Constraint, collision reflected in cost function, 122

- Computation of singularities, *see* Singularity, computation
- Configuration feasible, 1, 16, 39, 51, 86, 138  
nonsingular, 15  
shaky, 2, 17  
singular, 15  
tuple, 13  
wrench-feasible, *see* Wrench-feasible, configuration
- Configuration space, 13–14  
dimension of the, 21  
silhouettes of the, 25  
singularity, *see* Singularity, C-space  
singularity-free, *see* Singularity-free, C-space  
tangent space of the, *see* Tangent space, of the C-space  
wrench-feasible, *see* Wrench-feasible, C-space
- Connected component, 1, 39, 52, 76, 83
- Constraint assembly, 14, 39–42  
collision, 5, 169  
joint limit, *see* Joint, limit  
loop closure, 39, 56, 66, 92  
pose, 146, 159
- Contact constraint, 146, 160  
situation, 139, 146, 160, 162  
wrench, 139, 162
- Continuation method, *see* Method, continuation  
for workspace determination, *see* Workspace, determination, continuation method for
- Critical point, 22, 23, 78  
as a silhouette point, 24  
of a projection map, 23–25
- C-space, *see* Configuration space
- CUIK Suite, 52, 91, 124, 150
- Curvature of a manifold, *see* Manifold, curvature
- Cusp, 21
- D**
- Degenerate barrier, *see* Barrier, degenerate
- Degree of freedom, 5, 28, 32, 51, 125, 126, 138
- Dexterity loss, 1, 22, 25, 78, 80, 167
- Diffeomorphism, 116
- Differentiable map, 14, 22, 116, 147
- Differential geometry, 17
- Dimension change, 21, 38, 39, 115  
of the singularity set, *see* Singularity, set, codimension
- Discretisation method, *see* Method, discretisation
- Double-butterfly mechanism, *see* Mechanism, Double-butterfly
- Double-loop mechanism, *see* Mechanism, Double-loop
- Dynamical effects, 172
- E**
- Elimination method, *see* Method, elimination
- Euler angles, *see* Angles, Euler
- Euler-Rodrigues parameters, 65
- Exechon X700, *see* Mechanism, Exechon X700
- F**
- Feasible velocity, *see* Velocity, feasible
- FIKP, *see* Forward, instantanenous kinematic problem
- Forward instantaneous kinematic problem, 4, 15–16, 21, 32, 34, 64  
singularity, *see* Singularity, forward
- G**
- Generalised coordinates, 13
- Graph of charts, 121
- Greedy Best-First strategy, 119, 122, 152, 156, 160
- Grübler-Kutzbach formula, 50
- H**
- HEXA design, 163
- Hexacrane, *see* Mechanism, IRI Hexacrane
- Hexaglide mechanism, *see* Mechanism, Hexaglide
- Hexapod, 137–164  
cable-driven, 137–156  
Gough-Stewart platform, *see* Mechanism, Gough-Stewart platform  
rigid-limbed, 137–149, 159
- Hexapteron, *see* Mechanism, Hexapteron
- Hidden barrier, *see* Barrier, hidden
- Higher-dimensional continuation, *see* Method, continuation, higher-dimensional

- I**
- IICKP, *see* Inverse, instantanenous kinematic problem
  - Implicit function theorem, 26, 27, 78, 80, 115, 147
  - Inertia
    - force, 139, 142, 160
    - link, 127, 137
  - Infinitesimal flexibility, 17
  - Input
    - coordinate, 17
    - singularity, *see* Singularity, input
    - space, 25, 51
    - trajectory, *see* Trajectory, input
    - velocity, *see* Velocity, input
  - INRIA left hand mechanism, *see* Mechanism, INRIA left hand
  - Interior barrier, *see* Barrier, interior
  - Interval analysis, 75
  - Inverse
    - instantaneous kinematic problem, 4, 15–16, 21, 33, 34
    - singularity, *see* Singularity, inverse
  - IRI Hexacrane, *see* Mechanism, IRI Hexacrane
- J**
- Jacobian matrix, 21, 23, 77, 114, 163
  - screw, 139, 146, 147
  - Joint, 39
    - displacement, 39–40, 46, 85
    - limit, 64, 76, 78
      - constraint, 84–86
    - lower-pair, 5, 40
    - prismatic, 40, 42, 84–85
    - revolute, 40, 42, 55, 84
    - spherical, 40, 42
    - universal, 40, 42
    - velocity, 42, 56
- K**
- Karmarkar's bound, 50
  - Kawasaki Delta YF03N mechanism, *see* Mechanism, Kawasaki Delta YF03N
  - Kinematic chain, 15, 163
    - closed, *see* Closed kinematic chain
- L**
- L matrix, 14, 15, 44
    - block partitions of the, 15
    - constructed from twist-loop equations, 42–44
  - in the velocity equation, 14
  - number of columns, 15
  - size of the, 44
  - Leg
    - vertex space, 53
    - working mode, 129
  - Lemniscate curve of Gerono, 49
  - Linear
    - program, 47, 48, 50
    - programming, 50
  - Link, 39
    - ground, 39, 42
    - pose, 39
    - reference frame of a, 39
  - Loop closure equation, *see* Constraint, loop closure
  - Lower-pair joint, *see* Joint, lower-pair
- M**
- Manifold, 14, 22, 114, 117, 119, 137
    - curvature, 117, 119, 121
    - navigation, 145, 147
    - smooth, 111, 115, 116
  - Mechanism
    - 15-link, 107–108
    - 3-RPR, 2, 53
    - 3-RRR, 7, 20, 52–60, 126–134, 170
    - 3-slider, 28, 29, 33–35
    - 3R arm, 79
    - 4-bar, 28, 29
    - applications
      - aircraft building, 141
      - beam mounting, 161
      - camera orientation, 7, 102
      - cargo retrieval, 161
      - CNC machining, 3, 7, 141
      - drilling, 1, 140
      - driving simulation, 62
      - force feedback, 6
      - heavy-object handling, 1
      - inspection, 141
      - micropositioning, 6
      - pick-and-place, 54, 112
      - pipe assembling, 141
      - rapid prototyping, 6
      - swell simulation, 141
    - cable-driven, 6, 137–157
    - closed-chain, 14, 113
    - configuration, 13
    - DextAR, 112
    - DLR Light Weight Robot, 6
    - Double-butterfly, 91–92

- Double-loop, 66–70  
 Exechon X700, 7  
 Gough-Stewart platform, 6, 61–65, 75, 92–99, 138, 158, 163  
 Hexaglide, 3, 163  
 Hexapteron, 6  
 inertia, 112  
 INRIA Left Hand, 158  
 IRI Hexacrane, 7, 150, 155–157  
 Kawasaki Delta YF03N, 7  
 MicARH rotary hexapod, 6, 163  
 NIST RoboCrane, 140, 150  
 nonredundant, 5, 8, 15, 44, 75, 111, 113, 167–168  
 Omega.7 haptic device, 6  
 parallel, 2–5, 20, 44, 52–65, 92–104, 126–134, 137–164  
 planar, 2, 5, 18, 28–35, 52–60, 66–70, 91–92, 107–108, 126–134  
 redundant, 5, 75, 169  
 serial, 3  
 shaky, 17  
 spatial, 3, 5, 61–65, 92–98, 137–164  
 spherical, 5, 98–104  
     3-RRR, 98–101  
     3-UPS/S, 98–101  
     Agile Eye, 7, 101, 103  
     parallel, 98  
     symmetries, 169  
 trajectory, *see* Trajectory, mechanism with all singularities, 33–35
- Method  
     branch-and-prune, 1, 37–39, 46–50  
     continuation, 3, 37–39, 81–84  
         higher-dimensional, 1, 39, 111, 116–121  
     discretisation, 75  
     elimination, 37–39  
     Newton-Raphson, 83, 89, 117  
 MicARH rotary hexapod, *see* Mechanism, MicARH rotary hexapod
- Mobility  
     global, 15  
     instantaneous, 21, 22, 32  
     loss, 8, 78, 80
- Motion impediment, 75, 77, 79, 100, 167  
 Motion planning, 112  
 Multibody dynamics, 39
- N**  
 NIST RoboCrane, *see* Mechanism, NIST RoboCrane  
 Nonsingular
- configuration, *see* Configuration, nonsingular  
 transitions between assembly modes, 113
- O**  
 Okuma PM-600 machine, 140  
 Output  
     coordinate, 17  
     singularity, *see* Singularity, output  
     space, 25, 51  
     trajectory, *see* Trajectory, output  
     velocity, *see* Velocity, output
- P**  
 Parallel mechanism or robot, *see* Mechanism, parallel  
 Parallelization, 50  
 Passive velocity, *see* Velocity, passive  
 Path  
     clearance, 115, 137, 171  
     planning  
         singularity-free, *see* Singularity-free, path planning  
         wrench-feasible, *see* Wrench-feasible, path planning  
         singularity-free, *see* Singularity-free, path smoothing, 122, 152  
 Performance data, 71, 93, 160  
 Planar mechanism, *see* Mechanism, planar  
 Polynomial, 37, 39, 60, 108  
     equation, 3, 37, 45  
     system solving, 3, 37
- Polytope  
     approximation, 112  
     bound, 47  
     chart, *see* Chart, domain
- Portrait, *see* Singularity, portrait  
 Prismatic joint, *see* Joint, prismatic  
 Projection map, 24, 25, 77  
 Pseudocode  
     of the branch-and-prune solver, 48  
     of the continuation-based planner, 123
- R**  
 Reference point coordinates, 39  
 Regular point, 23  
 Resultant polynomial, 37  
 Revolute joint, *see* Joint, revolute  
 Rigidity loss, 1, 2, 112, 167  
 Robot  
     kinematics, 1

- position accuracy, 112, 137
  - Roll-pitch-yaw angles, *see* Angles, roll-pitch-yaw
  - Rotation matrix, 39, 40, 65, 86, 87, 91, 94, 138, 162
- S**
- Screw, 42, 63
    - in axis coordinates, xvi
    - in ray coordinates, 64
    - Jacobian matrix, *see* Jacobian matrix, screw reciprocal, 63, 64, 172
    - twist, *see* Twist
    - wrench, *see* Wrench
  - Screw Theory, 16, 42
  - Shaky configuration, *see* Configuration, shaky
  - Silhouette analysis, 17
  - Singular configuration, *see* Configuration, singular
  - Singularities
    - formulation, 16
    - geometric interpretation of, 17–27
      - as shaky configurations, 17–20
      - as silhouette points, 22–25
      - as sources of trajectory indeterminacy, 26–27
    - inclusion relationships of, 22
  - Singularity
    - analysis, 1–5, 13, 169
    - avoidance, *see* Singularity-free, path planning
    - barrier, 75, 78–81
    - C-space, 20–22
    - forward, 13–17, 22, 51
    - impossible input, 27–28, 31–35
    - impossible output, 27–31, 33–35
    - in-workspace, detection, 4
    - increased instantaneous mobility, 27–28, 32–35
    - input, 20–22, 24–25
    - inverse, 13–17, 22, 51
    - lower-level, types, 27–33
    - output, 20–22, 24–25
    - portrait, 51, 52, 57–60, 113
    - redundant input, 27–29, 33–35
    - redundant output, 27–29, 33–35
    - redundant passive motion, 27–28, 32–35
    - set, 1, 3, 4, 15–16, 37–38, 50
      - codimension, 38, 50
      - computation, 1, 3, 4, 37, 45–50, 167
      - equations of the, 16, 39–44, 86
      - isolation of the, 45
  - stratification of the, 171
  - visualisation of the, 50–52
- set  $\mathcal{W}$ , 78
  - traversable, 75, 78–81, 84, 89–91
  - type I, 4
  - type II, 4
- Singularity-free**
- C-space, 111, 113–124
  - path, 52, 111, 113
  - path planning, 1, 3, 4, 111–134, 163, 167, 168, 171
  - region, 52, 111
  - workspace, 111
- Smooth**
- function, *see* Differentiable map
  - manifold, *see* Manifold, smooth
  - trajectory, *see* Trajectory, smooth
- Spatial mechanism**, *see* Mechanism, spatial
- Spherical**
- joint, *see* Joint, spherical
  - parallel mechanism, *see* Mechanism, spherical parallel
- Swell simulator**, 140
- T**
- Tangent space, 20–22
    - of  $\mathcal{M}$ , 116, 117, 119, 146
    - of  $\pi_{\mathbf{u}}(\mathcal{W})$ , 80
    - of the C-space, 20–22, 25, 78
    - of the space  $\mathcal{U}$ , 78
  - Zariski, 21
- Tilt-and-torsion angles**, *see* Angles, tilt-and-torsion
- Trajectory**, 17, 26, 79, 80
  - C-space, 17, 26, 79, 80
  - input, 26–27
  - mechanism, 26
  - minimal-time, 112, 172
  - output, 26–27
  - smooth, 26, 27
- Traversable singularity**, *see* Singularity, traversable
- Twist**, 14, 42–44, 53, 63, 164
  - in axis coordinates, xvi, 42
  - loop equation, 15, 42, 56, 66
- U**
- Uncertainty ellipsoid, 137, 139, 141, 143, 150, 160–162, 164
  - Uncontrollable motions, 3, 25
  - Universal joint, *see* Joint, universal

**V**

Variety, *see* Algebraic variety

**Velocity**

- actuator, 2, 16, 51
- equation, 15, 28, 29, 31, 32, 39, 42–44, 63
  - equations forming the, 44
  - input/output, 4, 35
- feasible, 13, 17, 21, 25
- input, 14, 28, 31, 33
- output, 14, 29, 33
- passive, 14, 32
  - elimination of, 63
- vector, 14, 17, 21

Vertex space, *see* Leg, vertex space of a

**W**

- Working mode, 70, 127–130
- Workspace, 76
  - barrier, 78–81
  - boundary, 25, 51, 76–79
  - constant orientation, 94
  - constant position, 94
  - constant torsion, 100
  - definition of, 77

**determination**, 25, 75–108, 167

continuation method for, 76, 81–84

**dexterous**, 171

- input, 25
- multicomponent, 83, 91
- orientation, 98–100
- output, 25
- position, 107
- reachable, 91–92, 94
- singularity-free, *see* Singularity-free, workspace

**Wrench**, 139

- in ray coordinates, xvi
- uncertainty, *see* Uncertainty ellipsoid

**Wrench-feasible**

- C-space, 137, 142–144, 150, 156, 159
- configuration, 137, 139
- path, 142, 158
- path planning, 137–164, 171

**Z**

- Zariski tangent space, *see* Tangent space, Zariski