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This chapter is devoted to presenting a reference model for the functional architecture of an industrial robot's control system. The hierarchical structure and its articulation into functional ...

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the course with some discussion of technological and planning issues, as well as a laboratory. The laboratory consists of experiments involving on-line path planning and control of a few industrial robots, and the use of a simulation environment for on-line programming of robots. In

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In the case of an open chain robot such as the industrial manipulator of Figure 1.1(a), all of its joints are independently actuated. This is the essential idea behind the degrees of freedom of a robot: it is the sum of all the independently actuated degrees of freedom of the joints. For open chains the

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