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RareBooksClub. Paperback. Book Condition: New. This item is printed on demand. Paperback. 36 pages. Original publisher: Troy, N. Y. : Center for Intelligent Robotic Systems for Space Exploration, Rensselaer Polytechnic Institute, 1991 OCLC Number: (OCoLC)234904272 Subject: Robots -- Control systems. Excerpt: . . . 15 used with full dynamics control algorithms. The resulting system, w named CTOS, was developed as a multiple-processor, VME-bus based, real time robot control system for the CIRSSE 18-degree-of-freedom transporter. It hierarchically integrates the execution algorithms in planning, interaction, and servo control. It works together with the VXWORKS software and provides most of the transformations, and other kinematics and dynamics tools needed for servoing and manipulation. In earlier work it was shown that the control activities can be measured by entropy (Saridis 1985b). Therefore the measure of performance of the Motion Control System is consistent with the rest of the architecture of the Intelligent Machine. m L The Graspinq System. This system is planned to be separate from the Motion Control System. It would involve the grasping operations, the information gathering from various proximity sensors, and integration of these activities with the gripper motion control. It i will be driven by a special coordinator, and provide information back of proper grasping for job control purposes. However at the present time it is only a subsystem of the Motion Control System and isfollows commands issued by the its Coordinator, for purposes of expediency. 4, , 2 Entropy Formulation of Motion Control. The cost of control at the hardware level can be expressed as an entropy which measures the uncertainty of selecting an appropriate control to execute a task. By selecting an optimal control, one minimizes the entropy, e. g. , the uncertainty of execution. The entropy may be viewed in the respect as an energy...

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